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Chapter 1

Introduction

The Zephyr OS is based on a small-footprint kernel designed for use on resource-constrained and embedded systems: from simple embedded environmental sensors and LED wearables to sophisticated embedded controllers, smart watches, and IoT wireless applications.

The Zephyr kernel supports multiple architectures, including:

• ARCv2 (EM and HS) and ARCv3 (HS6X)
• ARMv6-M, ARMv7-M, and ARMv8-M (Cortex-M)
• ARMv7-A and ARMv8-A (Cortex-A, 32- and 64-bit)
• ARMv7-R, ARMv8-R (Cortex-R, 32- and 64-bit)
• Intel x86 (32- and 64-bit)
• MIPS (MIPS32 Release 1 specification)
• NIOS II Gen 2
• RISC-V (32- and 64-bit)
• SPARC V8
• Tensilica Xtensa

The full list of supported boards based on these architectures can be found here.

1.1 Licensing

Zephyr is permissively licensed using the Apache 2.0 license (as found in the LICENSE file in the project’s GitHub repo). There are some imported or reused components of the Zephyr project that use other licensing, as described in Licensing of Zephyr Project components.

1.2 Distinguishing Features

Zephyr offers a large and ever growing number of features including:

Extensive suite of Kernel services

Zephyr offers a number of familiar services for development:

• Multi-threading Services for cooperative, priority-based, non-preemptive, and preemptive threads with optional round robin time-slicing. Includes POSIX pthreads compatible API support.
• **Interrupt Services** for compile-time registration of interrupt handlers.

• **Memory Allocation Services** for dynamic allocation and freeing of fixed-size or variable-size memory blocks.

• **Inter-thread Synchronization Services** for binary semaphores, counting semaphores, and mutex semaphores.

• **Inter-thread Data Passing Services** for basic message queues, enhanced message queues, and byte streams.

• **Power Management Services** such as overarching, application or policy-defined, System Power Management and fine-grained, driver-defined, Device Power Management.

**Multiple Scheduling Algorithms**
Zephyr provides a comprehensive set of thread scheduling choices:

• Cooperative and Preemptive Scheduling

• Earliest Deadline First (EDF)

• Meta IRQ scheduling implementing “interrupt bottom half” or “tasklet” behavior

• Timeslicing: Enables time slicing between preemptible threads of equal priority

• Multiple queuing strategies:
  – Simple linked-list ready queue
  – Red/black tree ready queue
  – Traditional multi-queue ready queue

**Highly configurable / Modular for flexibility**
Allows an application to incorporate only the capabilities it needs as it needs them, and to specify their quantity and size.

**Cross Architecture**
Supports a wide variety of supported boards with different CPU architectures and developer tools. Contributions have added support for an increasing number of SoCs, platforms, and drivers.

**Memory Protection**
Implements configurable architecture-specific stack-overflow protection, kernel object and device driver permission tracking, and thread isolation with thread-level memory protection on x86, ARC, and ARM architectures, userspace, and memory domains.

For platforms without MMU/MPU and memory constrained devices, supports combining application-specific code with a custom kernel to create a monolithic image that gets loaded and executed on a system’s hardware. Both the application code and kernel code execute in a single shared address space.

**Compile-time resource definition**
Allows system resources to be defined at compile-time, which reduces code size and increases performance for resource-limited systems.

**Optimized Device Driver Model**
Provides a consistent device model for configuring the drivers that are part of the platform/system and a consistent model for initializing all the drivers configured into the system and allows the reuse of drivers across platforms that have common devices/IP blocks.

**Devicetree Support**
Use of devicetree to describe hardware. Information from devicetree is used to create the application image.

**Native Networking Stack supporting multiple protocols**
Networking support is fully featured and optimized, including LwM2M and BSD sockets compatible support. OpenThread support (on Nordic chipsets) is also provided - a mesh network designed to securely and reliably connect hundreds of products around the home.
Bluetooth Low Energy 5.0 support

Bluetooth 5.0 compliant (ESR10) and Bluetooth Low Energy Controller support (LE Link Layer). Includes Bluetooth Mesh and a Bluetooth qualification-ready Bluetooth controller.

- Generic Access Profile (GAP) with all possible LE roles
- Generic Attribute Profile (GATT)
- Pairing support, including the Secure Connections feature from Bluetooth 4.2
- Clean HCI driver abstraction
- Raw HCI interface to run Zephyr as a Controller instead of a full Host stack
- Verified with multiple popular controllers
- Highly configurable

Mesh Support:

- Relay, Friend Node, Low-Power Node (LPN) and GATT Proxy features
- Both Provisioning bearers supported (PB-ADV & PB-GATT)
- Highly configurable, fitting in devices with at least 16k RAM

Native Linux, macOS, and Windows Development

A command-line CMake build environment runs on popular developer OS systems. A native port (native_sim) lets you build and run Zephyr as a native application on Linux, aiding development and testing.

Virtual File System Interface with ext2, FatFs, and LittleFS Support

ext2, LittleFS and FatFS support; FCB (Flash Circular Buffer) for memory constrained applications.

Powerful multi-backend logging Framework

Support for log filtering, object dumping, panic mode, multiple backends (memory, networking, filesystem, console, ...) and integration with the shell subsystem.

User friendly and full-featured Shell interface

A multi-instance shell subsystem with user-friendly features such as autocompletion, wildcards, coloring, metakeys (arrows, backspace, ctrl+u, etc.) and history. Support for static commands and dynamic sub-commands.

Settings on non-volatile storage

The settings subsystem gives modules a way to store persistent per-device configuration and runtime state. Settings items are stored as key-value pair strings.

Non-volatile storage (NVS)

NVS allows storage of binary blobs, strings, integers, longs, and any combination of these.

Native port

Native sim allows running Zephyr as a Linux application with support for various subsystems and networking.

## 1.3 Community Support

Community support is provided via mailing lists and Discord; see the Resources below for details.

## 1.4 Resources

Here’s a quick summary of resources to help you find your way around:
1.4.1 Getting Started

- Zephyr Documentation
- Getting Started Guide
- Tips when asking for help
- Code samples

1.4.2 Code and Development

- Source Code Repository
- Releases
- Contribution Guide

1.4.3 Community and Support

- Discord Server for real-time community discussions
- User mailing list (users@lists.zephyrproject.org)
- Developer mailing list (devel@lists.zephyrproject.org)
- Other project mailing lists
- Project Wiki

1.4.4 Issue Tracking and Security

- GitHub Issues
- Security documentation
- Security Advisories Repository
- Report security vulnerabilities at vulnerabilities@zephyrproject.org

1.4.5 Additional Resources

- Zephyr Project Website
- Zephyr Tech Talks

1.5 Fundamental Terms and Concepts

See Glossary of Terms
Chapter 2

Developing with Zephyr

2.1 Getting Started Guide

Follow this guide to:

- Set up a command-line Zephyr development environment on Ubuntu, macOS, or Windows (instructions for other Linux distributions are discussed in Install Linux Host Dependencies)
- Get the source code
- Build, flash, and run a sample application

2.1.1 Select and Update OS

Click the operating system you are using.

Ubuntu
This guide covers Ubuntu version 20.04 LTS and later.

```
sudo apt update
sudo apt upgrade
```

macOS
On macOS Mojave or later, select System Preferences > Software Update. Click Update Now if necessary.
On other versions, see this Apple support topic.

Windows
Select Start > Settings > Update & Security > Windows Update. Click Check for updates and install any that are available.

2.1.2 Install dependencies

Next, you'll install some host dependencies using your package manager.
The current minimum required version for the main dependencies are:
<table>
<thead>
<tr>
<th>Tool</th>
<th>Min. Version</th>
</tr>
</thead>
<tbody>
<tr>
<td>CMake</td>
<td>3.20.5</td>
</tr>
<tr>
<td>Python</td>
<td>3.8</td>
</tr>
<tr>
<td>Devicetree compiler</td>
<td>1.4.6</td>
</tr>
</tbody>
</table>

**Ubuntu**

1. If using an Ubuntu version older than 22.04, it is necessary to add extra repositories to meet the minimum required versions for the main dependencies listed above. In that case, download, inspect and execute the Kitware archive script to add the Kitware APT repository to your sources list. A detailed explanation of `kitware-archive.sh` can be found here:

   ```bash
   wget https://apt.kitware.com/kitware-archive.sh
   sudo bash kitware-archive.sh
   ```

2. Use `apt` to install the required dependencies:

   ```bash
   sudo apt install --no-install-recommends git cmake ninja-build gperf 
   ccache dfu-util device-tree-compiler wget 
   python3-dev python3-pip python3-setuptools python3-tk python3-wheel xz-utils file 
   make gcc gcc-multilib g++-multilib libSDL2-dev libmagic1
   ```

3. Verify the versions of the main dependencies installed on your system by entering:

   ```bash
   cmake --version
   python3 --version
   dtc --version
   ```

   Check those against the versions in the table in the beginning of this section. Refer to the `Install Linux Host Dependencies` page for additional information on updating the dependencies manually.

**macOS**

1. Install Homebrew:

   ```bash
   /bin/bash -c "$(curl -fsSL https://raw.githubusercontent.com/Homebrew/install/HEAD/install.sh)"
   ```

2. After the Homebrew installation script completes, follow the on-screen instructions to add the Homebrew installation to the path.

   - On macOS running on Apple Silicon, this is achieved with:

     ```bash
     (echo; echo 'eval "$(/opt/homebrew/bin/brew shellenv)"');) >> ~/.zprofile
     source ~/.zprofile
     ```

   - On macOS running on Intel, use the command for Apple Silicon, but replace `/opt/homebrew/` with `/usr/local/`.

3. Use `brew` to install the required dependencies:

   ```bash
   brew install cmake ninja gperf python3 ccache qemu dtc libmagic
   ```

4. Add the Homebrew Python folder to the path, in order to be able to execute `python` and `pip` as well `python3` and `pip3`.

   ```bash
   (echo; echo 'export PATH="$(brew --prefix)'/opt/python/libexec/bin:$PATH"');) >> ~/.zprofile
   source ~/.zprofile
Windows

**Note:** Due to issues finding executables, the Zephyr Project doesn't currently support application flashing using the Windows Subsystem for Linux (WSL) (WSL). Therefore, we don't recommend using WSL when getting started.

These instructions must be run in a `cmd.exe` command prompt terminal window. In modern versions of Windows (10 and later) it is recommended to install the Windows Terminal application from the Microsoft Store. The required commands differ on PowerShell.

These instructions rely on Chocolatey. If Chocolatey isn't an option, you can install dependencies from their respective websites and ensure the command line tools are on your `PATH` environment variable.

1. Install chocolatey.

2. Open a `cmd.exe` terminal window as **Administrator**. To do so, press the Windows key, type `cmd.exe`, right-click the `Command Prompt` search result, and choose **Run as Administrator**.

3. Disable global confirmation to avoid having to confirm the installation of individual programs:

   ```
   choco feature enable -n allowGlobalConfirmation
   ```

4. Use choco to install the required dependencies:

   ```
   choco install cmake --installargs 'ADD_CMAKE_TO_PATH=System'
   choco install ninja gperf python311 git dtc-msys2 wget 7zip
   ```

   **Warning:** As of November 2023, Python 3.12 is not recommended for Zephyr development on Windows, as some required Python dependencies may be difficult to install.

5. Close the terminal window.

### 2.1.3 Get Zephyr and install Python dependencies

Next, clone Zephyr and its **modules** into a new **west** workspace named `zephyrproject`. You'll also install Zephyr's additional Python dependencies.

**Note:** It is easy to run into Python package incompatibilities when installing dependencies at a system or user level. This situation can happen, for example, if working on multiple Zephyr versions or other projects using Python on the same machine.

For this reason it is suggested to use **Python virtual environments**.

#### Ubuntu

Install within virtual environment

1. Use `apt` to install Python `venv` package:

   ```
   sudo apt install python3-venv
   ```

2. Create a new virtual environment:
3. Activate the virtual environment:

```
source ~/zephyrproject/.venv/bin/activate
```

Once activated your shell will be prefixed with (.venv). The virtual environment can be deactivated at any time by running deactivate.

**Note:** Remember to activate the virtual environment every time you start working.

4. Install west:

```
pip install west
```

5. Get the Zephyr source code:

```
west init ~/zephyrproject
cd ~/zephyrproject
west update
```

6. Export a Zephyr CMake package. This allows CMake to automatically load boilerplate code required for building Zephyr applications.

```
w west zephyr-export
```

7. Zephyr's `scripts/requirements.txt` file declares additional Python dependencies. Install them with `pip`.

```
pip install -r ~/zephyrproject/zephyr/scripts/requirements.txt
```

Install globally

1. Install west, and make sure `~/.local/bin` is on your `PATH environment variable`:

```
pip3 install --user --user west
echo 'export PATH=~/.local/bin:$PATH' >> ~/.bashrc
source ~/.bashrc
```

2. Get the Zephyr source code:

```
w west init ~/zephyrproject
cd ~/zephyrproject
west update
```

3. Export a Zephyr CMake package. This allows CMake to automatically load boilerplate code required for building Zephyr applications.

```
w west zephyr-export
```

4. Zephyr's `scripts/requirements.txt` file declares additional Python dependencies. Install them with `pip3`.

```
pip3 install --user --user ~/zephyrproject/zephyr/scripts/requirements.txt
```

macOS

Install within virtual environment

1. Create a new virtual environment:
2. Activate the virtual environment:

```bash
source ~/zephyrproject/.venv/bin/activate
```

Once activated your shell will be prefixed with (.venv). The virtual environment can be deactivated at any time by running deactivate.

**Note:** Remember to activate the virtual environment every time you start working.

3. Install west:

```bash
pip install west
```

4. Get the Zephyr source code:

```bash
west init ~/zephyrproject
cd ~/zephyrproject
west update
```

5. Export a Zephyr CMake package. This allows CMake to automatically load boilerplate code required for building Zephyr applications.

```bash
west zephyr-export
```

6. Zephyr's `scripts/requirements.txt` file declares additional Python dependencies. Install them with pip.

```bash
pip install -r ~/zephyrproject/zephyr/scripts/requirements.txt
```

Install globally

1. Install west:

```bash
pip3 install -U west
```

2. Get the Zephyr source code:

```bash
west init ~/zephyrproject
cd ~/zephyrproject
west update
```

3. Export a Zephyr CMake package. This allows CMake to automatically load boilerplate code required for building Zephyr applications.

```bash
west zephyr-export
```

4. Zephyr's `scripts/requirements.txt` file declares additional Python dependencies. Install them with pip3.

```bash
pip3 install -r ~/zephyrproject/zephyr/scripts/requirements.txt
```

Windows

Install within virtual environment

1. Open a `cmd.exe` terminal window **as a regular user**

2. Create a new virtual environment:
3. Activate the virtual environment:

```
%HOMEPATH%
python -m venv zephyrproject\.venv
```

Once activated your shell will be prefixed with (.venv). The virtual environment can be deactivated at any time by running `deactivate`.

**Note:** Remember to activate the virtual environment every time you start working.

4. Install west:

```
pip install west
```

5. Get the Zephyr source code:

```
west init zephyrproject
cd zephyrproject
west update
```

6. Export a Zephyr CMake package. This allows CMake to automatically load boilerplate code required for building Zephyr applications.

```
w west zephyr-export
```

7. Zephyr's `scripts\requirements.txt` file declares additional Python dependencies. Install them with pip.

```
pip install -r %HOMEPATH%\zephyrproject\zephyr\scripts\requirements.txt
```

Install globally

1. Open a cmd.exe terminal window as a regular user
2. Install west:

```
pip3 install -U west
```

3. Get the Zephyr source code:

```
cd %HOMEPATH%
w west init zephyrproject
cd zephyrproject
west update
```

4. Export a Zephyr CMake package. This allows CMake to automatically load boilerplate code required for building Zephyr applications.

```
w west zephyr-export
```

5. Zephyr's `scripts\requirements.txt` file declares additional Python dependencies. Install them with pip3.

```
pip3 install -r %HOMEPATH%\zephyrproject\zephyr\scripts\requirements.txt
```
2.1.4 Install the Zephyr SDK

The Zephyr Software Development Kit (SDK) contains toolchains for each of Zephyr's supported architectures, which include a compiler, assembler, linker and other programs required to build Zephyr applications.

It also contains additional host tools, such as custom QEMU and OpenOCD builds that are used to emulate, flash and debug Zephyr applications.

Note: You can change 0.16.5 to another version in the instructions below if needed; the Zephyr SDK Releases page contains all available SDK releases.

Note: If you want to uninstall the SDK, you may simply remove the directory where you installed it.

Ubuntu

1. Download and verify the Zephyr SDK bundle:

```bash
cd ~
wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/zephyr-sdk-0.16.5_linux-x86_64.tar.xz
wget -O - https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/sha256.sum | shasum --check --ignore-missing
```

If your host architecture is 64-bit ARM (for example, Raspberry Pi), replace x86_64 with aarch64 in order to download the 64-bit ARM Linux SDK.

2. Extract the Zephyr SDK bundle archive:

```bash
tar xvf zephyr-sdk-0.16.5_linux-x86_64.tar.xz
```

Note: It is recommended to extract the Zephyr SDK bundle at one of the following locations:

- $HOME
- $HOME/.local
- $HOME/.local/opt
- $HOME/bin
- /opt
- /usr/local

The Zephyr SDK bundle archive contains the zephyr-sdk-<version> directory and, when extracted under $HOME, the resulting installation path will be $HOME/zephyr-sdk-<version>.

3. Run the Zephyr SDK bundle setup script:

```bash
cd zephyr-sdk-0.16.5
./setup.sh
```

Note: You only need to run the setup script once after extracting the Zephyr SDK bundle.

You must rerun the setup script if you relocate the Zephyr SDK bundle directory after the initial setup.

4. Install udev rules, which allow you to flash most Zephyr boards as a regular user:
macOS

1. Download and verify the Zephyr SDK bundle:
   ```bash
cd ~
curl -L -O https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/zephyr-sdk-0.16.5_macos-x86_64.tar.xz
   curl -L https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/sha256.sum | shasum --check --ignore-missing
   ```
   If your host architecture is 64-bit ARM (Apple Silicon, also known as M1), replace x86_64 with aarch64 in order to download the 64-bit ARM macOS SDK.

2. Extract the Zephyr SDK bundle archive:
   ```bash
tar xvf zephyr-sdk-0.16.5_macos-x86_64.tar.xz
   ```

   **Note:** It is recommended to extract the Zephyr SDK bundle at one of the following locations:
   - $HOME
   - $HOME/.local
   - $HOME/.local/opt
   - $HOME/bin
   - /opt
   - /usr/local

   The Zephyr SDK bundle archive contains the zephyr-sdk-<version> directory and, when extracted under $HOME, the resulting installation path will be $HOME/zephyr-sdk-<version>.

3. Run the Zephyr SDK bundle setup script:
   ```bash
cd zephyr-sdk-0.16.5
./setup.sh
   ```

   **Note:** You only need to run the setup script once after extracting the Zephyr SDK bundle.

   You must rerun the setup script if you relocate the Zephyr SDK bundle directory after the initial setup.

Windows

1. Open a cmd.exe terminal window as a regular user

2. Download the Zephyr SDK bundle:
   ```bash
cd %HOMEPATH%
wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/zephyr-sdk-0.16.5_windows-x86_64.7z
   ```

3. Extract the Zephyr SDK bundle archive:
   ```bash
7z x zephyr-sdk-0.16.5_windows-x86_64.7z
   ```

   **Note:** It is recommended to extract the Zephyr SDK bundle at one of the following locations:
The Zephyr SDK bundle archive contains the zephyr-sdk-<version> directory and, when extracted under %HOMEPATH%, the resulting installation path will be %HOMEPATH%\zephyr-sdk-<version>.

4. Run the Zephyr SDK bundle setup script:
   
   cd zephyr-sdk-0.16.5
   setup.cmd

   **Note:** You only need to run the setup script once after extracting the Zephyr SDK bundle. You must rerun the setup script if you relocate the Zephyr SDK bundle directory after the initial setup.

### 2.1.5 Build the Blinky Sample

**Note:** blinky is compatible with most, but not all, boards. If your board does not meet Blinky's blinky-sample-requirements, then hello_world is a good alternative.

If you are unsure what name west uses for your board, west boards can be used to obtain a list of all boards Zephyr supports.

Build the blinky with `west build`, changing `<your-board-name>` appropriately for your board:

**Ubuntu**

```
   cd ~/zephyrproject/zephyr
   west build -p always -b <your-board-name> samples/basic/blinky
```

**macOS**

```
   cd ~/zephyrproject/zephyr
   west build -p always -b <your-board-name> samples/basic/blinky
```

**Windows**

```
   cd %HOMEPATH%\zephyrproject\zephyr
   west build -p always -b <your-board-name> samples\basic\blinky
```

The `-p always` option forces a pristine build, and is recommended for new users. Users may also use the `-p auto` option, which will use heuristics to determine if a pristine build is required, such as when building another sample.

### 2.1.6 Flash the Sample

Connect your board, usually via USB, and turn it on if there's a power switch. If in doubt about what to do, check your board's page in boards.

Then flash the sample using `west flash`:

```
   west flash
```
You may need to install additional host tools required by your board. The west flash command will print an error if any required dependencies are missing.

If you're using blinky, the LED will start to blink as shown in this figure:

Fig. 1: Phytec reel_board running blinky

### 2.1.7 Next Steps

Here are some next steps for exploring Zephyr:

- Try other samples-and-demos
- Learn about Application Development and the west tool
- Find out about west's flashing and debugging features, or more about Flashing and Hardware Debugging in general
- Check out Beyond the Getting Started Guide for additional setup alternatives and ideas
- Discover Resources for getting help from the Zephyr community

### 2.1.8 Troubleshooting Installation

Here are some tips for fixing some issues related to the installation process.

**Double Check the Zephyr SDK Variables When Updating**

When updating Zephyr SDK, check whether the ZEPHYR_TOOLCHAIN_VARIANT or ZEPHYR_SDK_INSTALL_DIR environment variables are already set. See Updating the Zephyr SDK toolchain for more information.

For more information about these environment variables in Zephyr, see Important Environment Variables.
2.1.9 Asking for Help

You can ask for help on a mailing list or on Discord. Please send bug reports and feature requests to GitHub.

- **Mailing Lists**: users@lists.zephyrproject.org is usually the right list to ask for help. Search archives and sign up here.
- **Discord**: You can join with this Discord invite.
- **GitHub**: Use GitHub issues for bugs and feature requests.

How to Ask

**Important**: Please search this documentation and the mailing list archives first. Your question may have an answer there.

Don’t just say “this isn’t working” or ask “is this working?”. Include as much detail as you can about:

1. What you want to do
2. What you tried (commands you typed, etc.)
3. What happened (output of each command, etc.)

**Use Copy/Paste**

Please **copy/paste text** instead of taking a picture or a screenshot of it. Text includes source code, terminal commands, and their output.

Doing this makes it easier for people to help you, and also helps other users search the archives. Unnecessary screenshots exclude vision impaired developers; some are major Zephyr contributors. **Accessibility** has been recognized as a basic human right by the United Nations.

When copy/pasting more than 5 lines of computer text into Discord or Github, create a snippet using three backticks to delimit the snippet.

2.2 Beyond the Getting Started Guide

The **Getting Started Guide** gives a straight-forward path to set up your Linux, macOS, or Windows environment for Zephyr development. In this document, we delve deeper into Zephyr development setup issues and alternatives.

2.2.1 Python and pip

Python 3 and its package manager, pip\(^1\), are used extensively by Zephyr to install and run scripts required to compile and run Zephyr applications, set up and maintain the Zephyr development environment, and build project documentation.

---

\(^1\) pip is Python’s package installer. Its `install` command first tries to reuse packages and package dependencies already installed on your computer. If that is not possible, pip `install` downloads them from the Python Package Index (PyPI) on the Internet.

The package versions requested by Zephyr’s `requirements.txt` may conflict with other requirements on your system, in which case you may want to set up a virtualenv for Zephyr development.
Depending on your operating system, you may need to provide the --user flag to the pip3 command when installing new packages. This is documented throughout the instructions. See Installing Packages in the Python Packaging User Guide for more information about pip\(^1\), including information on --user.

- On Linux, make sure ~/.local/bin is at the front of your PATH environment variable, or programs installed with --user won’t be found. Installing with --user avoids conflicts between pip and the system package manager, and is the default on Debian-based distributions.
- On macOS, Homebrew disables --user.
- On Windows, see the Installing Packages information on --user if you require using this option.

On all operating systems, pip’s -U flag installs or updates the package if the package is already installed locally but a more recent version is available. It is good practice to use this flag if the latest version of a package is required. (Check the scripts/requirements.txt file to see if a specific Python package version is expected.)

### 2.2.2 Advanced Platform Setup

Here are some alternative instructions for more advanced platform setup configurations for supported development platforms:

#### Install Linux Host Dependencies

Documentation is available for these Linux distributions:

- Ubuntu
- Fedora
- Clear Linux
- Arch Linux

For distributions that are not based on rolling releases, some of the requirements and dependencies may not be met by your package manager. In that case please follow the additional instructions that are provided to find software from sources other than the package manager.

**Note:** If you’re working behind a corporate firewall, you’ll likely need to configure a proxy for accessing the internet, if you haven’t done so already. While some tools use the environment variables http_proxy and https_proxy to get their proxy settings, some use their own configuration files, most notably apt and git.

#### Update Your Operating System

Ensure your host system is up to date.

**Ubuntu**

```bash
sudo apt-get update
sudo apt-get upgrade
```

**Fedora**

```bash
sudo dnf upgrade
```

**Clear Linux**


**Install Requirements and Dependencies**  
Note that both Ninja and Make are installed with these instructions; you only need one.

**Ubuntu**

```
sudo apt-get install --no-install-recommends git cmake ninja-build gperf 
ccache dfu-util device-tree-compiler wget python3-dev python3-pip python3-setuptools python3-tk python3-wheel xz-utils file 
made gcc gcc-multilib g++-multilib libssl-dev libmagic1
```

**Fedora**

```
sudo dnf group install "Development Tools" "C Development Tools and Libraries"

sudo dnf install cmake ninja-build gperf dfu-util dtc wget which 
python3-pip python3-tkinter xz file python3-devel SDL2-devel
```

**Clear Linux**

```
sudo swupd bundle-add c-basic dev-utils dfu-util dtc 
   os-core-dev python-basic python3-basic python3-tcl
```

The Clear Linux focus is on native performance and security and not cross-compilation. For that reason it uniquely exports by default to the environment of all users a list of compiler and linker flags. Zephyr’s CMake build system will either warn or fail because of these. To clear the C/C++ flags among these and fix the Zephyr build, run the following command as root then log out and back in:

```
echo 'unset CFLAGS CXXFLAGS' >> /etc/profile.d/unset_cflags.sh
```

Note this command unsets the C/C++ flags for all users on the system. Each Linux distribution has a unique, relatively complex and potentially evolving sequence of bash initialization files sourcing each other and Clear Linux is no exception. If you need a more flexible solution, start by looking at the logic in /usr/share/defaults/etc/profile.

**Arch Linux**

```
sudo pacman -S git cmake ninja gperf ccache dfu-util dtc wget 
python-pip python-setuptools python-wheel tk xz file make
```

**CMake**  
A recent CMake version is required. Check what version you have by using `cmake --version`. If you have an older version, there are several ways of obtaining a more recent one:

- On Ubuntu, you can follow the instructions for adding the kitware third-party apt repository to get an updated version of cmake using apt.

- Download and install a packaged cmake from the CMake project site. (Note this won’t uninstall the previous version of cmake.)

```
cd ~
chmod +x cmake-3.21.1-Linux-x86_64.sh
sudo ./cmake-3.21.1-Linux-x86_64.sh --skip-license --prefix=/usr/local
hash -r
```
Zephyr Project Documentation, Release 3.6.0-rc3
The hash -r command may be necessary if the installation script put cmake into a new
location on your PATH.
• Download and install from the pre-built binaries provided by the CMake project itself in
the CMake Downloads page. For example, to install version 3.21.1 in ~/bin/cmake:
mkdir $HOME/bin/cmake && cd $HOME/bin/cmake
,→64.sh
yes | sh cmake-3.21.1-Linux-x86_64.sh | cat
echo "export PATH=$PWD/cmake-3.21.1-Linux-x86_64/bin:\$PATH" >> $HOME/.zephyrrc

• Use pip3:
pip3 install --user cmake

Note this won’t uninstall the previous version of cmake and will install the new cmake into
your ~/.local/bin folder so you’ll need to add ~/.local/bin to your PATH. (See Python and pip
for details.)
• Check your distribution’s beta or unstable release package library for an update.
• On Ubuntu you can also use snap to get the latest version available:
sudo snap install cmake

After updating cmake, verify that the newly installed cmake is found using cmake --version. You
might also want to uninstall the CMake provided by your package manager to avoid conflicts.
(Use whereis cmake to find other installed versions.)
DTC (Device Tree Compiler) A recent DTC version is required. Check what version you have
by using dtc --version. If you have an older version, either install a more recent one by building
from source, or use the one that is bundled in the Zephyr SDK by installing it.
Python A modern Python 3 version is required. Check what version you have by using python3
--version.
If you have an older version, you will need to install a more recent Python 3. You can build from
source, or use a backport from your distribution’s package manager channels if one is available.
Isolating this Python in a virtual environment is recommended to avoid interfering with your
system Python.
Install the Zephyr Software Development Kit (SDK) The Zephyr Software Development Kit
(SDK) contains toolchains for each of Zephyr’s supported architectures. It also includes additional host tools, such as custom QEMU and OpenOCD.
Use of the Zephyr SDK is highly recommended and may even be required under certain conditions (for example, running tests in QEMU for some architectures).
The Zephyr SDK supports the following target architectures:
• ARC (32-bit and 64-bit; ARCv1, ARCv2, ARCv3)
• ARM (32-bit and 64-bit; ARMv6, ARMv7, ARMv8; A/R/M Profiles)
• MIPS (32-bit and 64-bit)
• Nios II
• RISC-V (32-bit and 64-bit; RV32I, RV32E, RV64I)
• x86 (32-bit and 64-bit)

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Chapter 2. Developing with Zephyr


Follow these steps to install the Zephyr SDK:

1. Download and verify the Zephyr SDK bundle:
   - Run `wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/zephyr-sdk-0.16.5_linux-x86_64.tar.xz`
   - Run `wget -O - https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/sha256.sum | shasum --check --ignore-missing

   You can change 0.16.5 to another version if needed; the Zephyr SDK Releases page contains all available SDK releases.

   If your host architecture is 64-bit ARM (for example, Raspberry Pi), replace x86_64 with aarch64 in order to download the 64-bit ARM Linux SDK.

2. Extract the Zephyr SDK bundle archive:
   - Run `cd <sdk download directory>`
   - Run `tar xvf zephyr-sdk-0.16.5_linux-x86_64.tar.xz`

3. Run the Zephyr SDK bundle setup script:
   - Run `cd zephyr-sdk-0.16.5`
   - Run `./setup.sh`

   If this fails, make sure Zephyr's dependencies were installed as described in Install Requirements and Dependencies.

If you want to uninstall the SDK, remove the directory where you installed it. If you relocate the SDK directory, you need to re-run the setup script.

**Note:** It is recommended to extract the Zephyr SDK bundle at one of the following locations:

- $HOME
- $HOME/.local
- $HOME/.local/opt
- $HOME/bin
- /opt
- /usr/local

The Zephyr SDK bundle archive contains the zephyr-sdk-<version> directory and, when extracted under $HOME, the resulting installation path will be $HOME/zephyr-sdk-<version>.

If you install the Zephyr SDK outside any of these locations, you must register the Zephyr SDK in the CMake package registry by running the setup script, or set ZEPHYR_SDK_INSTALL_DIR to point to the Zephyr SDK installation directory.

You can also use ZEPHYR_SDK_INSTALL_DIR for pointing to a directory containing multiple Zephyr SDKs, allowing for automatic toolchain selection. For example, ZEPHYR_SDK_INSTALL_DIR=/company/tools, where the company/tools folder contains the following subfolders:

- /company/tools/zephyr-sdk-0.13.2
- /company/tools/zephyr-sdk-a.b.c
- /company/tools/zephyr-sdk-x.y.z

This allows the Zephyr build system to choose the correct version of the SDK, while allowing multiple Zephyr SDKs to be grouped together at a specific path.
Building on Linux without the Zephyr SDK  The Zephyr SDK is provided for convenience and ease of use. It provides toolchains for all Zephyr target architectures, and does not require any extra flags when building applications or running tests. In addition to cross-compilers, the Zephyr SDK also provides prebuilt host tools. It is, however, possible to build without the SDK’s toolchain by using another toolchain as described in the Toolchains section.

As already noted above, the SDK also includes prebuilt host tools. To use the SDK’s prebuilt host tools with a toolchain from another source, you must set the ZEPHYR_SDK_INSTALL_DIR environment variable to the Zephyr SDK installation directory. To build without the Zephyr SDK’s prebuilt host tools, the ZEPHYR_SDK_INSTALL_DIR environment variable must be unset.

To make sure this variable is unset, run:

```bash
unset ZEPHYR_SDK_INSTALL_DIR
```

macOS alternative setup instructions

**Important note about Gatekeeper**  Starting with macOS 10.15 Catalina, applications launched from the macOS Terminal application (or any other terminal emulator) are subject to the same system security policies that are applied to applications launched from the Dock. This means that if you download executable binaries using a web browser, macOS will not let you execute those from the Terminal by default. In order to get around this issue you can take two different approaches:

- Run `xattr -r -d com.apple.quarantine /path/to/folder` where `path/to/folder` is the path to the enclosing folder where the executables you want to run are located.
- Open System Preferences • Security and Privacy • Privacy and then scroll down to “Developer Tools”. Then unlock the lock to be able to make changes and check the checkbox corresponding to your terminal emulator of choice. This will apply to any executable being launched from such terminal program.

Note that this section does **not** apply to executables installed with Homebrew, since those are automatically un-quarantined by brew itself. This is however relevant for most Toolchains.

**Additional notes for MacPorts users**  While MacPorts is not officially supported in this guide, it is possible to use MacPorts instead of Homebrew to get all the required dependencies on macOS. Note also that you may need to install rust and cargo for the Python dependencies to install correctly.

Windows alternative setup instructions

**Windows 10 WSL (Windows Subsystem for Linux)**  If you are running a recent version of Windows 10 you can make use of the built-in functionality to natively run Ubuntu binaries directly on a standard command-prompt. This allows you to use software such as the Zephyr SDK without setting up a virtual machine.

**Warning:**  Windows 10 version 1803 has an issue that will cause CMake to not work properly and is fixed in version 1809 (and later). More information can be found in Zephyr Issue 10420.

1. Install the Windows Subsystem for Linux (WSL).

   **Note:**  For the Zephyr SDK to function properly you will need Windows 10 build 15002 or greater. You can check which Windows 10 build you are running in the “About your PC”
section of the System Settings. If you are running an older Windows 10 build you might need to install the Creator’s Update.

2. Follow the Ubuntu instructions in the Install Linux Host Dependencies document.

### 2.2.3 Install a Toolchain

Zephyr binaries are compiled and linked by a toolchain comprised of a cross-compiler and related tools which are different from the compiler and tools used for developing software that runs natively on your host operating system.

You can install the Zephyr SDK to get toolchains for all supported architectures, or install an alternate toolchain recommended by the SoC vendor or a specific board (check your specific board-level documentation).

You can configure the Zephyr build system to use a specific toolchain by setting environment variables such as ZEPHYR_TOOLCHAIN_VARIANT to a supported value, along with additional variable(s) specific to the toolchain variant.

### 2.2.4 Updating the Zephyr SDK toolchain

When updating Zephyr SDK, check whether the ZEPHYR_TOOLCHAIN_VARIANT or ZEPHYR_SDK_INSTALL_DIR environment variables are already set.

- If the variables are not set, the latest compatible version of Zephyr SDK will be selected by default. Proceed to next step without making any changes.

- If ZEPHYR_TOOLCHAIN_VARIANT is set, the corresponding toolchain will be selected at build time. Zephyr SDK is identified by the value zephyr. If the ZEPHYR_TOOLCHAIN_VARIANT environment variable is not zephyr, then either unset it or change its value to zephyr to make sure Zephyr SDK is selected.

- If the ZEPHYR_SDK_INSTALL_DIR environment variable is set, it will override the default lookup location for Zephyr SDK. If you install Zephyr SDK to one of the recommended locations, you can unset this variable. Otherwise, set it to your chosen install location.

For more information about these environment variables in Zephyr, see Important Environment Variables.

### 2.2.5 Cloning the Zephyr Repositories

The Zephyr project source is maintained in the GitHub zephyr repo. External modules used by Zephyr are found in the parent GitHub Zephyr project. Because of these dependencies, it’s convenient to use the Zephyr-created west tool to fetch and manage the Zephyr and external module source code. See Basics for more details.

Once your development tools are installed, use West (Zephyr’s meta-tool) to create, initialize, and download sources from the zephyr and external module repos. We’ll use the name zephyrproject, but you can choose any name that does not contain a space anywhere in the path.

```
west init zephyrproject
cd zephyrproject
west update
```

The west update command fetches and keeps Modules (External projects) in the zephyrproject folder in sync with the code in the local zephyr repo.
**Warning:** You must run `west update` any time the `zephyr/west.yml` changes, caused, for example, when you pull the `zephyr` repository, switch branches in it, or perform a git bisect inside of it.

---

**Keeping Zephyr updated**

To update the Zephyr project source code, you need to get the latest changes via `git`. Afterwards, run `west update` as mentioned in the previous paragraph.

```
# replace zephyrproject with the path you gave west init
cd zephyrproject/zephyr
git pull
west update
```

---

### 2.2.6 Export Zephyr CMake package

The Zephyr CMake Package can be exported to CMake's user package registry if it has not already been done as part of Getting Started Guide.

### 2.2.7 Board Aliases

Developers who work with multiple boards may find explicit board names cumbersome and want to use aliases for common targets. This is supported by a CMake file with content like this:

```
# Variable foo_BOARD_ALIAS=bar replaces BOARD=foo with BOARD=bar and
# sets BOARD_ALIAS=foo in the CMake cache.
set(pca10028_BOARD_ALIAS nrf51dk_nrf51422)
set(pca10056_BOARD_ALIAS nrf52840dk_nrf52840)
set(k64f_BOARD_ALIAS frdm_k64f)
set(sltb004a_BOARD_ALIAS efr32mg_sltb004a)
```

and specifying its location in `ZEPHYR_BOARD_ALIASES`. This enables use of aliases pca10028 in contexts like `cmake -DBOARD=pca10028` and `west -b pca10028`.

### 2.2.8 Build and Run an Application

You can build, flash, and run Zephyr applications on real hardware using a supported host system. Depending on your operating system, you can also run it in emulation with QEMU, or as a native application with `native_sim`. Additional information about building applications can be found in the Building an Application section.

#### Build Blinky

Let's build the blinky sample application.

Zephyr applications are built to run on specific hardware, called a “board”\(^2\). We'll use the Phytec `reel_board` here, but you can change the `reel_board` build target to another value if you have

---

\(^2\) This has become something of a misnomer over time. While the target can be, and often is, a microprocessor running on its own dedicated hardware board, Zephyr also supports using QEMU to run targets built for other architectures in emulation, targets which produce native host system binaries that implement Zephyr's driver interfaces with POSIX APIs, and even running different Zephyr-based binaries on CPU cores of differing architectures on the same physical chip. Each of these hardware configurations is called a “board,” even though that doesn't always make perfect sense in context.
a different board. See boards or run west boards from anywhere inside the zephyrproject directory for a list of supported boards.

1. Go to the zephyr repository:

   ```bash
cd zephyrproject/zephyr
   ```

2. Build the blinky sample for the reel_board:

   ```bash
   west build -b reel_board samples/basic/blinky
   ```

The main build products will be in build/zephyr; build/zephyr/zephyr.elf is the blinky application binary in ELF format. Other binary formats, disassembly, and map files may be present depending on your board.

The other sample applications in the samples folder are documented in samples-and-demos.

**Note:** If you want to reuse an existing build directory for another board or application, you need to add the parameter `-p=auto` to `west build` to clean out settings and artifacts from the previous build.

### Run the Application by Flashing to a Board

Most hardware boards supported by Zephyr can be flashed by running `west flash`. This may require board-specific tool installation and configuration to work properly.

See [Run an Application](#) and your specific board's documentation in boards for additional details.

### Setting udev rules

Flashing a board requires permission to directly access the board hardware, usually managed by installation of the flashing tools. On Linux systems, if the `west flash` command fails, you likely need to define udev rules to grant the needed access permission.

Udev is a device manager for the Linux kernel and the udev daemon handles all user space events raised when a hardware device is added (or removed) from the system. We can add a rules file to grant access permission by non-root users to certain USB-connected devices.

The OpenOCD (On-Chip Debugger) project conveniently provides a rules file that defined board-specific rules for most Zephyr-supported arm-based boards, so we recommend installing this rules file by downloading it from their sourceforge repo, or if you've installed the Zephyr SDK there is a copy of this rules file in the SDK folder:

- Either download the OpenOCD rules file and copy it to the right location:

  ```bash
  wget -O 60-openocd.rules https://sf.net/p/openocd/code/ci/master/tree/contrib/60-
  openocd.rules?format=raw
  sudo cp 60-openocd.rules /etc/udev/rules.d
  ```

- or copy the rules file from the Zephyr SDK folder:

  ```bash
  sudo cp ${ZEPHYR_SDK_INSTALL_DIR}/sysroots/x86_64-pokysdk-linux/usr/share/openocd/
  contrib/60-openocd.rules /etc/udev/rules.d
  ```

Then, in either case, ask the udev daemon to reload these rules:

```bash
sudo udevadm control --reload
```
Unplug and plug in the USB connection to your board, and you should have permission to access the board hardware for flashing. Check your board-specific documentation (boards) for further information if needed.

**Run the Application in QEMU**

On Linux and macOS, you can run Zephyr applications via emulation on your host system using QEMU when targeting either the x86 or ARM Cortex-M3 architectures. (QEMU is included with the Zephyr SDK installation.)

On Windows, you need to install QEMU manually from Download QEMU. After installation, add path to QEMU installation folder to PATH environment variable. To enable QEMU in Test Runner (Twister) on Windows, set the environment variable QEMU_BIN_PATH to the path of QEMU installation folder.

For example, you can build and run the hello_world sample using the x86 emulation board configuration (qemu_x86), with:

```bash
# From the root of the zephyr repository
west build -b qemu_x86 samples/hello_world
west build -t run
```

To exit QEMU, type Ctrl-a, then x.

Use qemu_cortex_m3 to target an emulated Arm Cortex-M3 sample.

**Run a Sample Application natively (Linux)**

You can compile some samples to run as host programs on Linux. See native_sim for more information. On 64-bit host operating systems, you need to install a 32-bit C library, or build targeting native_sim_64.

First, build Hello World for native_sim.

```bash
# From the root of the zephyr repository
west build -b native_sim samples/hello_world
```

Next, run the application.

```bash
west build -t run
# or just run zephyr.exe directly:
./build/zephyr/zephyr.exe
```

Press Ctrl-C to exit.

You can run ./build/zephyr/zephyr.exe --help to get a list of available options.

This executable can be instrumented using standard tools, such as gdb or valgrind.

### 2.3 Environment Variables

Various pages in this documentation refer to setting Zephyr-specific environment variables. This page describes how.
2.3.1 Setting Variables

Option 1: Just Once

To set the environment variable `MY_VARIABLE` to `foo` for the lifetime of your current terminal window:

**Linux/macOS**

```
export MY_VARIABLE=foo
```

**Windows**

```
set MY_VARIABLE=foo
```

**Warning:** This is best for experimentation. If you close your terminal window, use another terminal window or tab, restart your computer, etc., this setting will be lost forever. Using options 2 or 3 is recommended if you want to keep using the setting.

Option 2: In all Terminals

**Linux/macOS**

Add the `export MY_VARIABLE=foo` line to your shell's startup script in your home directory. For Bash, this is usually `~/.bashrc` on Linux or `~/.bash_profile` on macOS. Changes in these startup scripts don't affect shell instances already started; try opening a new terminal window to get the new settings.

**Windows**

You can use the `setx` program in `cmd.exe` or the third-party RapidEE program.

To use `setx`, type this command, then close the terminal window. Any new `cmd.exe` windows will have `MY_VARIABLE` set to `foo`.

```
setx MY_VARIABLE foo
```

To install RapidEE, a freeware graphical environment variable editor, using Chocolatey in an Administrator command prompt:

```
choco install rapidee
```

You can then run `rapidee` from your terminal to launch the program and set environment variables. Make sure to use the “User” environment variables area – otherwise, you have to run RapidEE as administrator. Also make sure to save your changes by clicking the Save button at top left before exiting. Settings you make in RapidEE will be available whenever you open a new terminal window.

Option 3: Using zephyrrc files

Choose this option if you don't want to make the variable's setting available to all of your terminals, but still want to save the value for loading into your environment when you are using Zephyr:

**Linux/macOS**

Create a file named `~/.zephyrrc` if it doesn't exist, then add this line to it:
export MY_VARIABLE=foo

To get this value back into your current terminal environment, you must run `source zephyr-env.sh` from the main zephyr repository. Among other things, this script sources `~/.zephyrrc`.

The value will be lost if you close the window, etc.; run `source zephyr-env.sh` again to get it back.

Windows

Add the line `set MY_VARIABLE=foo` to the file `%userprofile%\zephyrrc.cmd` using a text editor such as Notepad to save the value.

To get this value back into your current terminal environment, you must run `zephyr-env.cmd` in a `cmd.exe` window after changing directory to the main zephyr repository. Among other things, this script runs `%userprofile%\zephyrrc.cmd`.

The value will be lost if you close the window, etc.; run `zephyr-env.cmd` again to get it back.

These scripts:

- set `ZEPHYR_BASE` to the location of the zephyr repository
- adds some Zephyr-specific locations (such as zephyr's scripts directory) to your `PATH` environment variable
- loads any settings from the `zephyrrc` files described above in Option 3: Using `zephyrrc` files.

You can thus use them any time you need any of these settings.

### 2.3.2 Zephyr Environment Scripts

You can use the zephyr repository scripts `zephyr-env.sh` (for macOS and Linux) and `zephyr-env.cmd` (for Windows) to load Zephyr-specific settings into your current terminal's environment. To do so, run this command from the zephyr repository:

**Linux/macOS**

```
source zephyr-env.sh
```

**Windows**

```
zephyr-env.cmd
```

These scripts:

- set `ZEPHYR_BASE` to the location of the zephyr repository
- adds some Zephyr-specific locations (such as zephyr's scripts directory) to your `PATH` environment variable
- loads any settings from the `zephyrrc` files described above in Option 3: Using `zephyrrc` files.

You can thus use them any time you need any of these settings.

### 2.3.3 Important Environment Variables

Some Important Build System Variables can also be set in the environment. Here is a description of some of these important environment variables. This is not a comprehensive list.

**BOARD**

See Important Build System Variables.
The following additional environment variables are significant when configuring the toolchain used to build Zephyr applications.

- **ZEPHYR_SDK_INSTALL_DIR**
  Path where Zephyr SDK is installed.

- **ZEPHYR_TOOLCHAIN_VARIANT**
  The name of the toolchain to use.

- **{TOOLCHAIN}_TOOLCHAIN_PATH**
  Path to the toolchain specified by `ZEPHYR_TOOLCHAIN_VARIANT`. For example, if `ZEPHYR_TOOLCHAIN_VARIANT=llvm`, use `LLVM_TOOLCHAIN_PATH`. (Note the capitalization when forming the environment variable name.)

You might need to update some of these variables when you update the Zephyr SDK toolchain.

Emulators and boards may also depend on additional programs. The build system will try to locate those programs automatically, but may rely on additional CMake or environment variables to do so. Please consult your emulator's or board's documentation for more information. The following environment variables may be useful in such situations:

- **PATH**
  PATH is an environment variable used on Unix-like or Microsoft Windows operating systems to specify a set of directories where executable programs are located.

### 2.4 Application Development

**Note:** In this document, we'll assume:

- your **application directory**, `<app>`, is something like `<home>/zephyrproject/app`
- its **build directory** is `<app>/build`

These terms are defined below. On Linux/macOS, `<home>` is equivalent to `~`. On Windows, it's `%userprofile%`.

Keeping your application inside the workspace (`<home>/zephyrproject`) makes it easier to use `west build` and other commands with it. (You can put your application anywhere as long as `ZEPHYR_BASE` is set appropriately, though.)
2.4.1 Overview

Zephyr's build system is based on CMake.

The build system is application-centric, and requires Zephyr-based applications to initiate building the Zephyr source code. The application build controls the configuration and build process of both the application and Zephyr itself, compiling them into a single binary.

The main zephyr repository contains Zephyr's source code, configuration files, and build system. You also likely have installed various Modules (External projects) alongside the zephyr repository, which provide third party source code integration.

The files in the application directory link Zephyr and any modules with the application. This directory contains all application-specific files, such as application-specific configuration files and source code.

Here are the files in a simple Zephyr application:

```
<app>
  ├── CMakeLists.txt
  │   └── app.overlay
  │   ├── prj.conf
  │   └── VERSION
  └── src
      └── main.c
```

These contents are:

- **CMakeLists.txt**: This file tells the build system where to find the other application files, and links the application directory with Zephyr's CMake build system. This link provides features supported by Zephyr's build system, such as board-specific configuration files, the ability to run and debug compiled binaries on real or emulated hardware, and more.

- **app.overlay**: This is a devicetree overlay file that specifies application-specific changes which should be applied to the base devicetree for any board you build for. The purpose of devicetree overlays is usually to configure something about the hardware used by the application.

  The build system looks for app.overlay by default, but you can add more devicetree overlays, and other default files are also searched for.

  See [Devicetree](#) for more information about devicetree.

- **prj.conf**: This is a Kconfig fragment that specifies application-specific values for one or more Kconfig options. These application settings are merged with other settings to produce the final configuration. The purpose of Kconfig fragments is usually to configure the software features used by the application.

  The build system looks for prj.conf by default, but you can add more Kconfig fragments, and other default files are also searched for.

  See [Kconfig Configuration](#) below for more information.

- **VERSION**: A text file that contains several version information fields. These fields let you manage the lifecycle of the application and automate providing the application version when signing application images.

  See [Application version management](#) for more information about this file and how to use it.

- **main.c**: A source code file. Applications typically contain source files written in C, C++, or assembly language. The Zephyr convention is to place them in a subdirectory of <app> named src.

Once an application has been defined, you will use CMake to generate a build directory, which contains the files you need to build the application and Zephyr, then link them together into a final binary you can run on your board. The easiest way to do this is with west build, but you
can use CMake directly also. Application build artifacts are always generated in a separate build
directory: Zephyr does not support “in-tree” builds.

The following sections describe how to create, build, and run Zephyr applications, followed by
more detailed reference material.

## 2.4.2 Application types

We distinguish three basic types of Zephyr application based on where `<app>` is located:

<table>
<thead>
<tr>
<th>Application type</th>
<th>&lt;app&gt; location</th>
</tr>
</thead>
<tbody>
<tr>
<td>repository</td>
<td>zephyr repository</td>
</tr>
<tr>
<td>workspace</td>
<td>west workspace where Zephyr is installed</td>
</tr>
<tr>
<td>freestanding</td>
<td>other locations</td>
</tr>
</tbody>
</table>

We’ll discuss these more below. To learn how the build system supports each type, see Zephyr CMake Package.

### Zephyr repository application

An application located within the `zephyr` source code repository in a Zephyr *west workspace* is
referred to as a Zephyr repository application. In the following example, the `hello_world` sample
is a Zephyr repository application:

```
zephyrproject/
├── .west/
│   └── config
└── zephyr/
    ├── arch/
    ├── boards/
    └── samples/
        └── hello_world/
    └── tests/
    └── ...
```

### Zephyr workspace application

An application located within a *workspace*, but outside the `zephyr` repository itself, is referred
to as a Zephyr workspace application. In the following example, `app` is a Zephyr workspace application:

```
zephyrproject/
├── .west/
│   └── config
├── zephyr/
│   └── bootloader/
│       └── modules/
│           └── tools/
│                  └── vendor/private-repositories>/
└── applications/
    └── app/
```
Zephyr freestanding application

A Zephyr application located outside of a Zephyr workspace is referred to as a Zephyr freestanding application. In the following example, app is a Zephyr freestanding application:

```plaintext
<home>/
├── zephyrproject/
    │ ├── .west/
    │ │ └── config
    │ ├── zephyr/
    │ ├── bootloader/
    │ ├── modules/
    │ ... 
    └── app/
        ├── CMakeLists.txt
        ├── prj.conf
        └── src/
            └── main.c
```

2.4.3 Creating an Application

In Zephyr, you can either use a reference workspace application or create your application by hand.

Using a Reference Workspace Application

The example-application Git repository contains a reference workspace application. It is recommended to use it as a reference when creating your own application as described in the following sections.

The example-application repository demonstrates how to use several commonly-used features, such as:

- Custom board ports
- Custom devicetree bindings
- Custom device drivers
- Continuous Integration (CI) setup, including using twister
- A custom west extension command

Basic example-application Usage The easiest way to get started with the example-application repository within an existing Zephyr workspace is to follow these steps:

```plaintext
cd <home>/zephyrproject
git clone https://github.com/zephyrproject-rtos/example-application my-app
```

The directory name my-app above is arbitrary: change it as needed. You can now go into this directory and adapt its contents to suit your needs. Since you are using an existing Zephyr workspace, you can use west build or any other west commands to build, flash, and debug.

Advanced example-application Usage You can also use the example-application repository as a starting point for building your own customized Zephyr-based software distribution. This lets you do things like:

- remove Zephyr modules you don’t need
• add additional custom repositories of your own
• override repositories provided by Zephyr with your own versions
• share the results with others and collaborate further

The example-application repository contains a `west.yml` file and is therefore also a west manifest repository. Use this to create a new, customized workspace by following these steps:

```bash
cd <home>
mkdir my-workspace
cd my-workspace
git clone https://github.com/zephyrproject-rtos/example-application my-manifest-repo
west init -l my-manifest-repo
```

This will create a new workspace with the T2 topology, with my-manifest-repo as the manifest repository. The my-workspace and my-manifest-repo names are arbitrary: change them as needed.

Next, customize the manifest repository. The initial contents of this repository will match the example-application's contents when you clone it. You can then edit `my-manifest-repo/west.yml` to your liking, changing the set of repositories in it as you wish. See Manifest Imports for many examples of how to add or remove different repositories from your workspace as needed. Make any other changes you need to other files.

When you are satisfied, you can run:

```bash
west update
```

and your workspace will be ready for use.

If you push the resulting my-manifest-repo repository somewhere else, you can share your work with others. For example, let's say you push the repository to https://git.example.com/my-manifest-repo. Other people can then set up a matching workspace by running:

```bash
west init -m https://git.example.com/my-manifest-repo my-workspace
cd my-workspace
west update
```

From now on, you can collaborate on the shared software by pushing changes to the repositories you are using and updating `my-manifest-repo/west.yml` as needed to add and remove repositories, or change their contents.

### Creating an Application by Hand

You can follow these steps to create a basic application directory from scratch. However, using the example-application repository or one of Zephyr's samples-and-demos as a starting point is likely to be easier.

1. Create an application directory.
   
   For example, in a Unix shell or Windows cmd.exe prompt:

   ```bash
   mkdir app
   ```

   **Warning:** Building Zephyr or creating an application in a directory with spaces anywhere on the path is not supported. So the Windows path C:\Users\YourName\app will work, but C:\Users\Your Name\app will not.

2. Create your source code files.
It’s recommended to place all application source code in a subdirectory named src. This makes it easier to distinguish between project files and sources.

Continuing the previous example, enter:

```
cd app
mkdir src
```

3. Place your application source code in the src sub-directory. For this example, we’ll assume you created a file named src/main.c.

4. Create a file named CMakeLists.txt in the app directory with the following contents:

```
cmake_minimum_required(VERSION 3.20.0)
find_package(Zephyr)
project(my_zephyr_app)
target_sources(app PRIVATE src/main.c)
```

Notes:

- The `cmake_minimum_required()` call is required by CMake. It is also invoked by the Zephyr package on the next line. CMake will error out if its version is older than either the version in your CMakeLists.txt file or the version number in the Zephyr package.
- `find_package(Zephyr)` pulls in the Zephyr build system, which creates a CMake target named app (see Zephyr CMake Package). Adding sources to this target is how you include them in the build. The Zephyr package will define Zephyr-Kernel as a CMake project and enable support for the C, CXX, ASM languages.
- `project(my_zephyr_app)` defines your application's CMake project. This must be called after `find_package(Zephyr)` to avoid interference with Zephyr's project(Zephyr-Kernel).
- `target_sources(app PRIVATE src/main.c)` is to add your source file to the app target. This must come after `find_package(Zephyr)` which defines the target. You can add as many files as you want with `target_sources()`.

5. Create at least one Kconfig fragment for your application (usually named prj.conf) and set Kconfig option values needed by your application there. See Kconfig Configuration. If no Kconfig options need to be set, create an empty file.

6. Configure any devicetree overlays needed by your application, usually in a file named app.overlay. See Set devicetree overlays.

7. Set up any other files you may need, such as twister configuration files, continuous integration files, documentation, etc.

### 2.4.4 Important Build System Variables

You can control the Zephyr build system using many variables. This section describes the most important ones that every Zephyr developer should know about.

Note: The variables BOARD, CONF_FILE, and DTC_OVERLAY_FILE can be supplied to the build system in 3 ways (in order of precedence):

- As a parameter to the `west build` or `cmake` invocation via the `-D` command-line switch. If you have multiple overlay files, you should use quotations, "file1.overlay;file2.overlay"
- As Environment Variables.
- As a set(<VARIABLE> <VALUE>) statement in your CMakeLists.txt
Zephyr Project Documentation, Release 3.6.0-rc3

- **ZEPHYR_BASE**: Zephyr base variable used by the build system. `find_package(Zephyr)` will automatically set this as a cached CMake variable. But ZEPHYR_BASE can also be set as an environment variable in order to force CMake to use a specific Zephyr installation.

- **BOARD**: Selects the board that the application's build will use for the default configuration. See boards for built-in boards, and Board Porting Guide for information on adding board support.

- **CONF_FILE**: Indicates the name of one or more Kconfig configuration fragment files. Multiple filenames can be separated with either spaces or semicolons. Each file includes Kconfig configuration values that override the default configuration values. See The Initial Configuration for more information.

- **EXTRA_CONF_FILE**: Additional Kconfig configuration fragment files. Multiple filenames can be separated with either spaces or semicolons. This can be useful in order to leave CONF_FILE at its default value, but “mix in” some additional configuration options.

- **DTC_OVERLAY_FILE**: One or more devicetree overlay files to use. Multiple files can be separated with semicolons. See Set devicetree overlays for examples and Introduction to devicetree for information about devicetree and Zephyr.

- **EXTRA_DTC_OVERLAY_FILE**: Additional devicetree overlay files to use. Multiple files can be separated with semicolons. This can be useful to leave DTC_OVERLAY_FILE at its default value, but “mix in” some additional overlay files.

- **SHIELD**: see Shields

- **ZEPHYR_MODULES**: A CMake list containing absolute paths of additional directories with source code, Kconfig, etc. that should be used in the application build. See Modules (External projects) for details. If you set this variable, it must be a complete list of all modules to use, as the build system will not automatically pick up any modules from west.

- **EXTRA_ZEPHYR_MODULES**: Like ZEPHYR_MODULES, except these will be added to the list of modules found via west, instead of replacing it.

- **FILE_SUFFIX**: Optional suffix for filenames that will be added to Kconfig fragments and devicetree overlays (if these files exists, otherwise will fallback to the name without the prefix). See File Suffixes for details.

**Note**: You can use a Zephyr Build Configuration CMake packages to share common settings for these variables.

### 2.4.5 Application CMakeLists.txt

Every application must have a CMakeLists.txt file. This file is the entry point, or top level, of the build system. The final zephyr.elf image contains both the application and the kernel libraries.

This section describes some of what you can do in your CMakeLists.txt. Make sure to follow these steps in order.

1. If you only want to build for one board, add the name of the board configuration for your application on a new line. For example:

   ```
   set(BOARD qemu_x86)
   ```

   Refer to boards for more information on available boards.

   The Zephyr build system determines a value for BOARD by checking the following, in order (when a BOARD value is found, CMake stops looking further down the list):
1. Any previously used value as determined by the CMake cache takes highest precedence. This ensures you don’t try to run a build with a different BOARD value than you set during the build configuration step.

2. If any value given on the CMake command line (directly or indirectly via west build) using -DBOARD=YOUR_BOARD will be checked for and used next.

3. If an environment variable BOARD is set, its value will then be used.

4. Finally, if you set BOARD in your application CMakeLists.txt as described in this step, this value will be used.

2. If your application uses a configuration file or files other than the usual prj.conf (or prj_YOUR_BOARD.conf, where YOUR_BOARD is a board name), add lines setting the CONF_FILE variable to these files appropriately. If multiple filenames are given, separate them by a single space or semicolon. CMake lists can be used to build up configuration fragment files in a modular way when you want to avoid setting CONF_FILE in a single place. For example:

```cmake
set(CONF_FILE "fragment_file1.conf")
list(APPEND CONF_FILE "fragment_file2.conf")
```

See The Initial Configuration for more information.

3. If your application uses devicetree overlays, you may need to set DTC_OVERLAY_FILE. See Set devicetree overlays.

4. If your application has its own kernel configuration options, create a Kconfig file in the same directory as your application’s CMakeLists.txt. See the Kconfig section of the manual for detailed Kconfig documentation.

   An (unlikely) advanced use case would be if your application has its own unique configuration options that are set differently depending on the build configuration.

   If you just want to set application specific values for existing Zephyr configuration options, refer to the CONF_FILE description above.

   Structure your Kconfig file like this:

   ```cmake
   # SPDX-License-Identifier: Apache-2.0
   mainmenu "Your Application Name"
   
   # Your application configuration options go here
   
   # Sources Kconfig.zephyr in the Zephyr root directory.
   
   # Note: All 'source' statements work relative to the Zephyr root directory (due
   # to the $srctree environment variable being set to $ZEPHYR_BASE). If you want
   # to 'source' relative to the current Kconfig file instead, use 'rsource' (or a
   # path relative to the Zephyr root).
   
   source "Kconfig.zephyr"
   ```

   **Note:** Environment variables in source statements are expanded directly, so you do not need to define an option env="ZEPHYR_BASE" Kconfig “bounce” symbol. If you use such a symbol, it must have the same name as the environment variable.

   See Kconfig extensions for more information.

The Kconfig file is automatically detected when placed in the application directory, but it is also possible for it to be found elsewhere if the CMake variable KCONFIG_ROOT is set with an absolute path.
5. Specify that the application requires Zephyr on a new line, after any lines added from the steps above:

```cmake
find_package(Zephyr)
project(my_zephyr_app)
```

**Note:** `find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})` can be used if enforcing a specific Zephyr installation by explicitly setting the `ZEPHYR_BASE` environment variable should be supported. All samples in Zephyr supports the `ZEPHYR_BASE` environment variable.

6. Now add any application source files to the ‘app’ target library, each on their own line, like so:

```cmake
target_sources(app PRIVATE src/main.c)
```

Below is a simple example CMakeList.txt:

```cmake
set(BOARD qemu_x86)
find_package(Zephyr)
project(my_zephyr_app)
target_sources(app PRIVATE src/main.c)
```

The CMake property `HEX_FILES_TO_MERGE` leverages the application configuration provided by Kconfig and CMake to let you merge externally built hex files with the hex file generated when building the Zephyr application. For example:

```cmake
set_property(GLOBAL APPEND PROPERTY HEX_FILES_TO_MERGE
             ${app_bootloader_hex}
             ${PROJECT_BINARY_DIR}/${KERNEL_HEX_NAME}
             ${app_provision_hex})
```

### 2.4.6 CMakeCache.txt

CMake uses a CMakeCache.txt file as persistent key/value string storage used to cache values between runs, including compile and build options and paths to library dependencies. This cache file is created when CMake is run in an empty build folder.

For more details about the CMakeCache.txt file see the official CMake documentation running-cmake.

### 2.4.7 Application Configuration

#### Application Configuration Directory

Zephyr will use configuration files from the application's configuration directory except for files with an absolute path provided by the arguments described earlier, for example `CONF_FILE`, `EXTRA_CONF_FILE`, `DTC_OVERLAY_FILE`, and `EXTRA_DTC_OVERLAY_FILE`.

The application configuration directory is defined by the `APPLICATION_CONFIG_DIR` variable. `APPLICATION_CONFIG_DIR` will be set by one of the sources below with the highest priority listed first.
1. If `APPLICATION_CONFIG_DIR` is specified by the user with 
   `-DAPPLICATION_CONFIG_DIR=<path>` or in a CMake file before `find_package(Zephyr)`
   then this folder is used as the application's configuration directory.

2. The application's source directory.

**Kconfig Configuration**

Application configuration options are usually set in `prj.conf` in the application directory. For example, C++ support could be enabled with this assignment:

```
CONFIG_CPP=y
```

Looking at existing samples is a good way to get started.

See [Setting Kconfig configuration values](#) for detailed documentation on setting Kconfig configuration values. The [The Initial Configuration](#) section on the same page explains how the initial configuration is derived. See `kconfig-search` for a complete list of configuration options. See [Hardening Tool](#) for security information related with Kconfig options.

The other pages in the [Kconfig section of the manual](#) are also worth going through, especially if you planning to add new configuration options.

**Experimental features** Zephyr is a project under constant development and thus there are features that are still in early stages of their development cycle. Such features will be marked `[EXPERIMENTAL]` in their Kconfig title.

The `CONFIG_WARN_EXPERIMENTAL` setting can be used to enable warnings at CMake configure time if any experimental feature is enabled.

```
CONFIG_WARN_EXPERIMENTAL=y
```

For example, if option `CONFIG_FOO` is experimental, then enabling it and `CONFIG_WARN_EXPERIMENTAL` will print the following warning at CMake configure time when you build an application:

```
warning: Experimental symbol FOO is enabled.
```

**Devicetree Overlays**

See [Set devicetree overlays](#).

**File Suffixes**

Zephyr applications might want to have a single code base with multiple configurations for different build/product variants which would necessitate different Kconfig options and devicetree configuration. In order to better configure this, Zephyr provides a `FILE_SUFFIX` option when configuring applications that can be automatically appended to filenames. This is applied to Kconfig fragments and board overlays but with a fallback so that if such files do not exist, the files without these suffixes will be used instead.

Given the following example project layout:

```
<app>
  ├── CMakeLists.txt
  │   └── prj.conf
  │   └── prj_mouse.conf
```

(continues on next page)
• If this is built normally without FILE_SUFFIX being defined for native_posix then prj.conf
  and boards/native_posix.overlay will be used.

• If this is build normally without FILE_SUFFIX being defined for qemu_cortex_m3 then prj.
  conf will be used, no application devicetree overlay will be used.

• If this is built with FILE_SUFFIX set to mouse for native_posix then prj_mouse.conf and
  boards/native_posix.overlay will be used (there is no native_posix_mouse.overlay file
  so it falls back to native_posix.overlay).

• If this is build with FILE_SUFFIX set to mouse for qemu_cortex_m3 then prj_mouse.conf will
  be used and boards/qemu_cortex_m3Mouse.overlay will be used.

Note: When CONF_FILE is set in the form of prj_X.conf then the X will be used as the build type.
If this is combined with FILE_SUFFIX then the file suffix option will take priority over the build type.

2.4.8 Application-Specific Code

Application-specific source code files are normally added to the application's src directory. If
the application adds a large number of files the developer can group them into sub-directories
under src, to whatever depth is needed.

Application-specific source code should not use symbol name prefixes that have been reserved
by the kernel for its own use. For more information, see Naming Conventions.

Third-party Library Code

It is possible to build library code outside the application’s src directory but it is important that
both application and library code targets the same Application Binary Interface (ABI). On most
architectures there are compiler flags that control the ABI targeted, making it important that
both libraries and applications have certain compiler flags in common. It may also be useful for
glue code to have access to Zephyr kernel header files.

To make it easier to integrate third-party components, the Zephyr build system has defined
CMake functions that give application build scripts access to the zephyr compiler options. The
functions are documented and defined in cmake/modules/extensions.cmake and follow the nam-
ing convention zephyr_get_<type>_<format>.

The following variables will often need to be exported to the third-party build system.

• CMAKE_C_COMPILER, CMAKE_AR.

• ARCH and BOARD, together with several variables that identify the Zephyr kernel version.

samples/application_development/external_lib is a sample project that demonstrates some of
these features.
2.4.9 Building an Application

The Zephyr build system compiles and links all components of an application into a single application image that can be run on simulated hardware or real hardware.

Like any other CMake-based system, the build process takes place in two stages. First, build files (also known as a buildsystem) are generated using the cmake command-line tool while specifying a generator. This generator determines the native build tool the buildsystem will use in the second stage. The second stage runs the native build tool to actually build the source files and generate an image. To learn more about these concepts refer to the CMake introduction in the official CMake documentation.

Although the default build tool in Zephyr is west, Zephyr’s meta-tool, which invokes cmake and the underlying build tool (ninja or make) behind the scenes, you can also choose to invoke cmake directly if you prefer. On Linux and macOS you can choose between the make and ninja generators (i.e. build tools), whereas on Windows you need to use ninja, since make is not supported on this platform. For simplicity we will use ninja throughout this guide, and if you choose to use west build to build your application know that it will default to ninja under the hood.

As an example, let's build the Hello World sample for the reel_board:

Using west:

```
west build -b reel_board samples/hello_world
```

Using CMake and ninja:

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=reel_board samples/hello_world

# Now run the build tool on the generated build system:
ninja -Cbuild
```

On Linux and macOS, you can also build with make instead of ninja:

Using west:

```
• to use make just once, add -- -G"Unix Makefiles" to the west build command line; see the west build documentation for an example.
```

Using CMake directly:

```
# Use cmake to configure a Make-based buildsystem:
cmake -Bbuild -DBOARD=reel_board samples/hello_world

# Now run the build tool on the generated build system:
make -Cbuild
```

Basics

1. Navigate to the application directory `<app>`.

2. Enter the following commands to build the application's zephyr.elf image for the board specified in the command-line parameters:

Using west:

```
west build -b <board>
```

Using CMake and ninja:
mkdir build && cd build

# Use cmake to configure a Ninja-based buildsystem:
cmake -GNinja -DBOARD=<board> ..

# Now run the build tool on the generated build system:
ninja

If desired, you can build the application using the configuration settings specified in an alternate .conf file using the CONF_FILE parameter. These settings will override the settings in the application's .config file or its default .conf file. For example:

Using west:

west build -b <board> --DCONF_FILE=prj.alternate.conf

Using CMake and ninja:

mkdir build && cd build
cmake -GNinja -DBOARD=<board> -DCONF_FILE=prj.alternate.conf ..
ninja

As described in the previous section, you can instead choose to permanently set the board and configuration settings by either exporting BOARD and CONF_FILE environment variables or by setting their values in your CMakeLists.txt using set() statements. Additionally, west allows you to set a default board.

Build Directory Contents

When using the Ninja generator a build directory looks like this:

```
<app>/build
  └── build.ninja
  └── CMakeCache.txt
  └── CMakeFiles
  └── cmake_install.cmake
  └── rules.ninja
  └── zephyr

The most notable files in the build directory are:

- build.ninja, which can be invoked to build the application.
- A zephyr directory, which is the working directory of the generated build system, and where most generated files are created and stored.

After running ninja, the following build output files will be written to the zephyr sub-directory of the build directory. (This is not the Zephyr base directory, which contains the Zephyr source code etc. and is described above.)

- .config, which contains the configuration settings used to build the application.

Note: The previous version of .config is saved to .config.old whenever the configuration is updated. This is for convenience, as comparing the old and new versions can be handy.

- Various object files (.o files and .a files) containing compiled kernel and application code.
- zephyr.elf, which contains the final combined application and kernel binary. Other binary output formats, such as .hex and .bin, are also supported.
Rebuilding an Application

Application development is usually fastest when changes are continually tested. Frequently rebuilding your application makes debugging less painful as the application becomes more complex. It's usually a good idea to rebuild and test after any major changes to the application's source files, CMakeLists.txt files, or configuration settings.

**Important:** The Zephyr build system rebuilds only the parts of the application image potentially affected by the changes. Consequently, rebuilding an application is often significantly faster than building it the first time.

Sometimes the build system doesn’t rebuild the application correctly because it fails to recompile one or more necessary files. You can force the build system to rebuild the entire application from scratch with the following procedure:

1. Open a terminal console on your host computer, and navigate to the build directory `<app>/build`.
2. Enter one of the following commands, depending on whether you want to use west or cmake directly to delete the application's generated files, except for the `.config` file that contains the application's current configuration information.
   ```bash
   west build -t clean
   
   or
   
   ninja clean
   ```

   Alternatively, enter one of the following commands to delete all generated files, including the `.config` files that contain the application's current configuration information for those board types.
   ```bash
   west build -t pristine
   
   or
   
   ninja pristine
   ```

   If you use west, you can take advantage of its capability to automatically make the build folder pristine whenever it is required.
3. Rebuild the application normally following the steps specified in *Building an Application* above.

Building for a board revision

The Zephyr build system has support for specifying multiple hardware revisions of a single board with small variations. Using revisions allows the board support files to make minor adjustments to a board configuration without duplicating all the files described in *Create your board directory* for each revision.

To build for a particular revision, use `<board>@<revision>` instead of plain `<board>`. For example:

Using west:
```bash
west build -b <board>@<revision>
```

Using CMake and ninja:
mkdir build && cd build
cmake -GNinja -DBOARD=<board>@<revision> ..
ninja

Check your board's documentation for details on whether it has multiple revisions, and what revisions are supported.
When targeting a board revision, the active revision will be printed at CMake configure time, like this:

```
-- Board: plank, Revision: 1.5.0
```

### 2.4.10 Run an Application

An application image can be run on a real board or emulated hardware.

**Running on a Board**

Most boards supported by Zephyr let you flash a compiled binary using the `flash` target to copy the binary to the board and run it. Follow these instructions to flash and run an application on real hardware:

1. Build your application, as described in *Building an Application*.
2. Make sure your board is attached to your host computer. Usually, you'll do this via USB.
3. Run one of these console commands from the build directory, `<app>/build`, to flash the compiled Zephyr image and run it on your board:

```
west flash
```

or

```
ninja flash
```

The Zephyr build system integrates with the board support files to use hardware-specific tools to flash the Zephyr binary to your hardware, then run it.

Each time you run the flash command, your application is rebuilt and flashed again.

In cases where board support is incomplete, flashing via the Zephyr build system may not be supported. If you receive an error message about flash support being unavailable, consult your board's documentation for additional information on how to flash your board.

**Note:** When developing on Linux, it's common to need to install board-specific udev rules to enable USB device access to your board as a non-root user. If flashing fails, consult your board's documentation to see if this is necessary.

### Running in an Emulator

Zephyr has built-in emulator support for QEMU. It allows you to run and test an application virtually, before (or in lieu of) loading and running it on actual target hardware.

Check out *Beyond the Getting Started Guide* for additional steps needed on Windows.

Follow these instructions to run an application via QEMU:

---

2.4. Application Development
1. Build your application for one of the QEMU boards, as described in *Building an Application*. For example, you could set `BOARD` to:
   - `qemu_x86` to emulate running on an x86-based board
   - `qemu_cortex_m3` to emulate running on an ARM Cortex M3-based board

2. Run one of these console commands from the build directory, `<app>/build`, to run the Zephyr binary in QEMU:
   - `west build -t run`
   - `ninja run`

3. Press Ctrl A, X to stop the application from running in QEMU.
   The application stops running and the terminal console prompt redisplays.
   Each time you execute the run command, your application is rebuilt and run again.

**Note:** If the (Linux only) *Zephyr SDK* is installed, the `run` target will use the SDK’s QEMU binary by default. To use another version of QEMU, *set the environment variable* `QEMU_BIN_PATH` to the path of the QEMU binary you want to use instead.

**Note:** You can choose a specific emulator by appending `_<emulator>` to your target name, for example `west build -t run_qemu` or `ninja run_qemu` for QEMU.

### 2.4.11 Custom Board, Devicetree and SOC Definitions

In cases where the board or platform you are developing for is not yet supported by Zephyr, you can add board, Devicetree and SOC definitions to your application without having to add them to the Zephyr tree.

The structure needed to support out-of-tree board and SOC development is similar to how boards and SOCs are maintained in the Zephyr tree. By using this structure, it will be much easier to upstream your platform related work into the Zephyr tree after your initial development is done.

Add the custom board to your application or a dedicated repository using the following structure:

```
boards/
soc/
CMakeLists.txt
prj.conf
README.rst
src/
```

where the `boards` directory hosts the board you are building for:

```
  boards
  ├── x86
  │     └── my_custom_board
  │         ├── doc
  │         │   └── img
  │         └── support
  └── src
```
and the soc directory hosts any SOC code. You can also have boards that are supported by a SOC that is available in the Zephyr tree.

**Boards**

Use the proper architecture folder name (e.g., x86, arm, etc.) under boards for my_custom_board. (See boards for a list of board architectures.)

Documentation (under doc/) and support files (under support/) are optional, but will be needed when submitting to Zephyr.

The contents of my_custom_board should follow the same guidelines for any Zephyr board, and provide the following files:

```plaintext
my_custom_board_defconfig
my_custom_board.dts
my_custom_board.yaml
board.cmake
board.h
CMakeLists.txt
doc/
Kconfig.board
Kconfig.defconfig
pinmux.c
support/
```

Once the board structure is in place, you can build your application targeting this board by specifying the location of your custom board information with the -DBOARD_ROOT parameter to the CMake build system:

Using west:

```plaintext
west build -b <board name> -- -DBOARD_ROOT=<path to boards>
```

Using CMake and ninja:

```plaintext
cmake -Bbuild -GNinja -DBOARD=<board name> -DBOARD_ROOT=<path to boards> .
ninja -Cbuild
```

This will use your custom board configuration and will generate the Zephyr binary into your application directory.

You can also define the BOARD_ROOT variable in the application CMakeLists.txt file. Make sure to do so before pulling in the Zephyr boilerplate with find_package(Zephyr ...).

**Note:** When specifying BOARD_ROOT in a CMakeLists.txt, then an absolute path must be provided, for example list(APPEND BOARD_ROOT ${CMAKE_CURRENT_SOURCE_DIR}/<extra-board-root>). When using -DBOARD_ROOT=<board-root> both absolute and relative paths can be used. Relative paths are treated relatively to the application directory.

**SOC Definitions**

Similar to board support, the structure is similar to how SOCs are maintained in the Zephyr tree, for example:

```plaintext
soc
│  └── arm
│      └── st stm32
```

(continues on next page)
The file `soc/Kconfig` will create the top-level SoC/CPU/Configuration Selection menu in Kconfig. Out of tree SoC definitions can be added to this menu using the `SOC_ROOT` CMake variable. This variable contains a semicolon-separated list of directories which contain SoC support files. Following the structure above, the following files can be added to load more SoCs into the menu.

The `Kconfig` files above may describe the SoC or load additional SoC Kconfig files. An example of loading `stm31l0` specific Kconfig files in this structure:

```
soc
  └── arm
      └── st_stm32
          └── Kconfig
              └── Kconfig.series
```

can be done with the following content in `st_stm32/Kconfig.soc`:

```
rsource "*/Kconfig.series"
```

Once the SOC structure is in place, you can build your application targeting this platform by specifying the location of your custom platform information with the `-DSOC_ROOT` parameter to the CMake build system:

Using west:

```
w west build -b <board name> -- -DSOC_ROOT=<path to soc> -DBOARD_ROOT=<path to boards>
```

Using CMake and ninja:

```
cmake -Bbuild -GNinja -DBOARD=<board name> -DSOC_ROOT=<path to soc> -DBOARD_ROOT=<path to boards> .
ninja -Cbuild
```

This will use your custom platform configurations and will generate the Zephyr binary into your application directory.

See **Build settings** for information on setting SOC_ROOT in a module's `zephyr/module.yml` file.

Or you can define the `SOC_ROOT` variable in the application `CMakeLists.txt` file. Make sure to do so **before** pulling in the Zephyr boilerplate with `find_package(Zephyr ...)`. **Note:** When specifying `SOC_ROOT` in a `CMakeLists.txt`, then an absolute path must be provided, for example `list(APPEND SOC_ROOT ${{CMAKE_CURRENT_SOURCE_DIR}}/extra-soc-root)`. When using `-DSOC_ROOT=<soc-root>` both absolute and relative paths can be used. Relative paths are treated relatively to the application directory.
Devicetree Definitions

Devicetree directory trees are found in APPLICATION_SOURCE_DIR, BOARD_DIR, and ZEPHYR_BASE, but additional trees, or DTS_ROOTs, can be added by creating this directory tree:

```
include/
dts/common/
dts/arm/
dts/
dts/bindings/
```

Where ‘arm’ is changed to the appropriate architecture. Each directory is optional. The binding directory contains bindings and the other directories contain files that can be included from DT sources.

Once the directory structure is in place, you can use it by specifying its location through the DTS_ROOT CMake Cache variable:

Using west:
```
west build -b <board name> -- -DDTS_ROOT=<path to dts root>
```

Using CMake and ninja:
```
cmake -Bbuild -GNinja -DBOARD=<board name> -DDTS_ROOT=<path to dts root>.
ninja -Cbuild
```

You can also define the variable in the application CMakeLists.txt file. Make sure to do so before pulling in the Zephyr boilerplate with find_package(Zephyr ...).

**Note:** When specifying DTS_ROOT in a CMakeLists.txt, then an absolute path must be provided, for example list(APPEND DTS_ROOT ${CMAKE_CURRENT_SOURCE_DIR}/<extra-dts-root>). When using -DDTS_ROOT=<dts-root> both absolute and relative paths can be used. Relative paths are treated relatively to the application directory.

Devicetree source are passed through the C preprocessor, so you can include files that can be located in a DTS_ROOT directory. By convention devicetree include files have a .dtsi extension.

You can also use the preprocessor to control the content of a devicetree file, by specifying directives through the DTS_EXTRA_CPPFLAGS CMake Cache variable:

Using west:
```
west build -b <board name> -- -DDTS_EXTRA_CPPFLAGS=-DTEST_ENABLE_FEATURE
```

Using CMake and ninja:
```
cmake -Bbuild -GNinja -DBOARD=<board name> -DDTS_EXTRA_CPPFLAGS=-DTEST_ENABLE_FEATURE.
ninja -Cbuild
```

### 2.5 Debugging

#### 2.5.1 Application Debugging

This section is a quick hands-on reference to start debugging your application with QEMU. Most content in this section is already covered in QEMU and GNU Debugger reference manuals.

In this quick reference, you'll find shortcuts, specific environmental variables, and parameters that can help you to quickly set up your debugging environment.
The simplest way to debug an application running in QEMU is using the GNU Debugger and setting a local GDB server in your development system through QEMU.

You will need an ELF (Executable and Linkable Format) binary image for debugging purposes. The build system generates the image in the build directory. By default, the kernel binary name is `zephyr.elf`. The name can be changed using `CONFIG_KERNEL_BIN_NAME`.

**GDB server**

We will use the standard 1234 TCP port to open a GDB (GNU Debugger) server instance. This port number can be changed for a port that best suits the development environment. There are multiple ways to do this. Each way starts a QEMU instance with the processor halted at startup and with a GDB server instance listening for a connection.

**Running QEMU directly** You can run QEMU to listen for a “gdb connection” before it starts executing any code to debug it.

```bash
qemu -s -S <image>
```

will setup Qemu to listen on port 1234 and wait for a GDB connection to it.

The options used above have the following meaning:

- `-S` Do not start CPU at startup; rather, you must type `c` in the monitor.
- `-s` Shorthand for `-gdb tcp::1234`: open a GDB server on TCP port 1234.

**Running QEMU via ninja** Run the following inside the build directory of an application:

```bash
ninja debugserver
```

QEMU will write the console output to the path specified in `${QEMU_PIPE}` via CMak, typically `qemu-fifo` within the build directory. You may monitor this file during the run with `tail -f qemu-fifo`.

**Running QEMU via west** Run the following from your project root:

```bash
west build -t debugserver_qemu
```

QEMU will write the console output to the terminal from which you invoked `west`.

**Configuring the gdbserver listening device** The Kconfig option `CONFIG_QEMU_GDBSERVER_LISTEN_DEV` controls the listening device, which can be a TCP port number or a path to a character device. GDB releases 9.0 and newer also support Unix domain sockets.

If the option is unset, then the QEMU invocation will lack a `-s` or a `-gdb` parameter. You can then use the `QEMU_EXTRA_FLAGS` shell environment variable to pass in your own listen device configuration.

**GDB client**

Connect to the server by running `gdb` and giving these commands:
Note: Substitute the correct `ZEPHYR_BASE` for your system.

You can use a local GDB configuration `.gdbinit` to initialize your GDB instance on every run. Your home directory is a typical location for `.gdbinit`, but you can configure GDB to load from other locations, including the directory from which you invoked `gdb`. This example file performs the same configuration as above:

```
target remote localhost:1234
dir ZEPHYR_BASE
```

Alternate interfaces  GDB provides a curses-based interface that runs in the terminal. Pass the `--tui` option when invoking `gdb` or give the `tui enable` command within `gdb`.

Note: The GDB version on your development system might not support the `--tui` option. Please make sure you use the GDB binary from the SDK which corresponds to the toolchain that has been used to build the binary.

Finally, the command below connects to the GDB server using the DDD (Data Display Debugger), a graphical frontend for GDB. The following command loads the symbol table from the ELF binary file, in this instance, `zephyr.elf`.

```
ddd --gdb --debugger "gdb zephyr.elf"
```

Both commands execute `gdb`. The command name might change depending on the toolchain you are using and your cross-development tools.

`ddd` may not be installed in your development system by default. Follow your system instructions to install it. For example, use `sudo apt-get install ddd` on an Ubuntu system.

Debugging

As configured above, when you connect the GDB client, the application will be stopped at system startup. You may set breakpoints, step through code, etc. as when running the application directly within `gdb`.

Note: `gdb` will not print the system console output as the application runs, unlike when you run a native application in GDB directly. If you just `continue` after connecting the client, the application will run, but nothing will appear to happen. Check the console output as described above.

### 2.5.2 Debug with Eclipse

Overview

CMake supports generating a project description file that can be imported into the Eclipse Integrated Development Environment (IDE) and used for graphical debugging.
The GNU MCU Eclipse plug-ins provide a mechanism to debug ARM projects in Eclipse with pyOCD, Segger J-Link, and OpenOCD debugging tools.

The following tutorial demonstrates how to debug a Zephyr application in Eclipse with pyOCD in Windows. It assumes you have already installed the GCC ARM Embedded toolchain and pyOCD.

Set Up the Eclipse Development Environment

1. Download and install Eclipse IDE for C/C++ Developers.
2. In Eclipse, install the GNU MCU Eclipse plug-ins by opening the menu Window->Eclipse Marketplace..., searching for GNU MCU Eclipse, and clicking Install on the matching result.
3. Configure the path to the pyOCD GDB server by opening the menu Window->Preferences, navigating to MCU, and setting the Global pyOCD Path.

Generate and Import an Eclipse Project

1. Set up a GNU Arm Embedded toolchain as described in GNU Arm Embedded.
2. Navigate to a folder outside of the Zephyr tree to build your application.

   # On Windows
   cd %userprofile%

   **Note:** If the build directory is a subdirectory of the source directory, as is usually done in Zephyr, CMake will warn:
   “The build directory is a subdirectory of the source directory.
   This is not supported well by Eclipse. It is strongly recommended to use a build directory which is a sibling of the source directory.”

3. Configure your application with CMake and build it with ninja. Note the different CMake generator specified by the `-G"Eclipse CDT4 - Ninja"` argument. This will generate an Eclipse project description file, .project, in addition to the usual ninja build files.

   Using west:
   ```
   west build -b frdm_k64f %ZEPHYR_BASE%\examples\synchronization -- -G"Eclipse CDT4 - Ninja"
   ```

   Using CMake and ninja:
   ```
   cmake -Bbuild -GNinja -DBOARD=frdm_k64f -G"Eclipse CDT4 - Ninja" %ZEPHYR_BASE%\examples\synchronization
   ninja -Cbuild
   ```

4. In Eclipse, import your generated project by opening the menu File->Import... and selecting the option Existing Projects into Workspace. Browse to your application build directory in the choice, Select root directory:. Check the box for your project in the list of projects found and click the Finish button.

Create a Debugger Configuration

1. Open the menu Run->Debug Configurations....
2. Select GDB PyOCD Debugging, click the New button, and configure the following options:
• In the Main tab:
  – Project: my_zephyr_app@build
  – C/C++ Application: zephyr/zephyr.elf

• In the Debugger tab:
  – pyOCD Setup
    * Executable path: $pyocd_path$pyocd_executable
    * Uncheck “Allocate console for semihosting”
  – Board Setup
    * Bus speed: 8000000 Hz
    * Uncheck “Enable semihosting”
  – GDB Client Setup
    * Executable path example (use your GNUARMEMB_TOOLCHAIN_PATH): C:\gcc-arm-none-eabi-6_2017-q2-update\bin\arm-none-eabi-gdb.exe

• In the SVD Path tab:
  – File path: <workspace top>\modules\hal\nxp\mcux\devices\MK64F12\MK64F12.xml

**Note:** This is optional. It provides the SoC’s memory-mapped register addresses and bitfields to the debugger.

3. Click the Debug button to start debugging.

**RTOS Awareness**

Support for Zephyr RTOS awareness is implemented in pyOCD v0.11.0 and later. It is compatible with GDB PyOCD Debugging in Eclipse, but you must enable CONFIG_DEBUG_THREAD_INFO=y in your application.

### 2.5.3 Debugging I2C communication

There is a possibility to log all or some of the I2C transactions done by the application. This feature is enabled by the Kconfig option CONFIG_I2C_DUMP_MESSAGES, but it uses the LOG_DBG function to print the contents so the CONFIG_I2C_LOG_LEVEL_DBG option must also be enabled.

The sample output of the dump looks like this:

```
D: I2C msg: io_i2c_ctrl7_port0, addr=50
D:  W  len=01: 00
D:  R Sr P len=08:
D: contents: 43 42 41 00 00 00 00 00 |CBA.....
```

The first line indicates the I2C controller and the target address of the transaction. In above example, the I2C controller is named io_i2c_ctrl7_port0 and the target device address is 0x50

**Note:** the address, length and contents values are in hexadecimal, but lack the 0x prefix
Next lines contain messages, both sent and received. The contents of write messages is always shown, while the content of read messages is controlled by a parameter to the function `i2c_dump_msgs_rw`. This function is available for use by user, but is also called internally by `i2c_transfer` API function with read content dump enabled. Before the length parameter, the header of the message is printed using abbreviations:

- W - write message
- R - read message
- Sr - restart bit
- P - stop bit

The above example shows one write message with byte 0x00 representing the address of register to read from the I2C target. After that the log shows the length of received message and following that, the bytes read from the target 43 42 41 00 00 00 00 00. The content dump consist of both the hex and ASCII representation.

Filtering the I2C communication dump

By default, all I2C communication is logged between all I2C controllers and I2C targets. It may litter the log with unrelated devices and make it difficult to effectively debug the communication with a device of interest.

Enable the Kconfig option `CONFIG_I2C_DUMP_MESSAGES_ALLOWLIST` to create an allowlist of I2C targets to log. The allowlist of devices is configured using the devicetree, for example:

```c
/ {
    i2c {
        display0: some-display@a {
            ...
        };
        sensor3: some-sensor@b {
            ...
        };
    };
    i2c-dump-allowlist {
        compatible = "zephyr,i2c-dump-allowlist";
        devices = < &display0 >, < &sensor3 >;
    };
}
```

The filters nodes are identified by the compatible string with `zephyr,i2c-dump-allowlist` value. The devices are selected using the devices property with phandles to the devices on the I2C bus.

In the above example, the communication with device `display0` and `sensor3` will be displayed in the log.

2.6 API Status and Guidelines

2.6.1 API Overview

The table lists Zephyr's APIs and information about them, including their current stability level. More details about API changes between major releases are available in the zephyr_release_notes.
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2.6. API Status and Guidelines
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#### 2.6.2 API Lifecycle

Developers using Zephyr's APIs need to know how long they can trust that a given API will not change in future releases. At the same time, developers maintaining and extending Zephyr's APIs need to be able to introduce new APIs that aren't yet fully proven, and to potentially retire old APIs when they're no longer optimal or supported by the underlying platforms.

An up-to-date table of all APIs and their maturity level can be found in the [API Overview](#) page.

**Experimental**

Experimental APIs denote that a feature was introduced recently, and may change or be removed in future versions. Try it out and provide feedback to the community via the [Developer mailing](#).
The following requirements apply to all new APIs:

- Documentation of the API (usage) explaining its design and assumptions, how it is to be used, current implementation limitations, and future potential, if appropriate.
- The API introduction should be accompanied by at least one implementation of said API (in the case of peripheral APIs, this corresponds to one driver)
- At least one sample using the new API (may only build on one single board)

**Peripheral APIs (Hardware Related)** When introducing an API (public header file with documentation) for a new peripheral or driver subsystem, review of the API is enforced and is driven by the Architecture working group consisting of representatives from different vendors.

The API shall be promoted to unstable when it has at least two implementations on different hardware platforms.

**Unstable**

The API is in the process of settling, but has not yet had sufficient real-world testing to be considered stable. The API is considered generic in nature and can be used on different hardware platforms.

**Note:** Changes will not be announced.

**Peripheral APIs (Hardware Related)** The API shall be promoted from experimental to unstable when it has at least two implementations on different hardware platforms.

**Hardware Agnostic APIs** For hardware agnostic APIs, multiple applications using it are required to promote an API from experimental to unstable.
Stable

The API has proven satisfactory, but cleanup in the underlying code may cause minor changes. Backwards-compatibility will be maintained if reasonable.

An API can be declared stable after fulfilling the following requirements:

- Test cases for the new API with 100% coverage
- Complete documentation in code. All public interfaces shall be documented and available in online documentation.
- The API has been in-use and was available in at least 2 development releases
- Stable APIs can get backward compatible updates, bug fixes and security fixes at any time.

In order to declare an API stable, the following steps need to be followed:

1. A Pull Request must be opened that changes the corresponding entry in the *API Overview* table
2. An email must be sent to the *devel* mailing list announcing the API upgrade request
3. The Pull Request must be submitted for discussion in the next *Zephyr Architecture meeting* where, barring any objections, the Pull Request will be merged

Introducing breaking API changes A stable API, as described above, strives to remain backwards-compatible through its life-cycle. There are however cases where fulfilling this objective prevents technical progress, or is simply unfeasible without unreasonable burden on the maintenance of the API and its implementation(s).

A breaking API change is defined as one that forces users to modify their existing code in order to maintain the current behavior of their application. The need for recompilation of applications (without changing the application itself) is not considered a breaking API change.

In order to restrict and control the introduction of a change that breaks the promise of backwards compatibility, the following steps must be followed whenever such a change is considered necessary in order to accept it in the project:

1. An *RFC issue* must be opened on GitHub with the following content:

<table>
<thead>
<tr>
<th>Title:</th>
<th>RFC: Breaking API Change: &lt;subsystem&gt;</th>
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<tr>
<td>Contents:</td>
<td>Problem Description:</td>
</tr>
<tr>
<td></td>
<td>- Background information on why the change is required</td>
</tr>
<tr>
<td></td>
<td>- Proposed Change (detailed):</td>
</tr>
<tr>
<td></td>
<td>- Brief description of the API change</td>
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<td></td>
<td>- Impact to users of the API, including the steps required to adapt out-of-tree users of the API to the change</td>
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   Instead of a written description of the changes, the RFC issue may link to a Pull Request containing those changes in code form.

2. The RFC issue must be labeled with the GitHub *Breaking API Change* label
3. The RFC issue must be submitted for discussion in the next *Zephyr Architecture meeting*
4. An email must be sent to the *devel* mailing list with a subject identical to the RFC issue title and that links to the RFC issue
The RFC will then receive feedback through issue comments and will also be discussed in the Zephyr Architecture meeting, where the stakeholders and the community at large will have a chance to discuss it in detail.

Finally, and if not done as part of the first step, a Pull Request must be opened on GitHub. It is left to the person proposing the change to decide whether to introduce both the RFC and the Pull Request at the same time or to wait until the RFC has gathered consensus enough so that the implementation can proceed with confidence that it will be accepted. The Pull Request must include the following:

- A title that matches the RFC issue
- A link to the RFC issue
- The actual changes to the API
  - Changes to the API header file
  - Changes to the API implementation(s)
  - Changes to the relevant API documentation
  - Changes to Device Tree source and bindings
- The changes required to adapt in-tree users of the API to the change. Depending on the scope of this task this might require additional help from the corresponding maintainers
- An entry in the “API Changes” section of the release notes for the next upcoming release
- The labels API, Breaking API Change and Release Notes, as well as any others that are applicable

Once the steps above have been completed, the outcome of the proposal will depend on the approval of the actual Pull Request by the maintainer of the corresponding subsystem. As with any other Pull Request, the author can request for it to be discussed and ultimately even voted on in the Zephyr TSC meeting.

If the Pull Request is merged then an email must be sent to the devel and user mailing lists informing them of the change.

**Note:** Breaking API changes will be listed and described in the migration guide.

### Deprecated

**Note:** Unstable APIs can be removed without deprecation at any time. Deprecation and removal of APIs will be announced in the “API Changes” section of the release notes.

The following are the requirements for deprecating an existing API:

- **Deprecation Time (stable APIs): 2 Releases** The API needs to be marked as deprecated in at least two full releases. For example, if an API was first deprecated in release 1.14, it will be ready to be removed in 1.16 at the earliest. There may be special circumstances, determined by the Architecture working group, where an API is deprecated sooner.

- **What is required when deprecating:**
  - Mark as deprecated. This can be done by using the compiler itself (__deprecated for function declarations and __DEPRECATED_MACRO for macro definitions), or by introducing a Kconfig option (typically one that contains the DEPRECATED word in it) that, when enabled, reverts the APIs back to their previous form
  - Document the deprecation
– Include the deprecation in the “API Changes” of the release notes for the next upcoming release
– Code using the deprecated API needs to be modified to remove usage of said API
– The change needs to be atomic and bisectable
– Create a GitHub issue to track the removal of the deprecated API, and add it to the roadmap targeting the appropriate release (in the example above, 1.16).

During the deprecation waiting period, the API will be in the deprecated state. The Zephyr maintainers will track usage of deprecated APIs on docs.zephyrproject.org and support developers migrating their code. Zephyr will continue to provide warnings:

• API documentation will inform users that the API is deprecated.
• Attempts to use a deprecated API at build time will log a warning to the console.

Retired

In this phase, the API is removed.

The target removal date is 2 releases after deprecation is announced. The Zephyr maintainers will decide when to actually remove the API: this will depend on how many developers have successfully migrated from the deprecated API, and on how urgently the API needs to be removed.

If it's OK to remove the API, it will be removed. The maintainers will remove the corresponding documentation, and communicate the removal in the usual ways: the release notes, mailing lists, Github issues and pull-requests.

If it's not OK to remove the API, the maintainers will continue to support migration and update the roadmap with the aim to remove the API in the next release.

2.6.3 API Design Guidelines

Zephyr development and evolution is a group effort, and to simplify maintenance and enhancements there are some general policies that should be followed when developing a new capability or interface.

Using Callbacks

Many APIs involve passing a callback as a parameter or as a member of a configuration structure. The following policies should be followed when specifying the signature of a callback:

• The first parameter should be a pointer to the object most closely associated with the callback. In the case of device drivers this would be `const struct device *dev`. For library functions it may be a pointer to another object that was referenced when the callback was provided.

• The next parameter(s) should be additional information specific to the callback invocation, such as a channel identifier, new status value, and/or a message pointer followed by the message length.

• The final parameter should be a `void *user_data` pointer carrying context that allows a shared callback function to locate additional material necessary to process the callback.

An exception to providing `user_data` as the last parameter may be allowed when the callback itself was provided through a structure that will be embedded in another structure. An example of such a case is `gpio_callback`, normally defined within a data structure specific to the code that also defines the callback function. In those cases further context can accessed by the callback indirectly by `CONTAINER_OF`. 
Examples

- The requirements of `k_timer_expiry_t` invoked when a system timer alarm fires are satisfied by:

  ```c
  void handle_timeout(struct k_timer *timer) {
      ...  
  }
  ```

  The assumption here, as with `gpio_callback`, is that the timer is embedded in a structure reachable from `CONTAINER_OF` that can provide additional context to the callback.

- The requirements of `counter_alarm_callback_t` invoked when a counter device alarm fires are satisfied by:

  ```c
  void handle_alarm(const struct device *dev,
                   uint8_t chan_id,
                   uint32_t ticks,
                   void *user_data)
  {
      ...  
  }
  ```

  This provides more complete useful information, including which counter channel timed-out and the counter value at which the timeout occurred, as well as user context which may or may not be the `counter_alarm_cfg` used to register the callback, depending on user needs.

Conditional Data and APIs

APIs and libraries may provide features that are expensive in RAM or code size but are optional in the sense that some applications can be implemented without them. Examples of such feature include capturing a timestamp or providing an alternative interface. The developer in coordination with the community must determine whether enabling the features is to be controllable through a Kconfig option.

In the case where a feature is determined to be optional the following practices should be followed.

- Any data that is accessed only when the feature is enabled should be conditionally included via `#ifdef CONFIG_MYFEATURE` in the structure or union declaration. This reduces memory use for applications that don’t need the capability.

- Function declarations that are available only when the option is enabled should be provided unconditionally. Add a note in the description that the function is available only when the specified feature is enabled, referencing the required Kconfig symbol by name. In the cases where the function is used but not enabled the definition of the function shall be excluded from compilation, so references to the unsupported API will result in a link-time error.

- Where code specific to the feature is isolated in a source file that has no other content that file should be conditionally included in `CMakeLists.txt`:

  ```
  zephyr_sources_ifdef(CONFIG_MYFEATURE foo_funcs.c)
  ```

- Where code specific to the feature is part of a source file that has other content the feature-specific code should be conditionally processed using `#ifdef CONFIG_MYFEATURE`.

The Kconfig flag used to enable the feature should be added to the `PREDEFINED` variable in `doc/zephyr.doxyfile.in` to ensure the conditional API and functions appear in generated documentation.
Return Codes

Implementations of an API, for example an API for accessing a peripheral might implement only a subset of the functions that is required for minimal operation. A distinction is needed between APIs that are not supported and those that are not implemented or optional:

- APIs that are supported but not implemented shall return `-ENOSYS`.
- Optional APIs that are not supported by the hardware should be implemented and the return code in this case shall be `-ENOTSUP`.
- When an API is implemented, but the particular combination of options requested in the call cannot be satisfied by the implementation the call shall return `-ENOTSUP`. (For example, a request for a level-triggered GPIO interrupt on hardware that supports only edge-triggered interrupts)

2.6.4 API Terminology

The following terms may be used as shorthand API tags to indicate the allowed calling context (thread, ISR, pre-kernel), the effect of a call on the current thread state, and other behavioral characteristics.

- **reschedule**
  - if executing the function reaches a reschedule point

- **sleep**
  - if executing the function can cause the invoking thread to sleep

- **no-wait**
  - if a parameter to the function can prevent the invoking thread from trying to sleep

- **isr-ok**
  - if the function can be safely called and will have its specified effect whether invoked from interrupt or thread context

- **pre-kernel-ok**
  - if the function can be safely called before the kernel has been fully initialized and will have its specified effect when invoked from that context.

- **async**
  - if the function may return before the operation it initializes is complete (i.e. function return and operation completion are asynchronous)

- **supervisor**
  - if the calling thread must have supervisor privileges to execute the function

Details on the behavioral impact of each attribute are in the following sections.

reschedule

The reschedule attribute is used on a function that can reach a *reschedule point* within its execution.

Details  The significance of this attribute is that when a rescheduling function is invoked by a thread it is possible for that thread to be suspended as a consequence of a higher-priority thread being made ready. Whether the suspension actually occurs depends on the operation associated with the reschedule point and the relative priorities of the invoking thread and the head of the ready queue.

Note that in the case of timeslicing, or reschedule points executed from interrupts, any thread may be suspended in any function.
Functions that are not **reschedule** may be invoked from either thread or interrupt context.

Functions that are **reschedule** may be invoked from thread context.

Functions that are **reschedule** but not **sleep** may be invoked from interrupt context.

**sleep**

The sleep attribute is used on a function that can cause the invoking thread to **sleep**.

**Explanation**  This attribute is of relevance specifically when considering applications that use only non-preemptible threads, because the kernel will not replace a running cooperative-only thread at a reschedule point unless that thread has explicitly invoked an operation that caused it to sleep.

This attribute does not imply the function will sleep unconditionally, but that the operation may require an invoking thread that would have to suspend, wait, or invoke *k_yield()* before it can complete its operation. This behavior may be mediated by **no-wait**.

Functions that are **sleep** are implicitly **reschedule**.

Functions that are **sleep** may be invoked from thread context.

Functions that are **sleep** may be invoked from interrupt and pre-kernel contexts if and only if invoked in **no-wait** mode.

**no-wait**

The no-wait attribute is used on a function that is also **sleep** to indicate that a parameter to the function can force an execution path that will not cause the invoking thread to sleep.

**Explanation**  The paradigmatic case of a no-wait function is a function that takes a timeout, to which *K_NO_WAIT* can be passed. The semantics of this special timeout value are to execute the function’s operation as long as it can be completed immediately, and to return an error code rather than sleep if it cannot.

It is use of the no-wait feature that allows functions like *k_sem_take()* to be invoked from ISRs, since it is not permitted to sleep in interrupt context.

A function with a no-wait path does not imply that taking that path guarantees the function is synchronous.

Functions with this attribute may be invoked from interrupt and pre-kernel contexts only when the parameter selects the no-wait path.

**isr-ok**

The isr-ok attribute is used on a function to indicate that it works whether it is being invoked from interrupt or thread context.

**Explanation**  Any function that is not **sleep** is inherently **isr-ok**. Functions that are **sleep** are **isr-ok** if the implementation ensures that the documented behavior is implemented even if called from an interrupt context. This may be achieved by having the implementation detect the calling context and transfer the operation that would sleep to a thread, or by documenting that when invoked from a non-thread context the function will return a specific error (generally -EWOULDBLOCK).
Note that a function that is **no-wait** is safe to call from interrupt context only when the no-wait path is selected. **isr-ok** functions need not provide a no-wait path.

**pre-kernel-ok**

The pre-kernel-ok attribute is used on a function to indicate that it works as documented even when invoked before the kernel main thread has been started.

**Explanation**  This attribute is similar to **isr-ok** in function, but is intended for use by any API that is expected to be called in `DEVICEDEFINE()` or `SYS_INIT()` calls that may be invoked with `PRE_KERNEL_1` or `PRE_KERNEL_2` initialization levels. Generally a function that is **pre-kernel-ok** checks `k_is_pre_kernel()` when determining whether it can fulfill its required behavior. In many cases it would also check `k_is_in_isr()` so it can be **isr-ok** as well.

**async**

A function is **async** (i.e. asynchronous) if it may return before the operation it initiates has completed. An asynchronous function will generally provide a mechanism by which operation completion is reported, e.g. a callback or event. A function that is not asynchronous is synchronous, i.e. the operation will always be complete when the function returns. As most functions are synchronous this behavior does not have a distinct attribute to identify it.

**Explanation**  Be aware that **async** is orthogonal to context-switching. Some APIs may provide completion information through a callback, but may suspend while waiting for the resource necessary to initiate the operation; an example is `spi_transceive_async()`.

If a function is both **no-wait** and **async** then selecting the no-wait path only guarantees that the function will not sleep. It does not affect whether the operation will be completed before the function returns.

**supervisor**

The supervisor attribute is relevant only in user-mode applications, and indicates that the function cannot be invoked from user mode.

### 2.7 Language Support

#### 2.7.1 C Language Support

C is a general-purpose low-level programming language that is widely used for writing code for embedded systems.

Zephyr is primarily written in C and natively supports applications written in the C language. All Zephyr API functions and macros are implemented in C and available as part of the C header files under the `include` directory, so writing Zephyr applications in C gives the developers access to the most features.
The `main()` function must have the return type of `int` as Zephyr applications run in a “hosted” environment as defined by the C standard. Applications must return zero (0) from main. All non-zero return values are reserved.

**Language Standards**

Zephyr does not target a specific version of the C standards; however, the Zephyr codebase makes extensive use of the features newly introduced in the 1999 release of the ISO C standard (ISO/IEC 9899:1999, hereinafter referred to as C99) such as those listed below, effectively requiring the use of a compiler toolchain that supports the C99 standard and above:

- inline functions
- standard boolean types (bool in `<stdbool.h>`)  
- fixed-width integer types ([u]intN_t in `<stdint.h>`)  
- designated initializers
- variadic macros
- restrict qualification

Some Zephyr components make use of the features newly introduced in the 2011 release of the ISO C standard (ISO/IEC 9899:2011, hereinafter referred to as C11) such as the type-generic expressions using the `_Generic` keyword. For example, the `cbprintf()` component, used as the default formatted output processor for Zephyr, makes use of the C11 type-generic expressions, and this effectively requires most Zephyr applications to be compiled using a compiler toolchain that supports the C11 standard and above.

In summary, it is recommended to use a compiler toolchain that supports at least the C11 standard for developing with Zephyr. It is, however, important to note that some optional Zephyr components and external modules may make use of the C language features that have been introduced in more recent versions of the standards, in which case it will be necessary to use a more up-to-date compiler toolchain that supports such standards.

**Standard Library**

The **C Standard Library** is an integral part of any C program, and Zephyr provides the support for a number of different C libraries for the applications to choose from, depending on the compiler toolchain being used to build the application.

**Common C library code**  Zephyr provides some C library functions that are designed to be used in conjunction with multiple C libraries. These either provide functions not available in multiple C libraries or are designed to replace functionality in the C library with code better suited for use in the Zephyr environment

**Time function**  This provides an implementation of the standard C function, `time()`, relying on the Zephyr function, `clock_gettime()`. This function can be enabled by selecting `COMMON_LIBC_TIME`.

**Dynamic Memory Management**  The common dynamic memory management implementation can be enabled by selecting the `CONFIG_COMMON_LIBC_MALLOC` in the application configuration file.

The common C library internally uses the **kernel memory heap API** to manage the memory heap used by the standard dynamic memory management interface functions such as `malloc()` and `free()`.
The internal memory heap is normally located in the .bss section. When userspace is enabled, however, it is placed in a dedicated memory partition called `z_malloc_partition`, which can be accessed from the user mode threads. The size of the internal memory heap is specified by the `CONFIG_COMMON_LIBC_MALLOC_ARENA_SIZE`.

The default heap size for applications using the common C library is zero (no heap). For other C library users, if there is an MMU present, then the default heap is 16kB. Otherwise, the heap uses all available memory.

There are also separate controls to select `calloc()` (`COMMON_LIBC_CALLOC`) and `reallocarray()` (`COMMON_LIBC_REALLOCARRAY`). Both of these are enabled by default as that doesn't impact memory usage in applications not using them.

The standard dynamic memory management interface functions implemented by the common C library are thread safe and may be simultaneously called by multiple threads. These functions are implemented in `lib/libc/common/source/stdlib/malloc.c`.

**Minimal libc** The most basic C library, named “minimal libc”, is part of the Zephyr codebase and provides the minimal subset of the standard C library required to meet the needs of Zephyr and its subsystems, primarily in the areas of string manipulation and display.

It is very low footprint and is suitable for projects that do not rely on less frequently used portions of the ISO C standard library. It can also be used with a number of different toolchains.

The minimal libc implementation can be found in `lib/libc/minimal` in the main Zephyr tree.

**Functions** The minimal libc implements the minimal subset of the ISO/IEC 9899:2011 standard C library functions required to meet the needs of the Zephyr kernel, as defined by the Coding Guidelines Rule A.4.

**Formatted Output** The minimal libc does not implement its own formatted output processor; instead, it maps the C standard formatted output functions such as `printf` and `sprintf` to the `cbprintf()` function, which is Zephyr's own C99-compatible formatted output implementation.

For more details, refer to the Formatted Output OS service documentation.

**Dynamic Memory Management** The minimal libc uses the malloc api family implementation provided by the common C library, which itself is built upon the kernel memory heap API.

**Error numbers** Error numbers are used throughout Zephyr APIs to signal error conditions as return values from functions. They are typically returned as the negative value of the integer literals defined in this section, and are defined in the `errno.h` header file.

A subset of the error numbers defined in the POSIX `errno.h` specification and other de-facto standard sources have been added to the minimal libc.

A conscious effort is made in Zephyr to keep the values of the minimal libc error numbers consistent with the different implementations of the C standard libraries supported by Zephyr. The minimal libc `errno.h` is checked against that of the Newlib to ensure that the error numbers are kept aligned.

Below is a list of the error number definitions. For the actual numeric values please refer to `errno.h`.

**group system_errno**

System error numbers Error codes returned by functions.

Includes a list of those defined by IEEE Std 1003.1-2017.
Defines

errno

EPERM
Not owner.

ENOENT
No such file or directory.

ESRCH
No such context.

EINVAL
Interrupted system call.

EIO
I/O error.

ENXIO
No such device or address.

E2BIG
Arg list too long.

ENOEXEC
Exec format error.

EBADF
Bad file number.

ECHILD
No children.

EAGAIN
No more contexts.

ENOMEM
Not enough core.

EACCES
Permission denied.

EFAULT
Bad address.

ENOTBLK
Block device required.
EBUSY
   Mount device busy.

EEXIST
   File exists.

EXDEV
   Cross-device link.

ENODEV
   No such device.

ENOTDIR
   Not a directory.

EISDIR
   Is a directory.

EINVAL
   Invalid argument.

ENFILE
   File table overflow.

EMFILE
   Too many open files.

ENOTTY
   Not a typewriter.

ETXTBSY
   Text file busy.

EFBIG
   File too large.

ENOSPC
   No space left on device.

ESPIPE
   Illegal seek.

EROFS
   Read-only file system.

EMLINK
   Too many links.
EPIPE
Broken pipe.

EDOM
Argument too large.

ERANGE
Result too large.

ENOMSG
Unexpected message type.

EDEADLK
Resource deadlock avoided.

ENOLCK
No locks available.

ENOSTR
STREAMS device required.

ENODATA
Missing expected message data.

ETIME
STREAMS timeout occurred.

ENOSR
Insufficient memory.

EPROTO
Generic STREAMS error.

EBADMSG
Invalid STREAMS message.

ENOSYS
Function not implemented.

ENOTEMPTY
Directory not empty.

ENAMETOOLONG
File name too long.

ELOOP
Too many levels of symbolic links.
EOPNOTSUPP
   Operation not supported on socket.

EPFNOSUPPORT
   Protocol family not supported.

ECONNRESET
   Connection reset by peer.

ENOBUFFS
   No buffer space available.

EAFNOSUPPORT
   Addr family not supported.

EPROTOTYPE
   Protocol wrong type for socket.

ENOTSOCK
   Socket operation on non-socket.

ENOPROTOOPT
   Protocol not available.

ESHUTDOWN
   Can’t send after socket shutdown.

ECONNREFUSED
   Connection refused.

EADDRINUSE
   Address already in use.

ECONNABORTED
   Software caused connection abort.

ENETUNREACH
   Network is unreachable.

ENETDOWN
   Network is down.

ETIMEDOUT
   Connection timed out.

EHOSTDOWN
   Host is down.
EHOSTUNREACH
   No route to host.

EINVAL
   Operation now in progress.

EFAULT
   Operation already in progress.

EPFNOSUPPORT
   Destination address required.

EMSGSIZE
   Message size.

EPFNOSUPPORT
   Protocol not supported.

ESOCKTNOSUPPORT
   Socket type not supported.

EADDRNOTAVAIL
   Can't assign requested address.

ENETRESET
   Network dropped connection on reset.

EISCONN
   Socket is already connected.

ENOTCONN
   Socket is not connected.

ETOOMANYREFS
   Too many references: can't splice.

ENOTSUP
   Unsupported value.

EILSEQ
   Illegal byte sequence.

EOVERFLOW
   Value overflow.

ECANCELED
   Operation canceled.

EWOULDBLOCK
   Operation would block.
**Newlib**  
Newlib is a complete C library implementation written for the embedded systems. It is a separate open source project and is not included in source code form with Zephyr. Instead, the Zephyr SDK includes a precompiled library for each supported architecture (libc.a and libm.a).

**Note:** Other 3rd-party toolchains, such as GNU Arm Embedded, also bundle the Newlib as a precompiled library.

Zephyr implements the “API hook” functions that are invoked by the C standard library functions in the Newlib. These hook functions are implemented in lib/libc/newlib/libc-hooks.c and translate the library internal system calls to the equivalent Zephyr API calls.

**Types of Newlib**  
The Newlib included in the Zephyr SDK comes in two versions: ‘full’ and ‘nano’ variants.

**Full Newlib**  
The Newlib full variant (libc.a and libm.a) is the most capable variant of the Newlib available in the Zephyr SDK, and supports almost all standard C library features. It is optimized for performance (prefers performance over code size) and its footprint is significantly larger than the nano variant.

This variant can be enabled by selecting the CONFIG_NEWLIB_LIBC and de-selecting the CONFIG_NEWLIB_LIBC_NANO in the application configuration file.

**Nano Newlib**  
The Newlib nano variant (libc_nano.a and libm_nano.a) is the size-optimized version of the Newlib, and supports all features that the full variant supports except the new format specifiers introduced in C99, such as the char, long long type format specifiers (i.e. %hhX and %llX).

This variant can be enabled by selecting the CONFIG_NEWLIB_LIBC and CONFIG_NEWLIB_LIBC_NANO in the application configuration file.

Note that the Newlib nano variant is not available for all architectures. The availability of the nano variant is specified by the CONFIG_HAS_NEWLIB_LIBC_NANO.

**Formatted Output**  
Newlib supports all standard C formatted input and output functions, including printf, fprintf, sprintf and sscanf.

The Newlib formatted input and output function implementation supports all format specifiers defined by the C standard with the following exceptions:

- Floating point format specifiers (e.g. %f) require CONFIG_NEWLIB_LIBC_FLOAT_PRINTF and CONFIG_NEWLIB_LIBC_FLOAT_SCANF to be enabled.
- C99 format specifiers are not supported in the Newlib nano variant (i.e. %hhX for char, %llX for long long, %jX for intmax_t, %zX for size_t, %tX for ptrdiff_t).

**Dynamic Memory Management**  
Newlib implements an internal heap allocator to manage the memory blocks used by the standard dynamic memory management interface functions (for example, malloc() and free()).

The internal heap allocator implemented by the Newlib may vary across the different types of the Newlib used. For example, the heap allocator implemented in the Full Newlib (libc.a and libm.a) of the Zephyr SDK requests larger memory chunks to the operating system and has a significantly higher minimum memory requirement compared to that of the Nano Newlib (libc_nano.a and libm_nano.a).
The only interface between the Newlib dynamic memory management functions and the Zephyr-side libc hooks is the \texttt{sbrk()} function, which is used by the Newlib to manage the size of the memory pool reserved for its internal heap allocator.

The \texttt{_sbrk()} hook function, implemented in \texttt{libc-hooks.c}, handles the memory pool size change requests from the Newlib and ensures that the Newlib internal heap allocator memory pool size does not exceed the amount of available memory space by returning an error when the system is out of memory.

When userspace is enabled, the Newlib internal heap allocator memory pool is placed in a dedicated memory partition called \texttt{z_malloc_partition}, which can be accessed from the user mode threads.

The amount of memory space available for the Newlib heap depends on the system configurations:

- When MMU is enabled (\texttt{CONFIG_MMU} is selected), the amount of memory space reserved for the Newlib heap is set by the size of the free memory space returned by the \texttt{k_mem_free_get()} function or the \texttt{CONFIG_NEWLIB_LIBC_MAX_MAPPED_REGION_SIZE}, whichever is the smallest.

- When MPU is enabled and the MPU requires power-of-two partition size and address alignment (\texttt{CONFIG_NEWLIB_LIBC_ALIGNED_HEAP_SIZE} is set to a non-zero value), the amount of memory space reserved for the Newlib heap is set by the \texttt{CONFIG_NEWLIB_LIBC_ALIGNED_HEAP_SIZE}.

- Otherwise, the amount of memory space reserved for the Newlib heap is equal to the amount of free (unallocated) memory in the SRAM region.

The standard dynamic memory management interface functions implemented by the Newlib are thread safe and may be simultaneously called by multiple threads.

### Picolibc

Picolibc is a complete C library implementation written for the embedded systems, targeting \texttt{C17 (ISO/IEC 9899:2018)} and \texttt{POSIX 2018 (IEEE Std 1003.1-2017)} standards. Picolibc is an external open source project which is provided for Zephyr as a module, and included as part of the Zephyr SDK in precompiled form for each supported architecture (\texttt{libc.a}).

**Note:** Picolibc is also available for other 3rd-party toolchains, such as GNU Arm Embedded.

Zephyr implements the “API hook” functions that are invoked by the C standard library functions in the Picolibc. These hook functions are implemented in \texttt{lib/libc/picolibc/libc-hooks.c} and translate the library internal system calls to the equivalent Zephyr API calls.

**Picolibc Module**   When built as a Zephyr module, there are several configuration knobs available to adjust the feature set in the library, balancing what the library supports versus the code size of the resulting functions. Because the standard C++ library must be compiled for the target C library, the Picolibc module cannot be used with applications which use the standard C++ library. Building the Picolibc module will increase the time it takes to compile the application.

The Picolibc module can be enabled by selecting \texttt{CONFIG_PICOLIBC_USE_MODULE} in the application configuration file.

When updating the Picolibc module to a newer version, the toolchain-bundled Picolibc in the Zephyr SDK must also be updated to the same version.

**Toolchain Picolibc**   Starting with version 0.16, the Zephyr SDK includes precompiled versions of Picolibc for every target architecture, along with precompiled versions of libstdc++.
The toolchain version of Picolibc can be enabled by de-selecting `CONFIG_PICOLIBC_USE_MODULE` in the application configuration file.

For every release of Zephyr, the toolchain-bundled Picolibc and the `Picolibc module` are guaranteed to be in sync when using the recommended version of Zephyr SDK.

**Building Without Toolchain bundled Picolibc** For toolchain where there is no bundled Picolibc, it is still possible to use Picolibc by building it from source. Note that any restrictions mentioned in `Picolibc Module` still apply.

To build without toolchain bundled Picolibc, the toolchain must enable `CONFIG_PICOLIBC_SUPPORTED`. For example, this needs to be added to the toolchain Kconfig file:

```
config TOOLCHAIN_<name>_PICOLIBC_SUPPORTED
def_bool y
  select PICOLIBC_SUPPORTED
```

By enabling `CONFIG_PICOLIBC_SUPPORTED`, the build system would automatically build Picolibc from source with its module when there is no toolchain bundled Picolibc.

**Formated Output** Picolibc supports all standard C formatted input and output functions, including `printf()`, `fprintf()`, `sprintf()` and `sscanf()`.

Picolibc formatted input and output function implementation supports all format specifiers defined by the C17 and POSIX 2018 standards with the following exceptions:

- Floating point format specifiers (e.g. `%f`) require `CONFIG_PICOLIBC_IO_FLOAT`.
- Long long format specifiers (e.g. `%lld`) require `CONFIG_PICOLIBC_IO_LONG_LONG`. This option is automatically enabled with `CONFIG_PICOLIBC_IO_FLOAT`.

**Printk, cbprintf and friends** When using Picolibc, Zephyr formatted output functions are implemented in terms of stdio calls. This includes:

- `printk`, `snprintf` and `vsnprintf`
- `cbprintf` and `cbvprintf`
- `fprintfcb`, `vfprintfcb`, `printfcb`, `vprintfcb`, `snprintfcb` and `vsnprintfcb`

When using tagged args (`CONFIG_CBPRINTF_PACKAGE_SUPPORT_TAGGED_ARGUMENTS` and `CBPRINTF_PACKAGE_ARGS_ARE_TAGGED`), calls to `cbprintf` will not use Picolibc, so formatting of output using those code will differ from Picolibc results as the `cbprintf` functions are not completely C/POSIX compliant.

**Math Functions** Picolibc provides full C17/IEEE STD 754-2019 support for float, double and long double math operations, except for long double versions of the Bessel functions.

**Thread Local Storage** Picolibc uses Thread Local Storage (TLS) (where supported) for data which is supposed to remain local to each thread, like `errno`. This means that TLS support is enabled when using Picolibc. As all TLS variables are allocated out of the thread stack area, this can affect stack size requirements by a few bytes.

**C Library Local Variables** Picolibc uses a few internal variables for things like heap management. These are collected in a dedicated memory partition called `z_libc_partition`. Applications using `CONFIG_USERSPACE` and memory domains must ensure that this partition is included in any domain active during Picolibc calls.
Dynamic Memory Management  Picolibc uses the malloc api family implementation provided by the common C library, which itself is built upon the kernel memory heap API.

Formatted Output

C defines standard formatted output functions such as printf and sprintf and these functions are implemented by the C standard libraries.

Each C standard library has its own set of requirements and configurations for selecting the formatted output modes and capabilities. Refer to each C standard library documentation for more details.

Dynamic Memory Management

C defines a standard dynamic memory management interface (for example, malloc() and free()) and these functions are implemented by the C standard libraries.

While the details of the dynamic memory management implementation varies across different C standard libraries, all supported libraries must conform to the following conventions. Every supported C standard library shall:

• manage its own memory heap either internally or by invoking the hook functions (for example, sbrk()) implemented in libc-hooks.c.

• maintain the architecture- and memory region-specific alignment requirements for the memory blocks allocated by the standard dynamic memory allocation interface (for example, malloc()).

• allocate memory blocks inside the z_malloc_partition memory partition when userspace is enabled. See Pre-defined Memory Partitions.

For more details regarding the C standard library-specific memory management implementation, refer to each C standard library documentation.

Note:  Native Zephyr applications should use the memory management API supported by the Zephyr kernel such as k_malloc() in order to take advantage of the advanced features that they offer.

C standard dynamic memory management interface functions such as malloc() should be used only by the portable applications and libraries that target multiple operating systems.

2.7.2 C++ Language Support

C++ is a general-purpose object-oriented programming language that is based on the C language.

Enabling C++ Support

Zephyr supports applications written in both C and C++. However, to use C++ in an application you must configure Zephyr to include C++ support by selecting the CONFIG_CPP in the application configuration file.

To enable C++ support, the compiler toolchain must also include a C++ compiler and the included compiler must be supported by the Zephyr build system. The Zephyr SDK, which includes the GNU C++ Compiler (part of GCC), is supported by Zephyr, and the features and their availability documented here assume the use of the Zephyr SDK.
The default C++ standard level (i.e. the language enforced by the compiler flags passed) for Zephyr apps is C++11. Other standards are available via kconfig choice, for example CON-
FIG_STD_CPP98. The oldest standard supported and tested in Zephyr is C++98.

When compiling a source file, the build system selects the C++ compiler based on the suffix (extension) of the files. Files identified with either a cpp or a cxx suffix are compiled using the C++ compiler. For example, myCplusplusApp.cpp is compiled using C++.

The C++ standard requires the main() function to have the return type of int. Your main() must be defined as int main(void). Zephyr ignores the return value from main, so applications should not return status information and should, instead, return zero.

**Note:** Do not use C++ for kernel, driver, or system initialization code.

### Language Features

Zephyr currently provides only a subset of C++ functionality. The following features are *not* supported:

- Static global object destruction
- OS-specific C++ standard library classes (e.g. std::thread, std::mutex)

While not an exhaustive list, support for the following functionality is included:

- Inheritance
- Virtual functions
- Virtual tables
- Static global object constructors
- Dynamic object management with the `new` and `delete` operators
- Exceptions
- RTTI (runtime type information)
- Standard Template Library (STL)

Static global object constructors are initialized after the drivers are initialized but before the application main() function. Therefore, use of C++ is restricted to application code.

In order to make use of the C++ exceptions, the CONFIG_CPP_EXCEPTIONS must be selected in the application configuration file.

### Zephyr Minimal C++ Library

Zephyr minimal C++ library (lib/cpp/minimal) provides a minimal subset of the C++ standard library and application binary interface (ABI) functions to enable basic C++ language support. This includes:

- `new` and `delete` operators
- virtual function stub and vtables
- static global initializers for global constructors

The scope of the minimal C++ library is strictly limited to providing the basic C++ language support, and it does not implement any Standard Template Library (STL) classes and functions. For this reason, it is only suitable for use in the applications that implement their own (non-standard) class library and do not rely on the Standard Template Library (STL) components.
Any application that makes use of the Standard Template Library (STL) components, such as `std::string` and `std::vector`, must enable the C++ standard library support.

### C++ Standard Library

The **C++ Standard Library** is a collection of classes and functions that are part of the ISO C++ standard (`std` namespace).

Zephyr does not include any C++ standard library implementation in source code form. Instead, it allows configuring the build system to link against the pre-built C++ standard library included in the C++ compiler toolchain.

To enable C++ standard library, select an applicable toolchain-specific C++ standard library type from the `CONFIG_LIBCPP_IMPLEMENTATION` in the application configuration file.

For instance, when building with the **Zephyr SDK**, the build system can be configured to link against the GNU C++ Library (`libstdc++.a`), which is a fully featured C++ standard library that provides all features required by the ISO C++ standard including the Standard Template Library (STL), by selecting `CONFIG_GLIBCXX_LIBCPP` in the application configuration file.

The following C++ standard libraries are supported by Zephyr:

- GNU C++ Library (`CONFIG_GLIBCXX_LIBCPP`)
- ARC MetaWare C++ Library (`CONFIG_ARCMWDT_LIBCPP`)

A Zephyr subsystem that requires the features from the full C++ standard library can select, from its config, `CONFIGQUIRES_FULL_LIBCPP`, which automatically selects a compatible C++ standard library unless the Kconfig symbol for a specific C++ standard library is selected.

#### 2.8 Optimizations

Guides on how to optimize Zephyr for performance, power and footprint.

##### 2.8.1 Optimizing for Footprint

**Stack Sizes**

Stack sizes of various system threads are specified generously to allow for usage in different scenarios on as many supported platforms as possible. You should start the optimization process by reviewing all stack sizes and adjusting them for your application:

- `CONFIG_ISR_STACK_SIZE`
  - Set to 2048 by default
- `CONFIG_MAIN_STACK_SIZE`
  - Set to 1024 by default
- `CONFIG_IDLE_STACK_SIZE`
  - Set to 320 by default
- `CONFIG_SYSTEM_WORKQUEUE_STACK_SIZE`
  - Set to 1024 by default
- `CONFIG_PRIVILEGED_STACK_SIZE`
  - Set to 1024 by default, depends on userspace feature.
Unused Peripherals

Some peripherals are enabled by default. You can disable unused peripherals in your project configuration, for example:

```plaintext
CONFIG_GPIO=n
CONFIG_SPI=n
```

Various Debug/Informational Options

The following options are enabled by default to provide more information about the running application and to provide means for debugging and error handling:

- `CONFIG_BOOT_BANNER`: This option can be disabled to save a few bytes.
- `CONFIG_DEBUG`: This option can be disabled for production builds

MPU/MMU Support

Depending on your application and platform needs, you can disable MPU/MMU support to gain some memory and improve performance. Consider the consequences of this configuration choice though, because you'll lose advanced stack checking and support.

2.8.2 Optimization Tools

Footprint and Memory Usage

The build system offers 3 targets to view and analyse RAM, ROM and stack usage in generated images. The tools run on the final image and give information about size of symbols and code being used in both RAM and ROM. Additionally, with features available through the compiler, we can also generate worst-case stack usage analysis:

Tools that are available as build system targets:

- **Build Target: ram_report**  List all compiled objects and their RAM usage in a tabular form with bytes per symbol and the percentage it uses. The data is grouped based on the file system location of the object in the tree and the file containing the symbol.

  Use the `ram_report` target with your board:

  Using west:

  ```bash
  west build -b reel_board samples/hello_world
  west build -t ram_report
  ```

  Using CMake and ninja:

  ```bash
  # Use cmake to configure a Ninja-based buildsystem:
  cmake -GNinja -DBOARD=reel_board samples/hello_world
  # Now run the build tool on the generated build system:
  ninja -Cbuild ram_report
  ```

  which will generate something similar to the output below:
<table>
<thead>
<tr>
<th>Path</th>
<th>Size</th>
<th>%</th>
</tr>
</thead>
<tbody>
<tr>
<td>Root</td>
<td>4637</td>
<td>100.00%</td>
</tr>
<tr>
<td>(hidden)</td>
<td>4</td>
<td>0.09%</td>
</tr>
<tr>
<td>(no paths)</td>
<td>2748</td>
<td>59.26%</td>
</tr>
<tr>
<td>├── _cpus_active</td>
<td>4</td>
<td>0.09%</td>
</tr>
<tr>
<td>│   ├── _kernel</td>
<td>32</td>
<td>0.69%</td>
</tr>
<tr>
<td>│   ├── _sw_isr_table</td>
<td>384</td>
<td>8.28%</td>
</tr>
<tr>
<td>│   └── cli.1</td>
<td>16</td>
<td>0.35%</td>
</tr>
<tr>
<td>│   └── on.2</td>
<td>4</td>
<td>0.09%</td>
</tr>
<tr>
<td>│   └── poll_out_lock.0</td>
<td>4</td>
<td>0.09%</td>
</tr>
<tr>
<td>│   └── z_idle_threads</td>
<td>128</td>
<td>2.76%</td>
</tr>
<tr>
<td>│   └── z_interrupt_stacks</td>
<td>2048</td>
<td>44.17%</td>
</tr>
<tr>
<td>│   └── z_main_thread</td>
<td>128</td>
<td>2.76%</td>
</tr>
<tr>
<td>└── WORKSPACE</td>
<td>184</td>
<td>3.97%</td>
</tr>
<tr>
<td>└── modules</td>
<td>184</td>
<td>3.97%</td>
</tr>
<tr>
<td>│   └── hal</td>
<td>184</td>
<td>3.97%</td>
</tr>
<tr>
<td>│       └── nordic</td>
<td>184</td>
<td>3.97%</td>
</tr>
<tr>
<td>│           └── nrfx</td>
<td>184</td>
<td>3.97%</td>
</tr>
<tr>
<td>│               └── src</td>
<td>184</td>
<td>3.97%</td>
</tr>
<tr>
<td>│                   └── nrfx_clock.c</td>
<td>8</td>
<td>0.17%</td>
</tr>
<tr>
<td>│                       └── m_clock_cb</td>
<td>8</td>
<td>0.17%</td>
</tr>
<tr>
<td>│                       └── nrfx_gpiote.c</td>
<td>132</td>
<td>2.85%</td>
</tr>
<tr>
<td>│                             └── m_cb</td>
<td>132</td>
<td>2.85%</td>
</tr>
<tr>
<td>│                       └── nrfx_ppi.c</td>
<td>4</td>
<td>0.09%</td>
</tr>
<tr>
<td>│                               └── m_channels_allocated</td>
<td>4</td>
<td>0.09%</td>
</tr>
<tr>
<td>│                       └── nrfx_twim.c</td>
<td>40</td>
<td>0.86%</td>
</tr>
<tr>
<td>│                               └── m_cb</td>
<td>40</td>
<td>0.86%</td>
</tr>
<tr>
<td>└── ZEPHYR_BASE</td>
<td>1701</td>
<td>36.68%</td>
</tr>
<tr>
<td>└── arch</td>
<td>5</td>
<td>0.11%</td>
</tr>
<tr>
<td>│   └── arm</td>
<td>5</td>
<td>0.11%</td>
</tr>
<tr>
<td>│       └── core</td>
<td>5</td>
<td>0.11%</td>
</tr>
<tr>
<td>│           └── mpu</td>
<td>1</td>
<td>0.02%</td>
</tr>
<tr>
<td>│                   └── arm_mpu.c</td>
<td>1</td>
<td>0.02%</td>
</tr>
<tr>
<td>│                       └── static_regions_num</td>
<td>1</td>
<td>0.02%</td>
</tr>
<tr>
<td>│                               └── tls.c</td>
<td>4</td>
<td>0.09%</td>
</tr>
<tr>
<td>│                       └── z_arm_tls_ptr</td>
<td>4</td>
<td>0.09%</td>
</tr>
<tr>
<td>└── drivers</td>
<td>258</td>
<td>5.56%</td>
</tr>
</tbody>
</table>

### Build Target: rom_report

List all compiled objects and their ROM usage in a tabular form with bytes per symbol and the percentage it uses. The data is grouped based on the file system location of the object in the tree and the file containing the symbol.

Use the `rom_report` to get the ROM report:

Using west:

```
west build -b reel_board samples/hello_world
west build -t rom_report
```

Using CMake and ninja:

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=reel_board samples/hello_world

# Now run the build tool on the generated build system:
ninja -Cbuild rom_report
```

2.8. Optimizations
which will generate something similar to the output below:

<table>
<thead>
<tr>
<th>Path</th>
<th>Size</th>
<th>%</th>
</tr>
</thead>
<tbody>
<tr>
<td>Root</td>
<td>21652</td>
<td>100.00%</td>
</tr>
<tr>
<td>ZEPHYR_BASE</td>
<td>13378</td>
<td>61.79%</td>
</tr>
<tr>
<td>arch</td>
<td>1718</td>
<td>7.93%</td>
</tr>
<tr>
<td>core</td>
<td>1020</td>
<td>4.71%</td>
</tr>
<tr>
<td>cortex_m</td>
<td>620</td>
<td>2.86%</td>
</tr>
<tr>
<td>bus_fault.constprop.0</td>
<td>108</td>
<td>0.50%</td>
</tr>
<tr>
<td>mem_manage_fault.constprop.0</td>
<td>120</td>
<td>0.55%</td>
</tr>
<tr>
<td>usage_fault.constprop.0</td>
<td>84</td>
<td>0.39%</td>
</tr>
<tr>
<td>z_arm_fault</td>
<td>292</td>
<td>1.35%</td>
</tr>
<tr>
<td>z_arm_fault_init</td>
<td>16</td>
<td>0.07%</td>
</tr>
<tr>
<td>boards</td>
<td>32</td>
<td>0.15%</td>
</tr>
<tr>
<td>arm</td>
<td>32</td>
<td>0.15%</td>
</tr>
<tr>
<td>reel_board</td>
<td>32</td>
<td>0.15%</td>
</tr>
<tr>
<td>board.c</td>
<td>32</td>
<td>0.15%</td>
</tr>
<tr>
<td>__init_board_reel_board_init</td>
<td>8</td>
<td>0.04%</td>
</tr>
<tr>
<td>board_reel_board_init</td>
<td>24</td>
<td>0.11%</td>
</tr>
<tr>
<td>build</td>
<td>194</td>
<td>0.90%</td>
</tr>
<tr>
<td>zephyr</td>
<td>194</td>
<td>0.90%</td>
</tr>
<tr>
<td>isr_tables.c</td>
<td>192</td>
<td>0.89%</td>
</tr>
<tr>
<td>_irq_vector_table</td>
<td>192</td>
<td>0.89%</td>
</tr>
<tr>
<td>misc</td>
<td>2</td>
<td>0.01%</td>
</tr>
<tr>
<td>generated</td>
<td>2</td>
<td>0.01%</td>
</tr>
<tr>
<td>configs.c</td>
<td>2</td>
<td>0.01%</td>
</tr>
<tr>
<td>_ConfigAbsSyms</td>
<td>2</td>
<td>0.01%</td>
</tr>
<tr>
<td>drivers</td>
<td>6162</td>
<td>28.46%</td>
</tr>
<tr>
<td>boards</td>
<td>32</td>
<td>0.15%</td>
</tr>
<tr>
<td>arm</td>
<td>32</td>
<td>0.15%</td>
</tr>
<tr>
<td>reel_board</td>
<td>32</td>
<td>0.15%</td>
</tr>
<tr>
<td>board.c</td>
<td>32</td>
<td>0.15%</td>
</tr>
<tr>
<td>__init_board_reel_board_init</td>
<td>8</td>
<td>0.04%</td>
</tr>
<tr>
<td>board_reel_board_init</td>
<td>24</td>
<td>0.11%</td>
</tr>
<tr>
<td>build</td>
<td>194</td>
<td>0.90%</td>
</tr>
<tr>
<td>zephyr</td>
<td>194</td>
<td>0.90%</td>
</tr>
<tr>
<td>isr_tables.c</td>
<td>192</td>
<td>0.89%</td>
</tr>
<tr>
<td>_irq_vector_table</td>
<td>192</td>
<td>0.89%</td>
</tr>
<tr>
<td>misc</td>
<td>2</td>
<td>0.01%</td>
</tr>
<tr>
<td>generated</td>
<td>2</td>
<td>0.01%</td>
</tr>
<tr>
<td>configs.c</td>
<td>2</td>
<td>0.01%</td>
</tr>
<tr>
<td>_ConfigAbsSyms</td>
<td>2</td>
<td>0.01%</td>
</tr>
</tbody>
</table>

**Build Target: puncover**  This target uses a third-party tool called puncover which can be found at [https://github.com/HBehrens/puncover](https://github.com/HBehrens/puncover). When this target is built, it will launch a local web server which will allow you to open a web client and browse the files and view their ROM, RAM, and stack usage. Before you can use this target, you will have to install the puncover python module:

```
pip3 install git+https://github.com/HBehrens/puncover --user
```

**Warning:** This is a third-party tool that might or might not be working at any given time. Please check the GitHub issues, and report new problems to the project maintainer.

Then:

Using west:

```
west build -b reel_board samples/hello_world
west build -t puncover
```

Using CMake and ninja:

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=reel_board samples/hello_world
```

(continues on next page)
To view worst-case stack usage analysis, build this with the CONFIG_STACK_USAGE enabled.

Using west:

```shell
west build -b reel_board samples/hello_world --DCONFIG_STACK_USAGE=y
west build -t puncover
```

Using CMake and ninja:

```shell
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=reel_board -DCONFIG_STACK_USAGE=y samples/hello_world

# Now run the build tool on the generated build system:
ninja -Cbuild puncover
```

## Data Structures

**Build Target: pahole**  
Poke-a-hole (pahole) is an object-file analysis tool to find the size of the data structures, and the holes caused due to aligning the data elements to the word-size of the CPU by the compiler.

Poke-a-hole (pahole) must be installed prior to using this target. It can be obtained from https://git.kernel.org/pub/scm/devel/pahole/pahole.git and is available in the dwarves package in both fedora and ubuntu:

```shell
sudo apt-get install dwarves
```

or in fedora:

```shell
sudo dnf install dwarves
```

Using west:

```shell
west build -b reel_board samples/hello_world
west build -t pahole
```

Using CMake and ninja:

```shell
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=reel_board -DCONFIG_STACK_USAGE=y samples/hello_world

# Now run the build tool on the generated build system:
ninja -Cbuild pahole
```

After running this target, pahole will output the results to the console:

```c
/* Used at: zephyr/isr_tables.c */
/* <80> ../include/sw_isr_table.h:30 */
struct _isr_table_entry {
  void * arg; /* 0 4 */
  void (*isr)(void *); /* 4 4 */
  /* size: 8, cachelines: 1, members: 2 */
  /* last cacheline: 8 bytes */
};
/* Used at: zephyr/isr_tables.c */
```

(continues on next page)
2.9 Flashing and Hardware Debugging

2.9.1 Flash & Debug Host Tools

This guide describes the software tools you can run on your host workstation to flash and debug Zephyr applications.

Zephyr's west tool has built-in support for all of these in its flash, debug, debugserver, and attach commands, provided your board hardware supports them and your Zephyr board directory's board.cmake file declares that support properly. See Building, Flashing and Debugging for more information on these commands.

SAM Boot Assistant (SAM-BA)

Atmel SAM Boot Assistant (Atmel SAM-BA) allows In-System Programming (ISP) from USB or UART host without any external programming interface. Zephyr allows users to develop and program boards with SAM-BA support using west. Zephyr supports devices with/without ROM bootloader and both extensions from Arduino and Adafruit. Full support was introduced in Zephyr SDK 0.12.0.

The typical command to flash the board is:

```
west flash [-r bossac] [-p /dev/ttyX]
```

Flash configuration for devices:

With ROM bootloader

These devices don't need any special configuration. After building your application, just run west flash to flash the board.

Without ROM bootloader

For these devices, the user should:

1. Define flash partitions required to accommodate the bootloader and application image; see Flash map for details.
2. Have board .defconfig file with the CONFIG_USE_DT_CODE_PARTITION Kconfig option set to y to instruct the build system to use these partitions for code relocation. This option can also be set in prj.conf or any other Kconfig fragment.

3. Build and flash the SAM-BA bootloader on the device.

With compatible SAM-BA bootloader

For these devices, the user should:

1. Define flash partitions required to accommodate the bootloader and application image; see Flash map for details.

2. Have board .defconfig file with the CONFIG_BOOTLOADER_BOSSA Kconfig option set to y. This will automatically select the CONFIG_USE_DT_CODE_PARTITION Kconfig option which instruct the build system to use these partitions for code relocation. The board .defconfig file should have CONFIG_BOOTLOADER_BOSSA_ARDUINO , CONFIG_BOOTLOADER_BOSSA_ADAFRUIT_UF2 or the CONFIG_BOOTLOADER_BOSSA_LEGACY Kconfig option set to y to select the right compatible SAM-BA bootloader mode. These options can also be set in prj.conf or any other Kconfig fragment.

3. Build and flash the SAM-BA bootloader on the device.

Note: The CONFIG_BOOTLOADER_BOSSA_LEGACY Kconfig option should be used as last resource. Try configure first with Devices without ROM bootloader.

**Typical flash layout and configuration** For bootloaders that reside on flash, the devicetree partition layout is mandatory. For devices that have a ROM bootloader, they are mandatory when the application uses a storage or other non-application partition. In this special case, the boot partition should be omitted and code_partition should start from offset 0. It is necessary to define the partitions with sizes that avoid overlaps, always.

A typical flash layout for devices without a ROM bootloader is:

```c
/ {
    chosen {
        zephyr,code-partition = &code_partition;
    };

    &flash0 {
        partitions {
            compatible = "fixed-partitions";
            address-cells = <1>;
            size-cells = <1>;

            boot_partition: partition@0 {
                label = "sam-ba";
                reg = <0x00000000 0x2000>;
                read-only;
            };

            code_partition: partition@2000 {
                label = "code";
                reg = <0x2000 0x3a00>;
                read-only;
            };

            /*
             * The final 16 KiB is reserved for the application.
             * Storage partition will be used by FCB/LittleFS/NVS
             */
        }
    }
}
```

(continues on next page)
A typical flash layout for devices with a ROM bootloader and storage partition is:

```c
/*
 * if enabled.
 */

storage_partition: partition@3c000 {
    label = "storage";
    reg = <0x0003c000 0x00004000>;
};

A typical flash layout for devices with a ROM bootloader and storage partition is:

```

/ {
    chosen {
        zephyr,code-partition = &code_partition;
    };
};

&flash0 {
    partitions {
        compatible = "fixed-partitions";
        #address-cells = <1>;
        #size-cells = <1>;

        code_partition: partition@0 {
            label = "code";
            reg = <0x0 0xF0000>
            read-only;
        };

        /*
        * The final 64 KiB is reserved for the application.
        * Storage partition will be used by FCB/LittleFS/NVS
        * if enabled.
        */

        storage_partition: partition@F0000 {
            label = "storage";
            reg = <0x00F0000 0x00100000>;
        };
    };
};
```

**Enabling SAM-BA runner** In order to instruct Zephyr west tool to use the SAM-BA bootloader the board.cmake file must have include(${ZEPHYR_BASE}/boards/common/bossac.board.cmake) entry. Note that Zephyr tool accept more entries to define multiple runners. By default, the first one will be selected when using west flash command. The remaining options are available passing the runner option, for instance west flash -r bossac.

More implementation details can be found in the boards documentation. As a quick reference, see these three board documentation pages:

- sam4e_xpro (ROM bootloader)
- adafruit_feather_m0_basic_proto (Adafruit UF2 bootloader)
- arduino_nano_33_iot (Arduino bootloader)
- arduino_nano_33_ble (Arduino legacy bootloader)

**Enabling BOSSAC on Windows Native [Experimental]** Zephyr SDK’s bossac is currently supported on Linux and macOS only. Windows support can be achieved by using the bossac ver-

---

Enabling SAM-BA runner...
sion from BOSSA official releases. After installing using default options, the bossac.exe must be added to Windows PATH. A specific bossac executable can be used by passing the --bossac option, as follows:

```bash
west flash -r bossac --bossac="C:\Program Files (x86)\BOSSA\bossac.exe" --bossac-port="COMx"
```

**Note:** WSL is not currently supported.

### LinkServer Debug Host Tools

Linkserver is a utility for launching and managing GDB servers for NXP debug probes, which also provides a command-line target flash programming capabilities. Linkserver can be used with the NXP MCUXpresso for Visual Studio Code implementation, with custom debug configurations based on GNU tools or as part of a headless solution for continuous integration and test. LinkServer can be used with MCU-Link, LPC-Link2, LPC11U35-based and OpenSDA based standalone or on-board debug probes from NXP.

NXP recommends installing LinkServer by using NXP's MCUXpresso Installer. This method will also install the tools supporting the debug probes below, including NXP's MCU-Link and LPC-Scrypt tools.

LinkServer is compatible with the following debug probes:

- **LPC-LINK2 CMSIS DAP Onboard Debug Probe**
- **MCU-Link CMSIS-DAP Onboard Debug Probe**
- **OpenSDA DAPLink Onboard Debug Probe**

To use LinkServer with West commands, the install folder should be added to the PATH environment variable. The default installation path to add is:

**Linux**

```
/usr/local/LinkServer
```

**Windows**

```
c:\nxp\LinkServer_<version>
```

Supported west commands:

1. flash
2. debug
3. debugserver
4. attach

Notes:

1. Probes can be listed with LinkServer:

   ```bash
   LinkServer probes
   ```

2. With multiple debug probes attached to the host, use the LinkServer west runner --probe option to pass the probe index.

   ```bash
   west flash --runner=linkserver --probe=3
   ```

3. Device-specific settings can be overridden with the west runner for LinkServer with the option ‘--override’. May be used multiple times. The format is dictated by LinkServer, e.g.:
J-Link Debug Host Tools

Segger provides a suite of debug host tools for Linux, macOS, and Windows operating systems:

• J-Link GDB Server: GDB remote debugging
• J-Link Commander: Command-line control and flash programming
• RTT Viewer: RTT terminal input and output
• SystemView: Real-time event visualization and recording

These debug host tools are compatible with the following debug probes:

• LPC-Link2 J-Link Onboard Debug Probe
• OpenSDA J-Link Onboard Debug Probe
• MCU-Link JLink Onboard Debug Probe
• J-Link External Debug Probe
• ST-LINK/V2-1 Onboard Debug Probe

Check if your SoC is listed in J-Link Supported Devices.

Download and install the J-Link Software and Documentation Pack to get the J-Link GDB Server and Commander, and to install the associated USB device drivers. RTT Viewer and SystemView can be downloaded separately, but are not required.

Note that the J-Link GDB server does not yet support Zephyr RTOS-awareness.

OpenOCD Debug Host Tools

OpenOCD is a community open source project that provides GDB remote debugging and flash programming support for a wide range of SoCs. A fork that adds Zephyr RTOS-awareness is included in the Zephyr SDK; otherwise see Getting OpenOCD for options to download OpenOCD from official repositories.

These debug host tools are compatible with the following debug probes:

• OpenSDA DAPLink Onboard Debug Probe
• J-Link External Debug Probe
• ST-LINK/V2-1 Onboard Debug Probe

Check if your SoC is listed in OpenOCD Supported Devices.

Note: On Linux, openocd is available though the Zephyr SDK. Windows users should use the following steps to install openocd:

• Download openocd for Windows from here: OpenOCD Windows
• Copy bin and share dirs to C:\Program Files\OpenOCD\n• Add C:\Program Files\OpenOCD\bin to ‘PATH’ environment variable
**pyOCD Debug Host Tools**

pyOCD is an open source project from Arm that provides GDB remote debugging and flash programming support for Arm Cortex-M SoCs. It is distributed on PyPi and installed when you complete the Get Zephyr and install Python dependencies step in the Getting Started Guide. pyOCD includes support for Zephyr RTOS-awareness.

These debug host tools are compatible with the following debug probes:

- *LPC-LINK2 CMSIS DAP Onboard Debug Probe*
- *MCU-Link CMSIS-DAP Onboard Debug Probe*
- *OpenSDA DAPLink Onboard Debug Probe*
- *ST-LINK/V2-1 Onboard Debug Probe*

Check if your SoC is listed in pyOCD Supported Devices.

**Lauterbach TRACE32 Debug Host Tools**

Lauterbach TRACE32 is a product line of microprocessor development tools, debuggers and real-time tracer with support for JTAG, SWD, NEXUS or ETM over multiple core architectures, including Arm Cortex-A/-R/-M, RISC-V, Xtensa, etc. Zephyr allows users to develop and program boards with Lauterbach TRACE32 support using *west*.

The runner consists of a wrapper around TRACE32 software, and allows a Zephyr board to execute a custom start-up script (Practice Script) for the different commands supported, including the ability to pass extra arguments from CMake. It is up to the board using this runner to define the actions performed on each command.

**Install Lauterbach TRACE32 Software**  Download Lauterbach TRACE32 software from the Lauterbach TRACE32 download website (registration required) and follow the installation steps described in Lauterbach TRACE32 Installation Guide.

**Flashing and Debugging**  Set the environment variable T32_DIR to the TRACE32 system directory. Then execute *west flash* or *west debug* commands to flash or debug the Zephyr application as detailed in Building, Flashing and Debugging. The debug command launches TRACE32 GUI to allow debug the Zephyr application, while the *flash* command hides the GUI and perform all operations in the background.

By default, the t32 runner will launch TRACE32 using the default configuration file named config.t32 located in the TRACE32 system directory. To use a different configuration file, supply the argument --config CONFIG to the runner, for example:

```
west flash --config myconfig.t32
```

For more options, run *west flash --context -r t32* to print the usage.

**Zephyr RTOS Awareness**  To enable Zephyr RTOS awareness follow the steps described in Lauterbach TRACE32 Zephyr OS Awareness Manual.

**NXP S32 Debug Probe Host Tools**

*NXP S32 Debug Probe* is designed to work in conjunction with NXP S32 Design Studio for S32 Platform.
Download (registration required) NXP S32 Design Studio for S32 Platform and follow the S32 Design Studio for S32 Platform Installation User Guide to get the necessary debug host tools and associated USB device drivers.

Note that Zephyr RTOS-awareness support for the NXP S32 GDB server depends on the target device. Consult the product release notes for more information.

Supported west commands:

1. debug
2. debugserver
3. attach

**Basic usage**  Before starting, add NXP S32 Design Studio installation directory to the system `PATH` environment variable. Alternatively, it can be passed to the runner on each invocation via `--s32ds-path` as shown below:

Linux

```bash
west debug --s32ds-path=/opt/NXP/S32DS.3.5
```

Windows

```bash
west debug --s32ds-path=C:\NXP\S32DS.3.5
```

If multiple S32 debug probes are connected to the host via USB, the runner will ask the user to select one via command line prompt before continuing. The connection string for the probe can be also specified when invoking the runner via `--dev-id=<connection-string>`. Consult NXP S32 debug probe user manual for details on how to construct the connection string. For example, if using a probe with serial ID `00:04:9f:00:ca:fe`:

```bash
west debug --dev-id='s32dbg:00:04:9f:00:ca:fe'
```

It is possible to pass extra options to the debug host tools via `--tool-opt`. When executing `debug` or `attach` commands, the tool options will be passed to the GDB client only. When executing `debugserver`, the tool options will be passed to the GDB server. For example, to load a Zephyr application to SRAM and afterwards detach the debug session:

```bash
west debug --tool-opt='--batch'
```

## 2.9.2 Debug Probes

A **debug probe** is special hardware which allows you to control execution of a Zephyr application running on a separate board. Debug probes usually allow reading and writing registers and memory, and support breakpoint debugging of the Zephyr application on your host workstation using tools like GDB. They may also support other debug software and more advanced features such as **tracing program execution**. For details on the related host software supported by Zephyr, see *Flash & Debug Host Tools*.

Debug probes are usually connected to your host workstation via USB; they are sometimes also accessible via an IP network or other means. They usually connect to the device running Zephyr using the JTAG or SWD protocols. Debug probes are either separate hardware devices or circuitry integrated into the same board which runs Zephyr.

Many supported boards in Zephyr include a second microcontroller that serves as an onboard debug probe, usb-to-serial adapter, and sometimes a drag-and-drop flash programmer. This eliminates the need to purchase an external debug probe and provides a variety of debug host tool options.
Several hardware vendors have their own branded onboard debug probe implementations: NXP LPC boards have LPC-Link2, NXP Kinetis (former Freescale) boards have OpenSDA, and ST boards have ST-LINK. Each onboard debug probe microcontroller can support one or more types of firmware that communicate with their respective debug host tools. For example, an OpenSDA microcontroller can be programmed with DAPLink firmware to communicate with pyOCD or OpenOCD debug host tools, or with J-Link firmware to communicate with J-Link debug host tools.

### Debug Probes & Host Tools Compatibility Chart

<table>
<thead>
<tr>
<th>Debug Probes</th>
<th>Host Tools</th>
<th>J-Link Debug</th>
<th>OpenOCD</th>
<th>pyOCD</th>
<th>NXP S32DS</th>
</tr>
</thead>
<tbody>
<tr>
<td>LPC-Link2 J-Link</td>
<td>✓</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>OpenSDA DAPLink</td>
<td>✓</td>
<td>✓</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>OpenSDA J-Link</td>
<td>✓</td>
<td></td>
<td>✓</td>
<td></td>
<td></td>
</tr>
<tr>
<td>J-Link External</td>
<td>✓</td>
<td></td>
<td>✓</td>
<td></td>
<td></td>
</tr>
<tr>
<td>ST-LINK/V2-1</td>
<td>✓</td>
<td>✓</td>
<td></td>
<td></td>
<td>some STM32 boards</td>
</tr>
<tr>
<td>NXP S32 Debug Probe</td>
<td></td>
<td></td>
<td></td>
<td>✓</td>
<td></td>
</tr>
</tbody>
</table>

Some supported boards in Zephyr do not include an onboard debug probe and therefore require an external debug probe. In addition, boards that do include an onboard debug probe often also have an SWD or JTAG header to enable the use of an external debug probe instead. One reason this may be useful is that the onboard debug probe may have limitations, such as lack of support for advanced debuggers or high-speed tracing. You may need to adjust jumpers to prevent the onboard debug probe from interfering with the external debug probe.

### MCU-Link CMSIS-DAP Onboard Debug Probe

The CMSIS-DAP debug probes allow debugging from any compatible toolchain, including IAR EWARM, Keil MDK, NXP's MCUXpresso IDE and MCUXpresso extension for VS Code. In addition to debug probe functionality, the MCU-Link probes may also provide:

1. SWO trace end point: this virtual device is used by MCUXpresso to retrieve SWO trace data. See the MCUXpresso IDE documentation for more information.
2. Virtual COM (VCOM) port / UART bridge connected to the target processor
3. USB to UART, SPI and/or I2C interfaces (depending on MCU-Link type/implementation)
4. Energy measurements of the target MCU

This debug probe is compatible with the following debug host tools:

- **LinkServer Debug Host Tools**

This probe is realized by programming the MCU-Link microcontroller with the CMSIS-DAP MCU-Link firmware, which is already installed by default. NXP recommends using NXP's MCUXpresso Installer, which installs both the MCU-Link host tools plus the LinkServer Debug Host Tools.

1. Put the MCU-Link microcontroller into DFU boot mode by attaching the DFU jumper, then powering up the board.
2. Run the program_CMSIS script, found in the installed MCU-Link scripts folder.
3. Remove the DFU jumper and power cycle the board.

---

2.9. Flashing and Hardware Debugging
MCU-Link JLink Onboard Debug Probe

The MCU-Link J-Link is an onboard debug probe and usb-to-serial adapter supported on many NXP development boards.

This debug probe is compatible with the following debug host tools:

- **J-Link Debug Host Tools**

These probes do not have JLink firmware installed by default, and must be updated. NXP recommends using NXP's MCUXpresso Installer, which installs both the J-Link Debug Host Tools plus the MCU-Link host tools.

1. Put the MCU-Link microcontroller into DFU boot mode by attaching the DFU jumper, then powering up the board.
2. Run the program_JLINK script, found in the installed MCU-Link scripts folder.
3. Remove the DFU jumper and power cycle the board.

LPC-LINK2 CMSIS DAP Onboard Debug Probe

The CMSIS-DAP debug probes allow debugging from any compatible toolchain, including IAR EWARM, Keil MDK, as well as NXP's MCUXpresso IDE and MCUXpresso extension for VS Code. As well as providing debug probe functionality, the LPC-Link2 probes also provide:

1. SWO trace end point: this virtual device is used by MCUXpresso to retrieve SWO trace data. See the MCUXpresso IDE documentation for more information.
2. Virtual COM (VCOM) port / UART bridge connected to the target processor
3. LPCSIO bridge that provides communication to I2C and SPI slave devices

This probe is realized by programming the LPC-Link2 microcontroller with the CMSIS-DAP LPC-Link2 firmware. Download and install LPCScrypt to get the firmware and programming scripts.

**Note:** Verify the firmware supports your board by visiting Firmware for LPCXpresso

1. Put the LPC-Link2 microcontroller into DFU boot mode by attaching the DFU jumper, then powering up the board.
2. Run the program_CMSIS script.
3. Remove the DFU jumper and power cycle the board.

LPC-Link2 J-Link Onboard Debug Probe

The LPC-Link2 J-Link is an onboard debug probe and usb-to-serial adapter supported on many NXP LPC and i.MX RT development boards.

This debug probe is compatible with the following debug host tools:

- **J-Link Debug Host Tools**

This probe is realized by programming the LPC-Link2 microcontroller with J-Link LPC-Link2 firmware. Download and install LPCScrypt to get the firmware and programming scripts.

**Note:** Verify the firmware supports your board by visiting Firmware for LPCXpresso

1. Put the LPC-Link2 microcontroller into DFU boot mode by attaching the DFU jumper, then powering up the board.
2. Run the program_JLINK script.
3. Remove the DFU jumper and power cycle the board.

OpenSDA DAPLink Onboard Debug Probe

The OpenSDA DAPLink is an onboard debug probe and usb-to-serial adapter supported on many NXP Kinetis and i.MX RT development boards. It also includes drag-and-drop flash programming support.

This debug probe is compatible with the following debug host tools:

- pyOCD Debug Host Tools
- OpenOCD Debug Host Tools

This probe is realized by programming the OpenSDA microcontroller with DAPLink OpenSDA firmware. NXP provides OpenSDA DAPLink Board-Specific Firmwares.

Install the debug host tools before you program the firmware.

As with all OpenSDA debug probes, the steps for programming the firmware are:

1. Put the OpenSDA microcontroller into bootloader mode by holding the reset button while you power on the board. Note that “bootloader mode” in this context applies to the OpenSDA microcontroller itself, not the target microcontroller of your Zephyr application.
2. After you power on the board, release the reset button. A USB mass storage device called BOOTLOADER or MAINTENANCE will enumerate.
3. Copy the OpenSDA firmware binary to the USB mass storage device.
4. Power cycle the board, this time without holding the reset button. You should see three USB devices enumerate: a CDC device (serial port), a HID device (debug port), and a mass storage device (drag-and-drop flash programming).

OpenSDA J-Link Onboard Debug Probe

The OpenSDA J-Link is an onboard debug probe and usb-to-serial adapter supported on many NXP Kinetis and i.MX RT development boards.

This debug probe is compatible with the following debug host tools:

- J-Link Debug Host Tools

This probe is realized by programming the OpenSDA microcontroller with J-Link OpenSDA firmware. Segger provides OpenSDA J-Link Generic Firmwares and OpenSDA J-Link Board-Specific Firmwares, where the latter is generally recommended when available. Board-specific firmwares are required for i.MX RT boards to support their external flash memories, whereas generic firmwares are compatible with all Kinetis boards.

Install the debug host tools before you program the firmware.

As with all OpenSDA debug probes, the steps for programming the firmware are:

1. Put the OpenSDA microcontroller into bootloader mode by holding the reset button while you power on the board. Note that “bootloader mode” in this context applies to the OpenSDA microcontroller itself, not the target microcontroller of your Zephyr application.
2. After you power on the board, release the reset button. A USB mass storage device called BOOTLOADER or MAINTENANCE will enumerate.
3. Copy the OpenSDA firmware binary to the USB mass storage device.
4. Power cycle the board, this time without holding the reset button. You should see two USB devices enumerate: a CDC device (serial port) and a vendor-specific device (debug port).
J-Link External Debug Probe

Segger J-Link is a family of external debug probes, including J-Link EDU, J-Link PLUS, J-Link ULTRA+, and J-Link PRO, that support a large number of devices from different hardware architectures and vendors.

This debug probe is compatible with the following debug host tools:

- J-Link Debug Host Tools
- OpenOCD Debug Host Tools

Install the debug host tools before you program the firmware.

ST-LINK/V2-1 Onboard Debug Probe

ST-LINK/V2-1 is a serial and debug adapter built into all Nucleo and Discovery boards. It provides a bridge between your computer (or other USB host) and the embedded target processor, which can be used for debugging, flash programming, and serial communication, all over a simple USB cable.

It is compatible with the following host debug tools:

- OpenOCD Debug Host Tools
- J-Link Debug Host Tools

For some STM32 based boards, it is also compatible with:

- pyOCD Debug Host Tools

While it works out of the box with OpenOCD, it requires some flashing to work with J-Link. To do this, SEGGER offers a firmware upgrading the ST-LINK/V2-1 on board on the Nucleo and Discovery boards. This firmware makes the ST-LINK/V2-1 compatible with J-LinkOB, allowing users to take advantage of most J-Link features like the ultra fast flash download and debugging speed or the free-to-use GDBServer.

More information about upgrading ST-LINK/V2-1 to JLink or restore ST-LINK/V2-1 firmware please visit: Segger over ST-Link

Flash and debug with ST-Link Using OpenOCD

OpenOCD is available by default on ST-Link and configured as the default flash and debug tool. Flash and debug can be done as follows:

```
# From the root of the zephyr repository
west build -b None samples/hello_world
west flash
```

```
# From the root of the zephyr repository
west build -b None samples/hello_world
west debug
```

Using Segger J-Link

Once STLink is flashed with SEGGER FW and J-Link GDB server is installed on your host computer, you can flash and debug as follows:

Use CMake with 
`-DBOARD_FLASH_RUNNER=jlink` to change the default OpenOCD runner to J-Link. Alternatively, you might add the following line to your application CMakeList.txt file.

```
set(BOARD_FLASH_RUNNER jlink)
```
If you use West (Zephyr's meta-tool) you can modify the default runner using the `--runner` (or `-r`) option.

```
west flash --runner jlink
```

To attach a debugger to your board and open up a debug console with jlink.

```
west debug --runner jlink
```

For more information about West and available options, see West (Zephyr's meta-tool).

If you configured your Zephyr application to use Segger RTT console instead, open telnet:

```
$ telnet localhost 19021
Trying ::1...
Trying 127.0.0.1...
Connected to localhost.
Escape character is '^]'.
SEGGER J-Link V6.30f - Real time terminal output
J-Link STLink V21 compiled Jun 26 2017 10:35:16 V1.0, SN=773895351
Process: JlinkGDBServerCLExe
Zephyr Shell, Zephyr version: 1.12.99
Type 'help' for a list of available commands
shell>
```

If you get no RTT output you might need to disable other consoles which conflict with the RTT one if they are enabled by default in the particular sample or application you are running, such as disable UART_CONSOLE in menuconfig.

**Updating or restoring ST-Link firmware** ST-Link firmware can be updated using STM32CubeProgrammer Tool. It is usually useful when facing flashing issues, for instance when using twister's device-testing option.

Once installed, you can update attached board ST-Link firmware with the following command

```
s java -jar ~/STMicroelectronics/STM32Cube/STM32CubeProgrammer/Drivers/FirmwareUpgrade/STLinkUpgrade.jar -sn <board_uid>
```

Where board_uid can be obtained using twister's generate-hardware-map option. For more information about twister and available options, see Test Runner (Twister).

**NXP S32 Debug Probe**

NXP S32 Debug Probe enables NXP S32 target system debugging via a standard debug port while connected to a developer's workstation via USB or remotely via Ethernet.

NXP S32 Debug Probe is designed to work in conjunction with NXP S32 Design Studio (S32DS) and NXP Automotive microcontrollers and processors. Install the debug host tools as in indicated in NXP S32 Debug Probe Host Tools before you program the firmware.

### 2.10 Modules (External projects)

Zephyr relies on the source code of several externally maintained projects in order to avoid reinventing the wheel and to reuse as much well-established, mature code as possible when it makes sense. In the context of Zephyr's build system those are called *modules*. These modules must be integrated with the Zephyr build system, as described in more detail in other sections on this page.
To be classified as a candidate for being included in the default list of modules, an external project is required to have its own life-cycle outside the Zephyr Project, that is, reside in its own repository, and have its own contribution and maintenance workflow and release process. Zephyr modules should not contain code that is written exclusively for Zephyr. Instead, such code should be contributed to the main zephyr tree.

Modules to be included in the default manifest of the Zephyr project need to provide functionality or features endorsed and approved by the project Technical Steering Committee and should comply with the module licensing requirements and contribution guidelines. They should also have a Zephyr developer that is committed to maintain the module codebase.

Zephyr depends on several categories of modules, including but not limited to:

- Debugger integration
- Silicon vendor Hardware Abstraction Layers (HALs)
- Cryptography libraries
- File Systems
- Inter-Process Communication (IPC) libraries

Additionally, in some cases modules (particularly vendor HALs) can contain references to optional binary blobs.

This page summarizes a list of policies and best practices which aim at better organizing the workflow in Zephyr modules.

### 2.10.1 Modules vs west projects

Zephyr modules, described in this page, are not the same as west projects. In fact, modules do not require west at all. However, when using modules with west, then the build system uses west in order to find modules.

In summary:

Modules are repositories that contain a zephyr/module.yml file, so that the Zephyr build system can pull in the source code from the repository. West projects are entries in the projects: section in the west.yml manifest file. West projects are often also modules, but not always. There are west projects that are not included in the final firmware image (eg. tools) and thus do not need to be modules. Modules are found by the Zephyr build system either via west itself, or via the ZEPHYR_MODULES CMake variable.

The contents of this page only apply to modules, and not to west projects in general (unless they are a module themselves).

### 2.10.2 Module Repositories

- All modules included in the default manifest shall be hosted in repositories under the zephyrproject-rtos GitHub organization.
- The module repository codebase shall include a module.yml file in a zephyr/ folder at the root of the repository.
- Module repository names should follow the convention of using lowercase letters and dashes instead of underscores. This rule will apply to all new module repositories, except for repositories that are directly tracking external projects (hosted in Git repositories); such modules may be named as their external project counterparts.
Note: Existing module repositories that do not conform to the above convention do not need to be renamed to comply with the above convention.

- Module repositories names should be explicitly set in the `zephyr/module.yml` file.
- Modules should use “zephyr” as the default name for the repository main branch. Branches for specific purposes, for example, a module branch for an LTS Zephyr version, shall have names starting with the ‘zephyr_’ prefix.
- If the module has an external (upstream) project repository, the module repository should preserve the upstream repository folder structure.

Note: It is not required in module repositories to maintain a ‘master’ branch mirroring the master branch of the external repository. It is not recommended as this may generate confusion around the module’s main branch, which should be ‘zephyr’.

- Modules should expose all provided header files with an include pathname beginning with the module-name. (E.g., mcuboot should expose its `bootutil/bootutil.h` as “mcu-boot/bootutil/bootutil.h”.)

### Synchronizing with upstream

It is preferred to synchronize a module repository with the latest stable release of the corresponding external project. It is permitted, however, to update a Zephyr module repository with the latest development branch tip, if this is required to get important updates in the module codebase. When synchronizing a module with upstream it is mandatory to document the rationale for performing the particular update.

**Requirements for allowed practices** Changes to the main branch of a module repository, including synchronization with upstream code base, may only be applied via pull requests. These pull requests shall be verifiable by Zephyr CI and mergeable (e.g., with the Rebase and merge, or Create a merge commit option using Github UI). This ensures that the incoming changes are always reviewable, and the downstream module repository history is incremental (that is, existing commits, tags, etc. are always preserved). This policy also allows to run Zephyr CI, git lint, identity, and license checks directly on the set of changes that are to be brought into the module repository.

Note: Force-pushing to a module's main branch is not allowed.

**Allowed practices** The following practices conform to the above requirements and should be followed in all modules repositories. It is up to the module code owner to select the preferred synchronization practice, however, it is required that the selected practice is consistently followed in the respective module repository.

**Updating modules with a diff from upstream:** Upstream changes brought as a single snapshot commit (manual diff) in a pull request against the module’s main branch, which may be merged using the Rebase & merge operation. This approach is simple and should be applicable to all modules with the downside of suppressing the upstream history in the module repository.

Note: The above practice is the only allowed practice in modules where the external project is not hosted in an upstream Git repository.
The commit message is expected to identify the upstream project URL, the version to which the module is updated (upstream version, tag, commit SHA, if applicable, etc.), and the reason for the doing the update.

**Updating modules by merging the upstream branch:** Upstream changes brought in by performing a Git merge of the intended upstream branch (e.g. main branch, latest release branch, etc.) submitting the result in pull request against the module main branch, and merging the pull request using the *Create a merge commit* operation. This approach is applicable to modules with an upstream project Git repository. The main advantages of this approach is that the upstream repository history (that is, the original commit SHAs) is preserved in the module repository. The downside of this approach is that two additional merge commits are generated in the downstream main branch.

### 2.10.3 Contributing to Zephyr modules

### Individual Roles & Responsibilities

To facilitate management of Zephyr module repositories, the following individual roles are defined.

**Administrator:** Each Zephyr module shall have an administrator who is responsible for managing access to the module repository, for example, for adding individuals as Collaborators in the repository at the request of the module owner. Module administrators are members of the Administrators team, that is a group of project members with admin rights to module GitHub repositories.

**Module owner:** Each module shall have a module code owner. Module owners will have the overall responsibility of the contents of a Zephyr module repository. In particular, a module owner will:

- coordinate code reviewing in the module repository
- be the default assignee in pull-requests against the repository's main branch
- request additional collaborators to be added to the repository, as they see fit
- regularly synchronize the module repository with its upstream counterpart following the policies described in *Synchronizing with upstream*
- be aware of security vulnerability issues in the external project and update the module repository to include security fixes, as soon as the fixes are available in the upstream code base
- list any known security vulnerability issues, present in the module codebase, in Zephyr release notes.

**Note:** Module owners are not required to be Zephyr *Maintainers.*

**Merger:** The Zephyr Release Engineering team has the right and the responsibility to merge approved pull requests in the main branch of a module repository.

### Maintaining the module codebase

Updates in the zephyr main tree, for example, in public Zephyr APIs, may require patching a module's codebase. The responsibility for keeping the module codebase up to date is shared between the *contributor* of such updates in Zephyr and the module *owner*. In particular:

- the contributor of the original changes in Zephyr is required to submit the corresponding changes that are required in module repositories, to ensure that Zephyr CI on the pull request with the original changes, as well as the module integration testing are successful.
• the module owner has the overall responsibility for synchronizing and testing the module codebase with the zephyr main tree. This includes occasional advanced testing of the module’s codebase in addition to the testing performed by Zephyr’s CI. The module owner is required to fix issues in the module’s codebase that have not been caught by Zephyr pull request CI runs.

**Contributing changes to modules**

Submitting and merging changes directly to a module’s codebase, that is, before they have been merged in the corresponding external project repository, should be limited to:

• changes required due to updates in the zephyr main tree
• urgent changes that should not wait to be merged in the external project first, such as fixes to security vulnerabilities.

Non-trivial changes to a module’s codebase, including changes in the module design or functionality should be discouraged, if the module has an upstream project repository. In that case, such changes shall be submitted to the upstream project, directly.

*Submitting changes to modules* describes in detail the process of contributing changes to module repositories.

**Contribution guidelines**

Contributing to Zephyr modules shall follow the generic project *Contribution guidelines*.

**Pull Requests:** may be merged with minimum of 2 approvals, including an approval by the PR assignee. In addition to this, pull requests in module repositories may only be merged if the introduced changes are verified with Zephyr CI tools, as described in more detail in other sections on this page.

The merging of pull requests in the main branch of a module repository must be coupled with the corresponding manifest file update in the zephyr main tree.

**Issue Reporting:** GitHub issues are intentionally disabled in module repositories, in favor of a centralized policy for issue reporting. Tickets concerning, for example, bugs or enhancements in modules shall be opened in the main zephyr repository. Issues should be appropriately labeled using GitHub labels corresponding to each module, where applicable.

**Note:** It is allowed to file bug reports for zephyr modules to track the corresponding upstream project bugs in Zephyr. These bug reports shall not affect the *Release Quality Criteria*.

### 2.10.4 Licensing requirements and policies

All source files in a module’s codebase shall include a license header, unless the module repository has **main license file** that covers source files that do not include license headers.

Main license files shall be added in the module’s codebase by Zephyr developers, only if they exist as part of the external project, and they contain a permissive OSI-compliant license. Main license files should preferably contain the full license text instead of including an SPDX license identifier. If multiple main license files are present it shall be made clear which license applies to each source file in a module’s codebase.

Individual license headers in module source files supersede the main license.

Any new content to be added in a module repository will require to have license coverage.
Note: Zephyr recommends conveying module licensing via individual license headers and main license files. This is not a hard requirement; should an external project have its own practice of conveying how licensing applies in the module's codebase (for example, by having a single or multiple main license files), this practice may be accepted by and be referred to in the Zephyr module, as long as licensing requirements, for example OSI compliance, are satisfied.

License policies

When creating a module repository a developer shall:

- import the main license files, if they exist in the external project, and
- document (for example in the module README or .yml file) the default license that covers the module's codebase.

License checks License checks (via CI tools) shall be enabled on every pull request that adds new content in module repositories.

2.10.5 Documentation requirements

All Zephyr module repositories shall include an .rst file documenting:

- the scope and the purpose of the module
- how the module integrates with Zephyr
- the owner of the module repository
- synchronization information with the external project (commit, SHA, version etc.)
- licensing information as described in Licensing requirements and policies.

The file shall be required for the inclusion of the module and the contained information should be kept up to date.

2.10.6 Testing requirements

All Zephyr modules should provide some level of integration testing, ensuring that the integration with Zephyr works correctly. Integration tests:

- may be in the form of a minimal set of samples and tests that reside in the zephyr main tree
- should verify basic usage of the module (configuration, functional APIs, etc.) that is integrated with Zephyr.
- shall be built and executed (for example in QEMU) as part of twister runs in pull requests that introduce changes in module repositories.

Note: New modules, that are candidates for being included in the Zephyr default manifest, shall provide some level of integration testing.

Note: Vendor HALs are implicitly tested via Zephyr tests built or executed on target platforms, so they do not need to provide integration tests.
The purpose of integration testing is not to provide functional verification of the module; this should be part of the testing framework of the external project.

Certain external projects provide test suites that reside in the upstream testing infrastructure but are written explicitly for Zephyr. These tests may (but are not required to) be part of the Zephyr test framework.

2.10.7 Deprecating and removing modules

Modules may be deprecated for reasons including, but not limited to:

- Lack of maintainership in the module
- Licensing changes in the external project
- Codebase becoming obsolete

The module information shall indicate whether a module is deprecated and the build system shall issue a warning when trying to build Zephyr using a deprecated module.

Deprecated modules may be removed from the Zephyr default manifest after 2 Zephyr releases.

Note: Repositories of removed modules shall remain accessible via their original URL, as they are required by older Zephyr versions.

2.10.8 Integrate modules in Zephyr build system

The build system variable ZEPHYR_MODULES is a CMake list of absolute paths to the directories containing Zephyr modules. These modules contain CMakeLists.txt and Kconfig files describing how to build and configure them, respectively. Module CMakeLists.txt files are added to the build using CMake's add_subdirectory() command, and the Kconfig files are included in the build's Kconfig menu tree.

If you have west installed, you don't need to worry about how this variable is defined unless you are adding a new module. The build system knows how to use west to set ZEPHYR_MODULES. You can add additional modules to this list by setting the EXTRA_ZEPHYR_MODULES CMake variable or by adding a EXTRA_ZEPHYR_MODULES line to .zephyrrc (See the section on Environment Variables for more details). This can be useful if you want to keep the list of modules found with west and also add your own.

Note: If the module FOO is provided by west but also given with -DEXTRA_ZEPHYR_MODULES=/<path>/foo then the module given by the command line variable EXTRA_ZEPHYR_MODULES will take precedence. This allows you to use a custom version of FOO when building and still use other Zephyr modules provided by west. This can for example be useful for special test purposes.

If you want to permanently add modules to the zephyr workspace and you are using zephyr as your manifest repository, you can also add a west manifest file into the submanifests directory. See submanifests/README.txt for more details.

See Basics for more on west workspaces.

Finally, you can also specify the list of modules yourself in various ways, or not use modules at all if your application doesn't need them.
2.10.9 Module yaml file description

A module can be described using a file named `zephyr/module.yml`. The format of `zephyr/module.yml` is described in the following:

Module name

Each Zephyr module is given a name by which it can be referred to in the build system. The name should be specified in the `zephyr/module.yml` file. This will ensure the module name is not changeable through user-defined directory names or `west` manifest files:

```
name: <name>
```

In CMake the location of the Zephyr module can then be referred to using the CMake variable `ZEPHYR_<MODULE_NAME>_MODULE_DIR` and the variable `ZEPHYR_<MODULE_NAME>_CMAKE_DIR` holds the location of the directory containing the module's `CMakeLists.txt` file.

**Note:** When used for CMake and Kconfig variables, all letters in module names are converted to uppercase and all non-alphanumeric characters are converted to underscores (_). As example, the module `foo-bar` must be referred to as `ZEPHYR_FOO_BAR_MODULE_DIR` in CMake and Kconfig.

Here is an example for the Zephyr module `foo`:

```
name: foo
```

**Note:** If the `name` field is not specified then the Zephyr module name will be set to the name of the module folder. As example, the Zephyr module located in `<workspace>/modules/bar` will use `bar` as its module name if nothing is specified in `zephyr/module.yml`.

Module integration files (in-module)

Inclusion of build files, `CMakeLists.txt` and `Kconfig`, can be described as:

```
build:
  cmake: <cmake-directory>
  kconfig: <directory>/Kconfig
```

The `cmake: <cmake-directory>` part specifies that `<cmake-directory>` contains the `CMakeLists.txt` to use. The `kconfig: <directory>/Kconfig` part specifies the `Kconfig` file to use. Neither is required: `cmake` defaults to `zephyr`, and `kconfig` defaults to `zephyr/Kconfig`.

Here is an example `module.yml` file referring to `CMakeLists.txt` and `Kconfig` files in the root directory of the module:

```
build:
  cmake: .
  kconfig: Kconfig
```

Sysbuild integration

`Sysbuild` is the Zephyr build system that allows for building multiple images as part of a single application, the sysbuild build process can be extended externally with modules as needed, for
example to add custom build steps or add additional targets to a build. Inclusion of sysbuild-specific build files, CMakeLists.txt and Kconfig, can be described as:

```yaml
build:
  sysbuild-cmake: <cmake-directory>
  sysbuild-kconfig: <directory>/Kconfig
```

The `sysbuild-cmake: <cmake-directory>` part specifies that `<cmake-directory>` contains the CMakeLists.txt to use. The `sysbuild-kconfig: <directory>/Kconfig` part specifies the Kconfig file to use.

Here is an example module.yml file referring to CMakeLists.txt and Kconfig files in the `sysbuild` directory of the module:

```yaml
build:
  sysbuild-cmake: sysbuild
  sysbuild-kconfig: sysbuild/Kconfig
```

The module description file zephyr/module.yml can also be used to specify that the build files, CMakeLists.txt and Kconfig, are located in a Module integration files (external).

Build files located in a MODULE_EXT_ROOT can be described as:

```yaml
build:
  sysbuild-cmake-ext: True
  sysbuild-kconfig-ext: True
```

This allows control of the build inclusion to be described externally to the Zephyr module.

**Build system integration**

When a module has a module.yml file, it will automatically be included into the Zephyr build system. The path to the module is then accessible through Kconfig and CMake variables.

**Zephyr modules** In both Kconfig and CMake, the variable ZEPHYR_<MODULE_NAME>_MODULE_DIR contains the absolute path to the module.

In CMake, ZEPHYR_<MODULE_NAME>_CMAKE_DIR contains the absolute path to the directory containing the CMakeLists.txt file that is included into CMake build system. This variable's value is empty if the module.yml file does not specify a CMakeLists.txt.

To read these variables for a Zephyr module named foo:

- In CMake: use `${ZEPHYR_FOO_MODULE_DIR}` for the module's top level directory, and `${ZEPHYR_FOO_CMAKE_DIR}` for the directory containing its CMakeLists.txt
- In Kconfig: use `${ZEPHYR_FOO_MODULE_DIR}` for the module's top level directory

Notice how a lowercase module name foo is capitalized to FOO in both CMake and Kconfig.

These variables can also be used to test whether a given module exists. For example, to verify that foo is the name of a Zephyr module:

```cmake
if(ZEPHYR_FOO_MODULE_DIR)
  # Do something if FOO exists.
endif()
```

In Kconfig, the variable may be used to find additional files to include. For example, to include the file some/Kconfig in module foo:

```cmake
source "$(ZEPHYR_FOO_MODULE_DIR)/some/Kconfig"
```

During CMake processing of each Zephyr module, the following variables are also available:
• the current module's name: `${ZEPHYR_CURRENT_MODULE_NAME}`
• the current module's top level directory: `${ZEPHYR_CURRENT_MODULE_DIR}`
• the current module's CMakeLists.txt directory: `${ZEPHYR_CURRENT_CMAKE_DIR}`

This removes the need for a Zephyr module to know its own name during CMake processing. The module can source additional CMake files using these CURRENT variables. For example:

```cmake
include(${ZEPHYR_CURRENT_MODULE_DIR}/cmake/code.cmake)
```

It is possible to append values to a Zephyr CMake list variable from the module's first CMakeLists.txt file. To do so, append the value to the list and then set the list in the PARENT_SCOPE of the CMakeLists.txt file. For example, to append bar to the FOO_LIST variable in the Zephyr CMakeLists.txt scope:

```cmake
list(APPEND FOO_LIST bar)
set(FOO_LIST ${FOO_LIST} PARENT_SCOPE)
```

An example of a Zephyr list where this is useful is when adding additional directories to the SYSCALL_INCLUDE_DIRS list.

Sysbuild modules In both Kconfig and CMake, the variable SYSBUILD_CURRENT_MODULE_DIR contains the absolute path to the sysbuild module. In CMake, SYSBUILD_CURRENT_CMAKE_DIR contains the absolute path to the directory containing the CMakeLists.txt file that is included into CMake build system. This variable's value is empty if the module.yml file does not specify a CMakeLists.txt.

To read these variables for a sysbuild module:

- In CMake: use `${SYSBUILD_CURRENT_MODULE_DIR}` for the module's top level directory, and `${SYSBUILD_CURRENT_CMAKE_DIR}` for the directory containing its CMakeLists.txt
- In Kconfig: use `${SYSBUILD_CURRENT_MODULE_DIR}` for the module's top level directory

In Kconfig, the variable may be used to find additional files to include. For example, to include the file some/Kconfig:

```kconfig
source "${SYSBUILD_CURRENT_MODULE_DIR}/some/Kconfig"
```

The module can source additional CMake files using these variables. For example:

```cmake
include(${SYSBUILD_CURRENT_MODULE_DIR}/cmake/code.cmake)
```

It is possible to append values to a Zephyr CMake list variable from the module's first CMakeLists.txt file. To do so, append the value to the list and then set the list in the PARENT_SCOPE of the CMakeLists.txt file. For example, to append bar to the FOO_LIST variable in the Zephyr CMakeLists.txt scope:

```cmake
list(APPEND FOO_LIST bar)
set(FOO_LIST ${FOO_LIST} PARENT_SCOPE)
```

Sysbuild modules hooks Sysbuild provides an infrastructure which allows a sysbuild module to define a function which will be invoked by sysbuild at a pre-defined point in the CMake flow.

Functions invoked by sysbuild:

- `<module-name>_pre_cmake(IMAGES <images>): This function is called for each sysbuild module before CMake configure is invoked for all images.
- `<module-name>_post_cmake(IMAGES <images>): This function is called for each sysbuild module after CMake configure has completed for all images.
• `<module-name>_pre_domains(IMAGES <images>): This function is called for each sysbuild module before domains yaml is created by sysbuild.
• `<module-name>_post_domains(IMAGES <images>): This function is called for each sysbuild module after domains yaml has been created by sysbuild.

arguments passed from sysbuild to the function defined by a module:

• `<images>` is the list of Zephyr images that will be created by the build system.

If a module foo want to provide a post CMake configure function, then the module's sysbuild CMakeLists.txt file must define function foo_post_cmake().

To facilitate naming of functions, the module name is provided by sysbuild CMake through the SYSBUILD_CURRENT_MODULE_NAME CMake variable when loading the module's sysbuild CMakeLists.txt file.

Example of how the foo sysbuild module can define foo_post_cmake():

```cmake
function(${SYSBUILD_CURRENT_MODULE_NAME}_post_cmake)
  cmake_parse_arguments(POST_CMAKE "" "" "" IMAGES ${ARGN})
  message("Invoking ${CMAKE_CURRENT_FUNCTION}. Images: ${POST_CMAKE_IMAGES}")
endfunction()
```

Zephyr module dependencies

A Zephyr module may be dependent on other Zephyr modules to be present in order to function correctly. Or it might be that a given Zephyr module must be processed after another Zephyr module, due to dependencies of certain CMake targets.

Such a dependency can be described using the depends field.

```cmake
build:
  depends:
    - <module>
```

Here is an example for the Zephyr module foo that is dependent on the Zephyr module bar to be present in the build system:

```cmake
name: foo
build:
  depends:
    - bar
```

This example will ensure that bar is present when foo is included into the build system, and it will also ensure that bar is processed before foo.

Module integration files (external)

Module integration files can be located externally to the Zephyr module itself. The MODULE_EXT_ROOT variable holds a list of roots containing integration files located externally to Zephyr modules.

Module integration files in Zephyr

The Zephyr repository contain CMakeLists.txt and Kconfig build files for certain known Zephyr modules.

Those files are located under
**Module integration files in a custom location**  You can create a similar MODULE_EXT_ROOT for additional modules, and make those modules known to Zephyr build system.

Create a MODULE_EXT_ROOT with the following structure:

```
<MODULE_EXT_ROOT>
  └── modules
      └── <module_name>
          ├── CMakeLists.txt
          └── Kconfig
```

and then build your application by specifying -DMODULE_EXT_ROOT parameter to the CMake build system. The MODULE_EXT_ROOT accepts a CMake list of roots as argument.

A Zephyr module can automatically be added to the MODULE_EXT_ROOT list using the module description file `zephyr/module.yml`, see [Build settings](https://zephyrproject.org/docs/zhzhhes/_modules/external).

**Note:** ZEPHYR_BASE is always added as a MODULE_EXT_ROOT with the lowest priority. This allows you to overrule any integration files under `<ZEPHYR_BASE>/modules/<module_name>` with your own implementation your own MODULE_EXT_ROOT.

The `modules.cmake` file must contain the logic that specifies the integration files for Zephyr modules via specifically named CMake variables.

To include a module's CMake file, set the variable ZEPHYR_<_MODULE_NAME>_<CMAKE_DIR> to the path containing the CMake file.

To include a module's Kconfig file, set the variable ZEPHYR_<_MODULE_NAME>_KCONFIG to the path to the Kconfig file.

The following is an example on how to add support the FOO module.

Create the following structure:

```
<MODULE_EXT_ROOT>
  └── modules
      └── modules.cmake
          └── foo
              ├── CMakeLists.txt
              └── Kconfig
```

and inside the `modules.cmake` file, add the following content:

```
set(ZEPHYR_FOO_CMAKE_DIR ${CMAKE_CURRENT_LIST_DIR}/foo)
set(ZEPHYR_FOO_KCONFIG ${CMAKE_CURRENT_LIST_DIR}/foo/Kconfig)
```

**Module integration files (zephyr/module.yml)**  The module description file `zephyr/module.yml` can be used to specify that the build files, CMakeLists.txt and Kconfig, are located in a Module integration files (external).

Build files located in a MODULE_EXT_ROOT can be described as:
This allows control of the build inclusion to be described externally to the Zephyr module. The Zephyr repository itself is always added as a Zephyr module ext root.

**Build settings**

It is possible to specify additional build settings that must be used when including the module into the build system.

All root settings are relative to the root of the module.

Build settings supported in the `module.yml` file are:

- `board_root`: Contains additional boards that are available to the build system. Additional boards must be located in a `<board_root>/boards` folder.
- `dts_root`: Contains additional dts files related to the architecture/soc families. Additional dts files must be located in a `<dts_root>/dts` folder.
- `snippet_root`: Contains additional snippets that are available for use. These snippets must be defined in `snippet.yml` files underneath the `<snippet_root>/snippets` folder. For example, if you have `snippet_root: foo`, then you should place your module's `snippet.yml` files in `<your-module>/foo/snippets` or any nested subdirectory.
- `soc_root`: Contains additional SoCs that are available to the build system. Additional SoCs must be located in a `<soc_root>/soc` folder.
- `arch_root`: Contains additional architectures that are available to the build system. Additional architectures must be located in a `<arch_root>/arch` folder.
- `module_ext_root`: Contains CMakeLists.txt and Kconfig files for Zephyr modules, see also Module integration files (external).
- `sca_root`: Contains additional SCA tool implementations available to the build system. Each tool must be located in `<sca_root>/sca/<tool>` folder. The folder must contain a `sca.cmake`.

Example of a `module.yml` file containing additional roots, and the corresponding file system layout.

```yaml
build:
  settings:
    board_root: .
    dts_root: .
    soc_root: .
    arch_root: .
    module_ext_root: .
```

requires the following folder structure:

```
<zephyr-module-root>
  ├── arch
  │   └── boards
  │       └── dts
  ├── modules
  └── soc
```
Twister (Test Runner)

To execute both tests and samples available in modules, the Zephyr test runner (twister) should be pointed to the directories containing those samples and tests. This can be done by specifying the path to both samples and tests in the `zephyr/module.yml` file. Additionally, if a module defines out of tree boards, the module file can point twister to the path where those files are maintained in the module. For example:

```yaml
build:
  cmake: .
samples:
  - samples
tests:
  - tests
boards:
  - boards
```

Binary Blobs

Zephyr supports fetching and using binary blobs, and their metadata is contained entirely in `zephyr/module.yml`. This is because a binary blob must always be associated with a Zephyr module, and thus the blob metadata belongs in the module’s description itself.

Binary blobs are fetched using `west blobs`. If `west` is not used, they must be downloaded and verified manually.

The `blobs` section in `zephyr/module.yml` consists of a sequence of maps, each of which has the following entries:

- **path**: The path to the binary blob, relative to the `zephyr/blobs/` folder in the module repository
- **sha256**: SHA-256 checksum of the binary blob file
- **type**: The type of binary blob. Currently limited to `img` or `lib`
- **version**: A version string
- **license-path**: Path to the license file for this blob, relative to the root of the module repository
- **url**: URL that identifies the location the blob will be fetched from, as well as the fetching scheme to use
- **description**: Human-readable description of the binary blob
- **doc-url**: A URL pointing to the location of the official documentation for this blob

Module Inclusion

**Using West** If west is installed and `ZEPHYR_MODULES` is not already set, the build system finds all the modules in your `west installation` and uses those. It does this by running `west list` to get the paths of all the projects in the installation, then filters the results to just those projects which have the necessary module metadata files.

Each project in the `west list` output is tested like this:

- If the project contains a file named `zephyr/module.yml`, then the content of that file will be used to determine which files should be added to the build, as described in the previous section.
• Otherwise (i.e. if the project has no `zephyr/module.yml`), the build system looks for `zephyr/CMakeLists.txt` and `zephyr/Kconfig` files in the project. If both are present, the project is considered a module, and those files will be added to the build.

• If neither of those checks succeed, the project is not considered a module, and is not added to `ZEPHYR_MODULES`.

**Without West** If you don’t have west installed or don’t want the build system to use it to find Zephyr modules, you can set `ZEPHYR_MODULES` yourself using one of the following options. Each of the directories in the list must contain either a `zephyr/module.yml` file or the files `zephyr/CMakeLists.txt` and `Kconfig`, as described in the previous section.

1. At the CMake command line, like this:

   ```
cmake -DZEPHYR_MODULES=<path-to-module1>;[<path-to-module2>][...] ...
   ```

2. At the top of your application’s top level `CMakeLists.txt`, like this:

   ```
   set(ZEPHYR_MODULES <path-to-module1> <path-to-module2> [...])
   find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})
   ```

   If you choose this option, make sure to set the variable before calling `find_package(Zephyr ...)` as shown above.

3. In a separate CMake script which is pre-loaded to populate the CMake cache, like this:

   ```
   # Put this in a file with a name like "zephyr-modules.cmake"
   set(ZEPHYR_MODULES <path-to-module1> <path-to-module2>
   CACHE STRING "pre-cached modules")
   ```

   You can tell the build system to use this file by adding `-C zephyr-modules.cmake` to your CMake command line.

**Not using modules** If you don’t have west installed and don’t specify `ZEPHYR_MODULES` yourself, then no additional modules are added to the build. You will still be able to build any applications that don’t require code or Kconfig options defined in an external repository.

### 2.10.10 Submitting changes to modules

When submitting new or making changes to existing modules the main repository Zephyr needs a reference to the changes to be able to verify the changes. In the main tree this is done using revisions. For code that is already merged and part of the tree we use the commit hash, a tag, or a branch name. For pull requests however, we require specifying the pull request number in the revision field to allow building the zephyr main tree with the changes submitted to the module.

To avoid merging changes to master with pull request information, the pull request should be marked as DNM (Do Not Merge) or preferably a draft pull request to make sure it is not merged by mistake and to allow for the module to be merged first and be assigned a permanent commit hash. Drafts reduce noise by not automatically notifying anyone until marked as “Ready for review”. Once the module is merged, the revision will need to be changed either by the submitter or by the maintainer to the commit hash of the module which reflects the changes.

Note that multiple and dependent changes to different modules can be submitted using exactly the same process. In this case you will change multiple entries of all modules that have a pull request against them.
Process for submitting a new module

Please follow the process in Submission and review process and obtain the TSC approval to integrate the external source code as a module.

If the request is approved, a new repository will be created by the project team and initialized with basic information that would allow submitting code to the module project following the project contribution guidelines.

If a module is maintained as a fork of another project on Github, the Zephyr module related files and changes in relation to upstream need to be maintained in a special branch named `zephyr`

Maintainers from the Zephyr project will create the repository and initialize it. You will be added as a collaborator in the new repository. Submit the module content (code) to the new repository following the guidelines described here, and then add a new entry to the `west.yml` with the following information:

```
- name: <name of repository>
  path: <path to where the repository should be cloned>
  revision: <ref pointer to module pull request>
```

For example, to add `my_module` to the manifest:

```
- name: my_module
  path: modules/lib/my_module
  revision: pull/23/head
```

Where 23 in the example above indicated the pull request number submitted to the `my_module` repository. Once the module changes are reviewed and merged, the revision needs to be changed to the commit hash from the module repository.

Process for submitting changes to existing modules

1. Submit the changes using a pull request to an existing repository following the contribution guidelines and expectations.

2. Submit a pull request changing the entry referencing the module into the `west.yml` of the main Zephyr tree with the following information:

```
- name: <name of repository>
  path: <path to where the repository should be cloned>
  revision: <ref pointer to module pull request>
```

For example, to add `my_module` to the manifest:

```
- name: my_module
  path: modules/lib/my_module
  revision: pull/23/head
```

Where 23 in the example above indicated the pull request number submitted to the `my_module` repository. Once the module changes are reviewed and merged, the revision needs to be changed to the commit hash from the module repository.

2.11 West (Zephyr’s meta-tool)

The Zephyr project includes a swiss-army knife command line tool named west. West is developed in its own repository.

---

1 Zephyr is an English name for the Latin Zephyrus, the ancient Greek god of the west wind.
West's built-in commands provide a multiple repository management system with features inspired by Google's Repo tool and Git submodules. West is also “pluggable”: you can write your own west extension commands which add additional features to west. Zephyr uses this to provide conveniences for building applications, flashing and debugging them, and more.

Like git and docker, the top-level west command takes some common options, a sub-command to run, and then options and arguments for that sub-command:

```
west [common-opts] <command> [opts] <args>
```

Since west v0.8, you can also run west like this:

```
python3 -m west [common-opts] <command> [opts] <args>
```

You can run `west --help` (or `west -h` for short) to get top-level help for available west commands, and `west <command> -h` for detailed help on each command.

### 2.11.1 Installing west

West is written in Python 3 and distributed through PyPI. Use pip3 to install or upgrade west:

On Linux:

```
pip3 install --user -U west
```

On Windows and macOS:

```
pip3 install -U west
```

**Note:** See *Python and pip* for additional clarification on using the `--user` switch.

Afterwards, you can run `pip3 show -f west` for information on where the west binary and related files were installed.

Once west is installed, you can use it to clone the Zephyr repositories.

### Structure

West's code is distributed via PyPI in a Python package named west. This distribution includes a launcher executable, which is also named west (or west.exe on Windows).

When west is installed, the launcher is placed by pip3 somewhere in the user's filesystem (exactly where depends on the operating system, but should be on the PATH *environment variable*). This launcher is the command-line entry point to running both built-in commands like west init, west update, along with any extensions discovered in the workspace.

In addition to its command-line interface, you can also use west's Python APIs directly. See west-apis for details.

### Enabling shell completion

West currently supports shell completion in the following combinations of platform and shell:

- Linux: bash
- macOS: bash
- Windows: not available
In order to enable shell completion, you will need to obtain the corresponding completion script and have it sourced every time you enter a new shell session.

To obtain the completion script you can use the `west completion` command:

```bash
cd /path/to/zephyr/
west completion bash > ~/west-completion.bash
```

**Note:** Remember to update your local copy of the completion script using `west completion` when you update Zephyr.

Next, you need to import `west-completion.bash` into your bash shell.

On Linux, you have the following options:

- Copy `west-completion.bash` to `/etc/bash_completion.d/`.
- Copy `west-completion.bash` to `/usr/share/bash-completion/completions/`.
- Copy `west-completion.bash` to a local folder and source it from your `~/.bashrc`.

On macOS, you have the following options:

- Copy `west-completion.bash` to a local folder and source it from your `~/.bash_profile`.
- Install the `bash-completion` package with `brew`:
  ```bash
  brew install bash-completion
  ```
  then source the main bash completion script in your `~/.bash_profile`:
  ```bash
  source /usr/local/etc/profile.d/bash_completion.sh
  ```
  and finally copy `west-completion.bash` to `/usr/local/etc/bash_completion.d/`.

### 2.11.2 West Release Notes

#### v1.2.0

Major changes:

- New `west grep` command for running a "grep tool" in your west workspace's repositories. Currently, `git grep`, `ripgrep`, and standard `grep` are supported grep tools.

To run this command to get `git grep foo` results from all cloned, active repositories, run:

```
west grep foo
```

Here are some other examples for running different grep commands with `west grep`:

```bash
<table>
<thead>
<tr>
<th>Command</th>
<th>Command</th>
<th>Command</th>
</tr>
</thead>
<tbody>
<tr>
<td>git grep --untracked</td>
<td>west grep --untracked foo</td>
<td>west grep --tool ripgrep foo</td>
</tr>
<tr>
<td>ripgrep</td>
<td>west grep --tool ripgrep foo</td>
<td>west grep --tool grep foo</td>
</tr>
<tr>
<td>grep --recursive</td>
<td>west grep --tool grep foo</td>
<td>west config grep.tool ripgrep</td>
</tr>
<tr>
<td></td>
<td></td>
<td>west config grep.tool grep</td>
</tr>
</tbody>
</table>
```

To switch the default grep tool in your workspace, run the appropriate command in this table:
For more details, run `west help grep`.

Other changes:

- The manifest file format now supports a description field in each `projects`: element. See `Projects` for examples.
- `west list` --format now accepts `{description}` in the format string, which prints the project's description: value.
- `west compare` now always prints information about `The manifest-rev branch`.

Bug fixes:

- `west init` aborts if the destination directory already exists.

API changes:

- `west.commands.WestCommand` methods `check_call()` and `check_output()` now take any kwargs that can be passed on to the underlying subprocess function.
- `west.commands.WestCommand.run_subprocess()`: new wrapper around `subprocess.run()`. This could not be named `run()` because `WestCommand` already had a method by this name.
- `west.commands.WestCommand` methods `dbg()`, `inf()`, `wrn()`, and `err()` now all take an end kwarg, which is passed on to the call to `print()`.
- `west.manifest.Project` now has a description attribute, which contains the parsed value of the description: field in the manifest data.

v1.1.0

Major changes:

- `west compare`: new command that compares the state of the workspace against the manifest.
- Support for a new `manifest.project-filter` configuration option. See `Built-in Configuration Options` for details. The `west manifest --freeze` and `west manifest --resolve` commands currently cannot be used when this option is set. This restriction can be removed in a later release.
- Project names which contain comma (,) or whitespace now generate warnings. These warnings are errors if the new `manifest.project-filter` configuration option is set. The warnings may be promoted to errors in a future major version of west.

Other changes:

- `west forall` now takes a --group argument that can be used to restrict the command to only run in one or more groups. Run `west help forall` for details.
- All west commands will now output log messages from west API modules at warning level or higher. In addition, the --verbose argument to west can be used once to include informational messages, or twice to include debug messages, from all commands.

Bug fixes:

- Various improvements to error messages, debug logging, and error handling.

API changes:

- `west.manifest.Manifest.is_active()` now respects the `manifest.project-filter configuration option's value.`
v1.0.1

Major changes:
- Manifest schema version “1.0” is now available for use in this release. This is identical to the “0.13” schema version in terms of features, but can be used by applications that do not wish to use a “0.x” manifest “version:” field. See Version for details on this feature.

Bug fixes:
- West no longer exits with a successful error code when sent an interrupt signal. Instead, it exits with a platform-specific error code and signals to the calling environment that the process was interrupted.

v1.0.0

Major changes in this release:
- The west-apis are now declared stable. Any breaking changes will be communicated by a major version bump from v1.x.y to v2.x.y.
- West v1.0 no longer works with the Zephyr v1.14 LTS releases. This LTS has long been obsoleted by Zephyr v2.7 LTS. If you need to use Zephyr v1.14, you must use west v0.14 or earlier.
- Like the rest of Zephyr, west now requires Python v3.8 or later
- West commands no longer accept abbreviated command line arguments. For example, you must now specify west update --keep-descendants instead of using an abbreviation like west update --keep-d. This is part of a change applied to all of Zephyr's Python scripts' command-line interfaces. The abbreviations were causing problems in practice when commands were updated to add new options with similar names but different behavior to existing ones.

Other changes:
- All built-in west functions have stopped using west.log
- west update: new --submodule-init-config option. See commit 9ba92b05 for details.

Bug fixes:
- West extension commands that failed to load properly sometimes dumped stack. This has been fixed and west now prints a sensible error message in this case.
- west config now fails on malformed configuration option arguments which lack a . in the option name

API changes:
- The west package now contains the metadata files necessary for some static analyzers (such as mypy) to auto-detect its type annotations. See commit d9f00e24 for details.
- the deprecated west.build module used for Zephyr v1.14 LTS compatibility was removed
- the deprecated west.cmake module used for Zephyr v1.14 LTS compatibility was removed
- the west.log module is now deprecated. This module uses global state, which can make it awkward to use it as an API which multiple different python modules may rely on.
- The west-apis-commands module got some new APIs which lay groundwork for a future change to add a global verbosity control to a command's output, and work to remove global state from the west package's API:
  - New west.commands.WestCommand.__init__() keyword argument: verbosity
  - New west.commands.WestCommand property: color_ui
- New `west.commands.WestCommand` methods, which should be used to print output from extension commands instead of writing directly to `sys.stdout` or `sys.stderr`: `inf()`, `wrn()`, `err()`, `die()`, `banner()`, `small_banner()`

- New `west.commands.VERBOSITY` enum

v0.14.0

Bug fixes:

- West commands that were run with a bad local configuration file dumped stack in a confusing way. This has been fixed and west now prints a sensible error message in this case.

- A bug in the way west looks for the zephyr repository was fixed. The bug itself usually appeared when running an extension command like `west build` in a new workspace for the first time; this used to fail (just for the first time, not on subsequent command invocations) unless you ran the command in the workspace's top level directory.

- West now prints sensible error messages when the user lacks permission to open the manifest file instead of dumping stack traces.

API changes:

- The `west.manifest.MalformedConfig` exception type has been moved to the `west.configuration` module

v0.13.1

Bug fix:

- When calling `west.manifest.Manifest.from_file()` when outside of a workspace, west again falls back on the ZEPHYR_BASE environment variable to locate the workspace.

v0.13.0

New features:

- You can now associate arbitrary user data with the manifest repository itself in the manifest: `self: userdata: value`, like so:

  ```yaml
  manifest:
  self:
    userdata: <any YAML value can go here>
  ```

Bug fixes:

- The path to the manifest repository reported by west could be incorrect in certain circumstances detailed in [issue #572](https://github.com/zephyrproject-rtos/west/issues/572). This has been fixed as part of a larger overhaul of path handling support in the `west.manifest` API module.

- The `west.Manifest.ManifestProject.__repr__` return value was fixed

API changes:
**west.configuration.Configuration**: new object-oriented interface to the current configuration. This reflects the system, global, and workspace-local configuration values, and allows you to read, write, and delete configuration options from any or all of these locations.

**west.commands.WestCommand**:
- `config`: new attribute, returns a `Configuration` object or aborts the program if none is set. This is always usable from within extension command `do_run()` implementations.
- `has_config`: new boolean attribute, which is True if and only if reading `self.config` will abort the program.

The path handling in the `west.manifest` package has been overhauled in a backwards-incompatible way. For more details, see commit [56cfe8d1d1](https://github.com/zephyrproject-rtos/west/commit/56cfe8d1d1f3c9b45de3e793c738acd62db52aca).

**west.manifest.Manifest.validate()**: this now returns the validated data as a Python dict. This can be useful if the value passed to this function was a str, and the dict is desired.

**west.manifest.Manifest**: new:
- `path` attributes: `abspath`, `posixpath`, `relative_path`, `yaml_path`, `repo_path`, `repo_posixpath`;
- `userdata` attribute, which contains the parsed value from `manifest: self: userdata`, or is None
- `from_topdir()` factory method

**west.manifest.ManifestProject**: new `userdata` attribute, which also contains the parsed value from `manifest: self: userdata`, or is None

**west.manifest.ManifestImportFailed**: the constructor can now take any value; this can be used to reflect failed imports from a `map` or other compound value.

**Deprecated configuration APIs**:
The following APIs are now deprecated in favor of using a `Configuration` object. Usually this will be done via `self.config` from a `WestCommand` instance, but this can be done directly by instantiating a `Configuration` object for other usages.
- `west.configuration.config`
- `west.configuration.read_config`
- `west.configuration.update_config`
- `west.configuration.delete_config`

**v0.12.0**

New features:
- West now works on the MSYS2 platform.
- West manifest files can now contain arbitrary user data associated with each project. See `Repository user data` for details.

Bug fixes:
- The `west list` command's `{sha}` format key has been fixed for the manifest repository; it now prints N/A (“not applicable”) as expected.

API changes:
- The `west.manifest.Project.userdata` attribute was added to support project user data.
v0.11.1

New features:

- west status now only prints output for projects which have a nonempty status.

Bug fixes:

- The manifest file parser was incorrectly allowing project names which contain the path separator characters / and \. These invalid characters are now rejected.

Note: if you need to place a project within a subdirectory of the workspace todir, use the path: key. If you need to customize a project's fetch URL relative to its remote url-base:, use repo-path:. See Projects for examples.

- The changes made in west v0.10.1 to the west init --manifest-rev option which selected the default branch name were leaving the manifest repository in a detached HEAD state. This has been fixed by using git clone internally instead of git init and git fetch. See issue #522 for details.

- The WEST_CONFIG_LOCAL environment variable now correctly overrides the default location, <workspace todir>/.west/config.

- west update --fetch=smart (smart is the default) now correctly skips fetches for project revisions which are lightweight tags (it already worked correctly for annotated tags; only lightweight tags were unnecessarily fetched).

Other changes:

- The fix for issue #522 mentioned above introduces a new restriction. The west init --manifest-rev option value, if given, must now be either a branch or a tag. In particular, “pseudo-branches” like GitHub's pull/1234/head references which could previously be used to fetch a pull request can no longer be passed to --manifest-rev. Users must now fetch and check out such revisions manually after running west init.

API changes:

- west.manifest.Manifest.get_projects() avoids incorrect results in some edge cases described in issue #523.

- west.manifest.Project.sha() now works correctly for tag revisions. (This applies to both lightweight and annotated tags.)

v0.11.0

New features:

- west update now supports --narrow, --name-cache, and --path-cache options. These can be influenced by the update.narrow, update.name-cache, and update.path-cache Configuration options. These can be used to optimize the speed of the update.

- west update now supports a --fetch-opt option that will be passed to the git fetch command used to fetch remote revisions when updating each project.

Bug fixes:

- west update now synchronizes Git submodules in projects by default. This avoids issues if the URL changes in the manifest file from when the submodule was first initialized. This behavior can be disabled by setting the update.sync-submodules configuration option to false.

Other changes:

- the west-apis-manifest module has fixed docstrings for the Project class
v0.10.1

New features:

- The `west init` command's `--manifest-rev (--mr)` option no longer defaults to `master`. Instead, the command will query the repository for its default branch name and use that instead. This allows users to move from `master` to `main` without breaking scripts that do not provide this option.

v0.10.0

New features:

- The `name` key in a project's `submodules list` is now optional.

Bug fixes:

- West now checks that the manifest schema version is one of the explicitly allowed values documented in `Version`. The old behavior was just to check that the schema version was newer than the west version where the `manifest: version:` key was introduced. This incorrectly allowed invalid schema versions, like `0.8.2`.

Other changes:

- A manifest file's `group-filter` is now propagated through an `import`. This is a change from how `west v0.9.x` handled this. In `west v0.9.x`, only the top level manifest file's `group-filter` had any effect; the group filter lists from any imported manifests were ignored.

Starting with `west v0.10.0`, the group filter lists from imported manifests are also imported. For details, see `Group Filters and Imports`.

The new behavior will take effect if `manifest: version:` is not given or is at least `0.10`. The old behavior is still available in the top level manifest file only with an explicit `manifest: version: 0.9`. See `Version` for more information on schema versions.

See `west pull request #482` for the motivation for this change and additional context.

v0.9.1

Bug fixes:

- Commands like `west manifest --resolve` now correctly include group and group filter information.

Other changes:

- `west` now warns if you combine `import` with `group-filter`. Semantics for this combination have changed starting with `v0.10.x`. See the `v0.10.0` release notes above for more information.

v0.9.0

**Warning:** The `west config` fix described below comes at a cost: any comments or other manual edits in configuration files will be removed when setting a configuration option via that command or the `west.configuration` API.
Warning: Combining the group-filter feature introduced in this release with manifest imports is discouraged. The resulting behavior has changed in west v0.10.

New features:

- West manifests now support *Git Submodules in Projects*. This allows you to clone *Git submodules* into a west project repository in addition to the project repository itself.
- West manifests now support *Project Groups*. Project groups can be enabled and disabled to determine what projects are “active”, and therefore will be acted upon by the following commands: west update, west list, west diff, west status, west forall.
- west update no longer updates inactive projects by default. It now supports a --group-filter option which allows for one-time modifications to the set of enabled and disabled project groups.
- Running west list, west diff, west status, or west forall with no arguments does not print information for inactive projects by default. If the user specifies a list of projects explicitly at the command line, output for them is included regardless of whether they are active.
  These commands also now support --all arguments to include all projects, even inactive ones.
- west list now supports a \{groups\} format string key in its --format argument.

Bug fixes:

- The west config command and west.configuration API did not correctly store some configuration values, such as strings which contain commas. This has been fixed; see commit 36f3f91e for details.
- A manifest file with an empty manifest: self: path: value is invalid, but west used to let it pass silently. West now rejects such manifests.
- A bug affecting the behavior of the west init -l . command was fixed; see issue #435.

API changes:

- added west.manifest.Manifest.is_active()
- added west.manifest.Manifest.group_filter
- added submodules attribute to west.manifest.Project, which has newly added type west.manifest.Submodule

Other changes:

- The Manifest Imports feature now supports the terms allowlist and blocklist instead of whitelist and blacklist, respectively.
  The old terms are still supported for compatibility, but the documentation has been updated to use the new ones exclusively.

v0.8.0

This is a feature release which changes the manifest schema by adding support for a path-prefix: key in an import: mapping, along with some other features and fixes.

- Manifest import mappings now support a path-prefix: key, which places the project and its imported repositories in a subdirectory of the workspace. See Example 3.4: Import into a subdirectory for an example.
The west command line application can now also be run using `python3 -m west`. This makes it easier to run west under a particular Python interpreter without modifying the `PATH` environment variable.

- **west manifest --path** prints the absolute path to `west.yml`
- **west init** now supports an `--mf foo.yml` option, which initializes the workspace using `foo.yml` instead of `west.yml`.
- **west list** now prints the manifest repository's path using the `manifest.path` configuration option, which may differ from the `self: path: value` in the manifest data. The old behavior is still available, but requires passing a new `--manifest-path-from-yaml` option.
- Various Python API changes; see `west-apis` for details.

**v0.7.3**

This is a bugfix release.

- Fix an error where a failed import could leave the workspace in an unusable state (see [PR #415](https://github.com/zephyrproject-rtos/west/pull/415) for details)

**v0.7.2**

This is a bugfix and minor feature release.

- Filter out duplicate extension commands brought in by manifest imports
- Fix `west.Manifest.get_projects()` when finding the manifest repository by path

**v0.7.1**

This is a bugfix and minor feature release.

- **west update --stats** now prints timing for operations which invoke a subprocess, time spent in west's Python process for each project, and total time updating each project.
- **west topdir** always prints a POSIX style path
- minor console output changes

**v0.7.0**

The main user-visible feature in west 0.7 is the Manifest Imports feature. This allows users to load `west` manifest data from multiple different files, resolving the results into a single logical manifest.

Additional user-visible changes:

- The idea of a “west installation” has been renamed to “west workspace” in this documentation and in the west API documentation. The new term seems to be easier for most people to work with than the old one.
- West manifests now support a schema version.
- The “west config” command can now be run outside of a workspace, e.g. to run `west config --global section.key value` to set a configuration option's value globally.
- There is a new `west topdir` command, which prints the root directory of the current west workspace.
• The `west init` command now prints the git operations being performed, and their results.

• The restriction that no project can be named “manifest” is now enforced; the name “manifest” is reserved for the manifest repository, and is usable as such in commands like `west list manifest`, instead of `west list path-to-manifest-repository` being the only way to say that

• It’s no longer an error if there is no project named “zephyr”. This is part of an effort to make west generally usable for non-Zephyr use cases.

• Various bug fixes.

The developer-visible changes to the west-apis are:

• `west.build` and `west.cmake`: deprecated; this is Zephyr-specific functionality and should never have been part of west. Since Zephyr v1.14 LTS relies on it, it will continue to be included in the distribution, but will be removed when that version of Zephyr is obsoleted.

• `west.commands`:
  – `WestCommand.requires_installation`: deprecated; use `requires_workspace` instead
  – `WestCommand.requires_workspace`: new
  – `WestCommand.has_manifest`: new
  – `WestCommand.manifest`: this is now settable

• `west.configuration`: callers can now identify the workspace directory when reading and writing configuration files

• `west.log`:
  – `msg()`: new

• `west.manifest`:
  – The module now uses the standard logging module instead of `west.log`
  – `QUAL_REFS_WEST`: new
  – `SCHEMA_VERSION`: new
  – Defaults: removed
  – `Manifest.as_dict()`: new
  – `Manifest.as_frozen_yaml()`: new
  – `Manifest.as_yaml()`: new
  – `Manifest.from_file()` and `from_data()`: these factory methods are more flexible to use and less reliant on global state
  – `Manifest.validate()`: new
  – `ManifestImportFailed`: new
  – `ManifestProject`: semi-deprecated and will likely be removed later.
  – `Project`: the constructor now takes a `topdir` argument
  – `Project.format()` and its callers are removed. Use f-strings instead.
  – `Project.name_and_path`: new
  – `Project.remote_name`: new
  – `Project.sha()` now captures stderr
  – Remote: removed
West now requires Python 3.6 or later. Additionally, some features may rely on Python dictionaries being insertion-ordered; this is only an implementation detail in CPython 3.6, but it is part of the language specification as of Python 3.7.

v0.6.3

This point release fixes an error in the behavior of the deprecated `west.cmake` module.

v0.6.2

This point release fixes an error in the behavior of `west update --fetch=smart`, introduced in v0.6.1.

All v0.6.1 users must upgrade.

v0.6.1

**Warning:** Do not use this point release. Make sure to use v0.6.2 instead.

The user-visible features in this point release are:

- The `west update` command has a new `--fetch` command line flag and `update.fetch` configuration option. The default value, “smart”, skips fetching SHAs and tags which are available locally.

- Better and more consistent error-handling in the `west diff`, `west status`, `west forall`, and `west update` commands. Each of these commands can operate on multiple projects; if a subprocess related to one project fails, these commands now continue to operate on the rest of the projects. All of them also now report a nonzero error code from the west process if any of these subprocesses fails (this was previously not true of `west forall` in particular).

- The `west manifest` command also handles errors better.

- The `west list` command now works even when the projects are not cloned, as long as its format string only requires information which can be read from the manifest file. It still fails if the format string requires data stored in the project repository, e.g. if it includes the `{sha}` format string key.

- Commands and options which operate on git revisions now accept abbreviated SHAs. For example, `west init --mr SHA_PREFIX` now works. Previously, the `--mr` argument needed to be the entire 40 character SHA if it wasn’t a branch or a tag.

The developer-visible changes to the west-apis are:

- `west.log.banner()`: new
- `west.log.small_banner()`: new
- `west.manifest.Manifest.get_projects()`: new
- `west.manifest.Project.is_cloned()`: new
- `west.commands.WestCommand` instances can now access the parsed Manifest object via a new `self.manifest` property during the `do_run()` call. If read, it returns the Manifest object or aborts the command if it could not be parsed.
- `west.manifest.Project.git()` now has a `capture_stderr` kwarg
v0.6.0

- No separate bootstrapper

In west v0.5.x, the program was split into two components, a bootstrapper and a per-installation clone. See Multiple Repository Management in the v1.14 documentation for more details.

This is similar to how Google's Repo tool works, and lets west iterate quickly at first. It caused confusion, however, and west is now stable enough to be distributed entirely as one piece via PyPI.

From v0.6.x onwards, all of the core west commands and helper classes are part of the west package distributed via PyPI. This eliminates complexity and makes it possible to import west modules from anywhere in the system, not just extension commands.

- The selfupdate command still exists for backwards compatibility, but now simply exits after printing an error message.

- Manifest syntax changes

  - A west manifest file's projects elements can now specify their fetch URLs directly, like so:

    ```
    manifest:
    projects:
      - name: example-project-name
        url: https://github.com/example/example-project
    ```

    Project elements with url attributes set in this way may not also have remote attributes.

  - Project names must be unique: this restriction is needed to support future work, but was not possible in west v0.5.x because distinct projects may have URLs with the same final pathname component, like so:

    ```
    manifest:
    remotes:
      - name: remote-1
        url-base: https://github.com/remote-1
      - name: remote-2
        url-base: https://github.com/remote-2
    projects:
      - name: project
        remote: remote-1
        path: remote-1-project
      - name: project
        remote: remote-2
        path: remote-2-project
    ```

    These manifests can now be written with projects that use url instead of remote, like so:

    ```
    manifest:
    projects:
      - name: remote-1-project
        url: https://github.com/remote-1/project
      - name: remote-2-project
        url: https://github.com/remote-2/project
    ```

- The west list command now supports a {sha} format string key
- The default format string for west list was changed to "\{name:12\} \{path:28\} \{revision:40\} \{url\}"
The command `west manifest --validate` can now be run to load and validate the current manifest file, among other error-handling fixes related to manifest parsing.

Incompatible API changes were made to west's APIs. Further changes are expected until API stability is declared in west v1.0.

- The `west.manifest.Project` constructor's remote and defaults positional arguments are now kwargs. A new `url` kwarg was also added; if given, the Project URL is set to that value, and the remote kwarg is ignored.
- `west.manifest.MANIFEST_SECTIONS` was removed. There is only one section now, namely `manifest`. The `sections` kwargs in the `west.manifest.Manifest` factory methods and constructor were also removed.
- The `west.manifest.SpecialProject` class was removed. Use `west.manifest.ManifestProject` instead.

v0.5.x

West v0.5.x is the first version used widely by the Zephyr Project as part of its v1.14 Long-Term Support (LTS) release. The `west v0.5.x documentation` is available as part of the Zephyr's v1.14 documentation.

West's main features in v0.5.x are:

- Multiple repository management using Git repositories, including self-update of west itself
- Hierarchical configuration files
- Extension commands

Versions Before v0.5.x

Tags in the west repository before v0.5.x are prototypes which are of historical interest only.

2.11.3 Troubleshooting West

This page covers common issues with west and how to solve them.

`west update` fetching failures

One good way to troubleshoot fetching issues is to run `west update` in verbose mode, like this:

```
west -v update
```

The output includes Git commands run by west and their outputs. Look for something like this:

```
=== updating your_project (path/to/your/project):
west.manifest: your_project: checking if cloned
[...other west.manifest logs...]
--- your_project: fetching, need revision SOME_SHA
west.manifest: running 'git fetch ... https://github.com/your-username/your_project ...' in...
˓→/some/directory
```

The `git fetch` command example in the last line above is what needs to succeed.

One strategy is to go to `path/to/your/project`, copy/paste and run the entire `git fetch` command, then debug from there using the documentation for your credential storage helper.
If you’re behind a corporate firewall and may have proxy or other issues, `curl -v FETCH_URL` (for HTTPS URLs) or `ssh -v FETCH_URL` (for SSH URLs) may be helpful.

If you can get the `git fetch` command to run successfully without prompting for a password when you run it directly, you will be able to run `west update` without entering your password in that same shell.

"'west' is not recognized as an internal or external command, operable program or batch file.'"

On Windows, this means that either west is not installed, or your `PATH` environment variable does not contain the directory where pip installed `west.exe`.

First, make sure you've installed west; see Installing west. Then try running west from a new `cmd.exe` window. If that still doesn't work, keep reading.

You need to find the directory containing `west.exe`, then add it to your `PATH`. (This `PATH` change should have been done for you when you installed Python and pip, so ordinarily you should not need to follow these steps.)

Run this command in `cmd.exe`:

```
pip3 show west
```

Then:

1. Look for a line in the output that looks like `Location: C:\foo\python\python38\lib\site-packages`. The exact location will be different on your computer.
2. Look for a file named `west.exe` in the `scripts` directory `C:\foo\python\python38\scripts`.

**Important:** Notice how `lib\site-packages` in the `pip3 show` output was changed to `scripts`!

3. If you see `west.exe` in the `scripts` directory, add the full path to `scripts` to your `PATH` using a command like this:

```
setx PATH "%PATH%;C:\foo\python\python38\scripts"
```

**Do not just copy/paste this command.** The `scripts` directory location will be different on your system.

4. Close your `cmd.exe` window and open a new one. You should be able to run `west`.

"Error: unexpected keyword argument 'requires_workspace'"

This error occurs on some Linux distributions after upgrading to west 0.7.0 or later from 0.6.x. For example:

```
$ west update
[... stack trace ...]
TypeError: __init__() got an unexpected keyword argument 'requires_workspace'
```

This appears to be a problem with the distribution's pip; see this comment in west issue 373 for details. Some versions of Ubuntu and Linux Mint are known to have this problem. Some users report issues on Fedora as well.

Neither macOS nor Windows users have reported this issue. There have been no reports of this issue on other Linux distributions, like Arch Linux, either.

**Workaround 1:** remove the old version, then upgrade:
$ pip3 show west | grep Location: | cut -f 2 -d ' '  
/home/foo/.local/lib/python3.6/site-packages  
$ rm -r /home/foo/.local/lib/python3.6/site-packages/west  
$ pip3 install --user west==0.7.0

**Workaround 2:** install west in a Python virtual environment

One option is to use the venv module that's part of the Python 3 standard library. Some distributions remove this module from their base Python 3 packages, so you may need to do some additional work to get it installed on your system.

**“invalid choice: ‘build’” (or ‘flash’, etc.)**

If you see an unexpected error like this when trying to run a Zephyr extension command (like west flash, west build, etc.):

```
$ west build [...]  
west: error: argument <command>: invalid choice: 'build' (choose from 'init', [...])
```

```
$ west flash [...]  
west: error: argument <command>: invalid choice: 'flash' (choose from 'init', [...])
```

The most likely cause is that you're running the command outside of a west workspace. West needs to know where your workspace is to find Extensions.

To fix this, you have two choices:

1. Run the command from inside a workspace (e.g. the zephyrproject directory you created when you got started).
   
   For example, create your build directory inside the workspace, or run west flash --build-dir YOUR_BUILD_DIR from inside the workspace.

2. Set the ZEPHYR_BASE environment variable and re-run the west extension command. If set, west will use ZEPHYR_BASE to find your workspace.

If you're unsure whether a command is built-in or an extension, run west help from inside your workspace. The output prints extension commands separately, and looks like this for mainline Zephyr:

```
$ west help

built-in commands for managing git repositories:
init: create a west workspace
[...]

other built-in commands:
help: get help for west or a command
[...]

extension commands from project manifest (path: zephyr):
build: compile a Zephyr application
flash: flash and run a binary on a board
[...]
```

**“invalid choice: ‘post-init’”**

If you see this error when running west init:
Then you have an old version of west installed, and are trying to use it in a workspace that requires a more recent version.

The easiest way to resolve this issue is to upgrade west and retry as follows:

1. Install the latest west with the -U option for pip3 install as shown in Installing west.
2. Back up any contents of zephyrproject/.west/config that you want to save. (If you don’t have any configuration options set, it’s safe to skip this step.)
3. Completely remove the zephyrproject/.west directory (if you don’t, you will get the “already in a workspace” error message discussed next).
4. Run west init again.

“already in an installation”

You may see this error when running west init with west 0.6:

```
FATAL ERROR: already in an installation (<some directory>), aborting
```

If this is unexpected and you’re really trying to create a new west workspace, then it’s likely that west is using the ZEPHYR_BASE environment variable to locate a workspace elsewhere on your system.

This is intentional; it allows you to put your Zephyr applications in any directory and still use west to build, flash, and debug them, for example.

To resolve this issue, unset ZEPHYR_BASE and try again.

2.11.4 Basics

This page introduces west’s basic concepts and provides references to further reading.

West’s built-in commands allow you to work with projects (Git repositories) under a common workspace directory.

Example workspace

If you’ve followed the upstream Zephyr getting started guide, your workspace looks like this:

```
zephyrproject/ # west topdir
  ├── .west/ # marks the location of the topdir
  │     └── config # per-workspace local configuration file
  │
  │ # The manifest repository, never modified by west after creation:
  │ zephyr/ # .git/ repo
  │   └── west.yml # manifest file
  │     └── [... other files ...]
  │
  │ # Projects managed by west:
  │ modules/
  │   └── lib/
  │       └── zcbor # .git/ project
  │ net-tools/ # .git/ project
  │ [ ... other projects ...]
```
Workspace concepts

Here are the basic concepts you should understand about this structure. Additional details are in Workspaces.

topdir
Above, zephyrproject is the name of the workspace's top level directory, or topdir. (The name zephyrproject is just an example – it could be anything, like z, my-zephyr-workspace, etc.)

You'll typically create the topdir and a few other files and directories using west init.

.west directory
The topdir contains the .west directory. When west needs to find the topdir, it searches for .west, and uses its parent directory. The search starts from the current working directory (and starts again from the location in the ZEPHYR_BASE environment variable as a fallback if that fails).

configuration file
The file .west/config is the workspace's local configuration file.

manifest repository
Every west workspace contains exactly one manifest repository, which is a Git repository containing a manifest file. The location of the manifest repository is given by the manifest.path configuration option in the local configuration file.

For upstream Zephyr, zephyr is the manifest repository, but you can configure west to use any Git repository in the workspace as the manifest repository. The only requirement is that it contains a valid manifest file. See Topologies supported for information on other options, and West Manifests for details on the manifest file format.

manifest file
The manifest file is a YAML file that defines projects, which are the additional Git repositories in the workspace managed by west. The manifest file is named west.yml by default; this can be overridden using the manifest.file local configuration option.

You use the west update command to update the workspace's projects based on the contents of the manifest file.

projects
Projects are Git repositories managed by west. Projects are defined in the manifest file and can be located anywhere inside the workspace. In the above example workspace, zcbor and net-tools are projects.

By default, the Zephyr build system uses west to get the locations of all the projects in the workspace, so any code they contain can be used as Modules (External projects). Note however that modules and projects are conceptually different.

extensions
Any repository known to west (either the manifest repository or any project repository) can define Extensions. Extensions are extra west commands you can run when using that workspace.

The zephyr repository uses this feature to provide Zephyr-specific commands like west build. Defining these as extensions keeps west's core agnostic to the specifics of any workspace's Zephyr version, etc.

ignored files
A workspace can contain additional Git repositories or other files and directories not managed by west. West basically ignores anything in the workspace except .west, the manifest repository, and the projects specified in the manifest file.
west init and west update

The two most important workspace-related commands are `west init` and `west update`.

`west init` basics  This command creates a west workspace.

**Important:** West doesn't change your manifest repository contents after `west init` is run. Use ordinary Git commands to pull new versions, etc.

You will typically run it once, like this:

```
west init -m https://github.com/zephyrproject-rtos/zephyr --mr v2.5.0 zephyrproject
```

This will:

1. Create the topdir, `zephyrproject`, along with `.west` and `.west/config` inside it
2. Clone the manifest repository from https://github.com/zephyrproject-rtos/zephyr, placing it into `zephyrproject/zephyr`
3. Check out the `v2.5.0` git tag in your local zephyr clone
4. Set `manifest.path` to `zephyr` in `.west/config`
5. Set `manifest.file` to `west.yml`

Your workspace is now almost ready to use; you just need to run `west update` to clone the rest of the projects into the workspace to finish.

For more details, see `west init`.

`west update` basics  This command makes sure your workspace contains Git repositories matching the projects in the manifest file.

**Important:** Whenever you check out a different revision in your manifest repository, you should run `west update` to make sure your workspace contains the project repositories the new revision expects.

The `west update` command reads the manifest file's contents by:

1. Finding the topdir. In the `west init` example above, that means finding `zephyrproject`.
2. Loading `.west/config` in the topdir to read the `manifest.path` (e.g. `zephyr`) and `manifest.file` (e.g. `west.yml`) options.
3. Loading the manifest file given by these options (e.g. `zephyrproject/zephyr/west.yml`).

It then uses the manifest file to decide where missing projects should be placed within the workspace, what URLs to clone them from, and what Git revisions should be checked out locally. Project repositories which already exist are updated in place by fetching and checking out their respective Git revisions in the manifest file.

For more details, see `west update`.

Other built-in commands

See `Built-in commands`.‌
Zephyr Extensions

See the following pages for information on Zephyr's extension commands:

- Building, Flashing and Debugging
- Signing Binaries
- Additional Zephyr extension commands
- Enabling shell completion

Troubleshooting

See Troubleshooting West.

2.11.5 Built-in commands

This page describes west's built-in commands, some of which were introduced in Basics, in more detail.

Some commands are related to Git commands with the same name, but operate on the entire workspace. For example, west diff shows local changes in multiple Git repositories in the workspace.

Some commands take projects as arguments. These arguments can be project names as specified in the manifest file, or (as a fallback) paths to them on the local file system. Omitting project arguments to commands which accept them (such as west list, west forall, etc.) usually defaults to using all projects in the manifest file plus the manifest repository itself.

For additional help, run west <command> -h (e.g. west init -h).

west init

This command creates a west workspace. It can be used in two ways:

1. Cloning a new manifest repository from a remote URL
2. Creating a workspace around an existing local manifest repository

Option 1: to clone a new manifest repository from a remote URL, use:

```
west init [-m URL] [--mr REVISION] [--mf FILE] [directory]
```

The new workspace is created in the given directory, creating a new .west inside this directory. You can give the manifest URL using the `-m` switch, the initial revision to check out using `--mr`, and the location of the manifest file within the repository using `--mf`.

For example, running:

```
wst init -m https://github.com/zephyrproject-rtos/zephyr --mr v1.14.0 zp
```

would clone the upstream official zephyr repository into zp/zephyr, and check out the v1.14.0 release. This command creates zp/.west, and set the manifest.path configuration option to zephyr to record the location of the manifest repository in the workspace. The default manifest file location is used.

The `-m` option defaults to https://github.com/zephyrproject-rtos/zephyr. The `--mf` option defaults to west.yml. Since west v0.10.1, west will use the default branch in the manifest repository unless the `--mr` option is used to override it. (In prior versions, `--mr` defaulted to master.)

If no directory is given, the current working directory is used.
Option 2: to create a workspace around an existing local manifest repository, use:

```
west init -l [--mf FILE] directory
```

This creates `.west` next to `directory` in the file system, and sets `manifest.path` to `directory`.

As above, `--mf` defaults to `west.yml`.

**Reconfiguring the workspace:**

If you change your mind later, you are free to change `manifest.path` and `manifest.file` using `west config` after running `west init`. Just be sure to run `west update` afterwards to update your workspace to match the new manifest file.

**west update**

```
w west update [-f {always,smart}] [-k] [-r] 
   [--group-filter FILTER] [--stats] [PROJECT ...]
```

**Which projects are updated:**

By default, this command parses the manifest file, usually `west.yml`, and updates each project specified there. If your manifest uses `project groups`, then only the active projects are updated.

To operate on a subset of projects only, give `PROJECT` argument(s). Each `PROJECT` is either a project name as given in the manifest file, or a path that points to the project within the workspace. If you specify projects explicitly, they are updated regardless of whether they are active.

**Project update procedure:**

For each project that is updated, this command:

1. Initializes a local Git repository for the project in the workspace, if it does not already exist
2. Inspects the project's revision field in the manifest, and fetches it from the remote if it is not already available locally
3. Sets the project's `manifest-rev` branch to the commit specified by the revision in the previous step
4. Checks out `manifest-rev` in the local working copy as a detached HEAD
5. If the manifest file specifies a `submodules` key for the project, recursively updates the project's submodules as described below.

To avoid unnecessary fetches, `west update` will not fetch project revision values which are Git SHAs or tags that are already available locally. This is the behavior when the `-f` (`--fetch`) option has its default value, `smart`. To force this command to fetch from project remotes even if the revisions appear to be available locally, either use `-f always` or set the `update.fetch` configuration option to `always`. SHAs may be given as unique prefixes as long as they are acceptable to Git.\(^1\)

If the project revision is a Git ref that is neither a tag nor a SHA (i.e. if the project is tracking a branch), `west update` always fetches, regardless of `-f` and `update.fetch`.

Some branch names might look like short SHAs, like `deadbeef`. West treats these like SHAs. You can disambiguate by prefixing the revision value with `refs/heads/`, e.g. revision: `refs/heads/deadbeef`.

For safety, `west update` uses `git checkout --detach` to check out a detached HEAD at the manifest revision for each updated project, leaving behind any branches which were already checked out. This is typically a safe operation that will not modify any of your local branches.

However, if you had added some local commits onto a previously detached HEAD checked out by `west`, then `git` will warn you that you've left behind some commits which are no longer referred

\(^1\) West may fetch all refs from the Git server when given a SHA as a revision. This is because some Git servers have historically not allowed fetching SHAs directly.
to by any branch. These may be garbage-collected and lost at some point in the future. To avoid
this if you have local commits in the project, make sure you have a local branch checked out
before running west update.

If you would rather rebase any locally checked out branches instead, use the \texttt{-r} \texttt{(--rebase)} op-
tion.

If you would like west update to keep local branches checked out as long as they point to commits
that are descendants of the new manifest-rev, use the \texttt{-k} \texttt{(--keep-descendants)} option.

\textbf{Note}: west update \texttt{--rebase} will fail in projects that have git conflicts between your branch
and new commits brought in by the manifest. You should immediately resolve these conflicts
as you usually do with git, or you can use \texttt{git -C <project_path> rebase --abort} to ignore
incoming changes for the moment.

With a clean working tree, a plain west update never fails because it does not try to hold on to
your commits and simply leaves them aside.

west update \texttt{--keep-descendants} offers an intermediate option that never fails either but does not treat all projects the same:

\begin{itemize}
  \item in projects where your branch diverged from the incoming commits, it does not even try to
  rebase and leaves your branches behind just like a plain west update does;
  \item in all other projects where no rebase or merge is needed it keeps your branches in place.
\end{itemize}

\textbf{One-time project group manipulation}:

The \texttt{--group-filter} option can be used to change which project groups are enabled or disabled
for the duration of a single west update command. See \textit{Project Groups} for details on the project
group feature.

The west update command behaves as if the \texttt{--group-filter} option's value were appended to
the manifest.group-filter configuration option.

For example, running west update \texttt{--group-filter=+foo,-bar} would behave the same way as
if you had temporarily appended the string \"+foo,-bar\" to the value of manifest.group-filter, run west update, then restored manifest.group-filter to its original value.

Note that using the syntax \texttt{--group-filter=VALUE} instead of \texttt{--group-filter VALUE} avoids
issues parsing command line options if you just want to disable a single group, e.g.
\texttt{--group-filter=bar}.

\textbf{Submodule update procedure}:

If a project in the manifest has a \texttt{submodules} key, the submodules are updated as follows, de-
pending on the value of the \texttt{submodules} key.

If the project has \texttt{submodules: true}, west first synchronizes the project's submodules with:

\texttt{git submodule sync --recursive}

West then runs one of the following in the project repository, depending on whether you run
west update with the \texttt{--rebase} option or without it:

\begin{itemize}
  \item \texttt{# without --rebase, e.g. "west update"}:
    \texttt{git submodule update --init --checkout --recursive}
  \item \texttt{# with --rebase, e.g. "west update --rebase"}:
    \texttt{git submodule update --init --rebase --recursive}
\end{itemize}

Otherwise, the project has submodules: \texttt{<list-of-submodules>}. In this case, west synchronizes
the project's submodules with:
Then it updates each submodule in the list as follows, depending on whether you run `west update` with the `--rebase` option or without it:

```bash
# without --rebase, e.g. "west update":
git submodule update --init --checkout --recursive <submodule-path>
# with --rebase, e.g. "west update --rebase":
git submodule update --init --rebase --recursive <submodule-path>
```

The `git submodule sync` commands are skipped if the `update.sync-submodules` Configuration option is false.

**Other project commands**

West has a few more commands for managing the projects in the workspace, which are summarized here. Run `west <command> -h` for detailed help.

- `west compare`: compare the state of the workspace against the manifest
- `west diff`: run `git diff` in local project repositories
- `west forall`: run an arbitrary command in local project repositories
- `west grep`: search for patterns in local project repositories
- `west list`: print a line of information about each project in the manifest, according to a format string
- `west manifest`: manage the manifest file. See [Manifest Command](#).
- `west status`: run `git status` in local project repositories

**Other built-in commands**

Finally, here is a summary of other built-in commands.

- `west config`: get or set configuration options
- `west todir`: print the top level directory of the west workspace
- `west help`: get help about a command, or print information about all commands in the workspace, including Extensions

## 2.11.6 Workspaces

This page describes the `west workspace` concept introduced in [Basics](#) in more detail.

**The manifest-rev branch**

West creates and controls a Git branch named `manifest-rev` in each project. This branch points to the revision that the manifest file specified for the project at the time `west update` was last run. Other workspace management commands may use `manifest-rev` as a reference point for the upstream revision as of this latest update. Among other purposes, the `manifest-rev` branch allows the manifest file to use SHAs as project revisions.

Although `manifest-rev` is a normal Git branch, west will recreate and/or reset it on the next update. For this reason, it is dangerous to check it out or otherwise modify it yourself. For
instance, any commits you manually add to this branch may be lost the next time you run west update. Instead, check out a local branch with another name, and either rebase it on top of a new manifest-rev, or merge manifest-rev into it.

Note: West does not create a manifest-rev branch in the manifest repository, since west does not manage the manifest repository’s branches or revisions.

The refs/west/* Git refs

West also reserves all Git refs that begin with refs/west/ (such as refs/west/foo) for itself in local project repositories. Unlike manifest-rev, these refs are not regular branches. West’s behavior here is an implementation detail; users should not rely on these refs’ existence or behavior.

Private repositories

You can use west to fetch from private repositories. There is nothing west-specific about this.

The west update command essentially runs git fetch YOUR_PROJECT_URL when a project’s manifest-rev branch must be updated to a newly fetched commit. It’s up to your environment to make sure the fetch succeeds.

You can either enter the password manually or use any of the credential helpers built in to Git. Since Git has credential storage built in, there is no need for a west-specific feature.

The following sections cover common cases for running west update without having to enter your password, as well as how to troubleshoot issues.

Fetching via HTTPS

On Windows when fetching from GitHub, recent versions of Git prompt you for your GitHub password in a graphical window once, then store it for future use (in a default installation). Passwordless fetching from GitHub should therefore work “out of the box” on Windows after you have done it once.

In general, you can store your credentials on disk using the “store” git credential helper. See the git-credential-store manual page for details.

To use this helper for all the repositories in your workspace, run:

```
west forall -c "git config credential.helper store"
```

To use this helper on just the projects foo and bar, run:

```
west forall -c "git config credential.helper store" foo bar
```

To use this helper by default on your computer, run:

```
git config --global credential.helper store
```

On GitHub, you can set up a personal access token to use in place of your account password. (This may be required if your account has two-factor authentication enabled, and may be preferable to storing your account password in plain text even if two-factor authentication is disabled.)

You can use the Git credential store to authenticate with a GitHub PAT (Personal Access Token) like so:

```
echo "https://x-access-token:$GH_TOKEN@github.com" >> ~/.git-credentials
```
If you don't want to store any credentials on the file system, you can store them in memory temporarily using `git-credential-cache` instead.

If you setup fetching via SSH, you can use Git URL rewrite feature. The following command instructs Git to use SSH URLs for GitHub instead of HTTPS ones:

```
git config --global url."git@github.com:".insteadOf "https://github.com/"
```

**Fetching via SSH**  If your SSH key has no password, fetching should just work. If it does have a password, you can avoid entering it manually every time using `ssh-agent`.

On GitHub, see Connecting to GitHub with SSH for details on configuration and key creation.

**Project locations**

Projects can be located anywhere inside the workspace, but they may not “escape” it.

In other words, project repositories need not be located in subdirectories of the manifest repository or as immediate subdirectories of the topdir. However, projects must have paths inside the workspace.

You may replace a project's repository directory within the workspace with a symbolic link to elsewhere on your computer, but west will not do this for you.

**Topologies supported**

The following are example source code topologies supported by west.

- **T1: star topology, zephyr is the manifest repository**
  - The zephyr repository acts as the central repository and specifies its Modules (External projects) in its `west.yml`
  - Analogy with existing mechanisms: Git submodules with zephyr as the super-project

This is the default. See Workspace concepts for how mainline Zephyr is an example of this topology.

- **T2: star topology, application is the manifest repository**
  - Useful for those focused on a single application
  - A repository containing a Zephyr application acts as the central repository and names other projects required to build it in its `west.yml`. This includes the zephyr repository and any modules.
  - Analogy with existing mechanisms: Git submodules with the application as the super-project, zephyr and other projects as submodules

A workspace using this topology looks like this:
Here is an example application/west.yml which uses Manifest Imports, available since west 0.7, to import Zephyr v2.5.0 and its modules into the application manifest file:

```yaml
# Example T2 west.yml, using manifest imports.
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: v2.5.0
      import: true
    self:
      path: application
```

You can still selectively “override” individual Zephyr modules if you use import: in this way; see Example 1.3: Downstream of a Zephyr release, with module fork for an example.

Another way to do the same thing is to copy/paste zephyr/west.yml to application/west.yml, adding an entry for the zephyr project itself, like this:

```yaml
# Equivalent to the above, but with manually maintained Zephyr modules.
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  defaults:
    remote: zephyrproject-rtos
  projects:
    - name: zephyr
      revision: v2.5.0
      west-commands: scripts/west-commands.yml
    - name: net-tools
      revision: some-sha-goes-here
      path: tools/net-tools
      # ... other Zephyr modules go here ...
  self:
    path: application
```

(The west-commands is there for Building, Flashing and Debugging and other Zephyr-specific Extensions. It's not necessary when using import.)

The main advantage to using import is not having to track the revisions of imported projects separately. In the above example, using import means Zephyr's module versions are automatically determined from the zephyr/west.yml revision, instead of having to be copy/pasted (and
maintained) on their own.

**T3: Forest topology**

- Useful for those supporting multiple independent applications or downstream distributions with no “central” repository
- A dedicated manifest repository which contains no Zephyr source code, and specifies a list of projects all at the same “level”
- Analogy with existing mechanisms: Google repo-based source distribution

A workspace using this topology looks like this:

```
west-workspace/
├── app1/ # .git/ project
│   ├── CMakeLists.txt
│   ├── prj.conf
│   └── src/
│       └── main.c
├── app2/ # .git/ project
│   ├── CMakeLists.txt
│   └── prj.conf
│       └── src/
│           └── main.c
├── manifest-repo/ # .git/ never modified by west
│   └── west.yml # main manifest with optional import(s) and override(s)
├── modules/
│   └── lib/
│       └── zcbor/ # .git/ project from either the main manifest or
│              # from some import
└── zephyr/ # .git/ project
    └── west.yml # This can be partially imported with lower precedence or ignored. # Only the 'manifest-rev' version can be imported.
```

Here is an example T3 manifest-repo/west.yml which uses *Manifest Imports*, available since west 0.7, to import Zephyr v2.5.0 and its modules, then add the app1 and app2 projects:

```
manifest:
remotes:
  - name: zephyrproject-rtos
    url-base: https://github.com/zephyrproject-rtos
  - name: your-git-server
    url-base: https://git.example.com/your-company
defaults:
  remote: your-git-server
projects:
  - name: zephyr
    remote: zephyrproject-rtos
    revision: v2.5.0
    import: true
  - name: app1
    revision: SOME_SHA_OR_BRANCH_OR_TAG
  - name: app2
    revision: ANOTHER_SHA_OR_BRANCH_OR_TAG
self:
  path: manifest-repo
```

You can also do this “by hand” by copy/pasting zephyr/west.yml as shown *above* for the T2 topology, with the same caveats.
2.11.7 West Manifests

This page contains detailed information about west's multiple repository model, manifest files, and the `west manifest` command. For API documentation on the `west.manifest` module, see `west-apis-manifest`. For a more general introduction and command overview, see *Basics*.

**Multiple Repository Model**

West's view of the repositories in a *west workspace*, and their history, looks like the following figure (though some parts of this example are specific to upstream Zephyr's use of west):

![West multi-repo history](image)

*Fig. 3: West multi-repo history*

The history of the manifest repository is the line of Git commits which is “floating” on top of the gray plane. Parent commits point to child commits using solid arrows. The plane below contains the Git commit history of the repositories in the workspace, with each project repository boxed in by a rectangle. Parent/child commit relationships in each repository are also shown with solid arrows.

The commits in the manifest repository (again, for upstream Zephyr this is the zephyr repository itself) each have a manifest file. The manifest file in each commit specifies the corresponding commits which it expects in each of the project repositories. This relationship is shown using dotted line arrows in the diagram. Each dotted line arrow points from a commit in the manifest repository to a corresponding commit in a project repository.

Notice the following important details:

- Projects can be added (like P1 between manifest repository commits D and E) and removed (P2 between the same manifest repository commits)
- Project and manifest repository histories don’t have to move forwards or backwards together:
  - P2 stays the same from A → B, as do P1 and P3 from F → G.
  - P3 moves forward from A → B.
  - P3 moves backward from C → D.
One use for moving backward in project history is to “revert” a regression by going back to a revision before it was introduced.

- Project repository commits can be “skipped”: P3 moves forward multiple commits in its history from B → C.
- In the above diagram, no project repository has two revisions “at the same time”: every manifest file refers to exactly one commit in the projects it cares about. This can be relaxed by using a branch name as a manifest revision, at the cost of being able to bisect manifest repository history.

**Manifest Files**

West manifests are YAML files. Manifests have a top-level `manifest` section with some subsections, like this:

```yaml
manifest:
  remotes:
    # short names for project URLs
  projects:
    # a list of projects managed by west
  defaults:
    # default project attributes
  self:
    # configuration related to the manifest repository itself,
    # i.e. the repository containing west.yml
  version: "<schema-version>"
  group-filter:
    # a list of project groups to enable or disable
```

In YAML terms, the manifest file contains a mapping, with a `manifest` key. Any other keys and their contents are ignored (west v0.5 also required a `west` key, but this is ignored starting with v0.6).

The manifest contains subsections, like `defaults`, `remotes`, `projects`, and `self`. In YAML terms, the value of the `manifest` key is also a mapping, with these “subsections” as keys. As of west v0.10, all of these “subsection” keys are optional.

The `projects` value is a list of repositories managed by west and associated metadata. We'll discuss it soon, but first we will describe the `remotes` section, which can be used to save typing in the `projects` list.

**Remotes**  
The `remotes` subsection contains a sequence which specifies the base URLs where projects can be fetched from.

Each `remotes` element has a name and a “URL base”. These are used to form the complete Git fetch URL for each project. A project's fetch URL can be set by appending a project-specific path onto a remote URL base. (As we'll see below, projects can also specify their complete fetch URLs.)

For example:

```yaml
manifest:
  # ...
  remotes:
    - name: remote1
      url-base: https://git.example.com/base1
    - name: remote2
      url-base: https://git.example.com/base2
```

The `remotes` keys and their usage are in the following table.
### Table 2: remotes keys

<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>name</td>
<td>Mandatory; a unique name for the remote.</td>
</tr>
<tr>
<td>url-base</td>
<td>A prefix that is prepended to the fetch URL for each project with this remote.</td>
</tr>
</tbody>
</table>

Above, two remotes are given, with names `remote1` and `remote2`. Their URL bases are respectively `https://git.example.com/base1` and `https://git.example.com/base2`. You can use SSH URL bases as well; for example, you might use `git@example.com:base1` if `remote1` supported Git over SSH as well. Anything acceptable to Git will work.

**Projects**  
The projects subsection contains a sequence describing the project repositories in the west workspace. Every project has a unique name. You can specify what Git remote URLs to use when cloning and fetching the projects, what revisions to track, and where the project should be stored on the local file system. Note that west projects are different from modules.

Here is an example. We’ll assume the remotes given above.

```
manifest:
  # [... same remotes as above...]
  projects:
    - name: proj1
      description: the first example project
      remote: remote1
      path: extra/project-1
    - name: proj2
      description: |
        A multi-line description of the second example project.
      repo-path: my-path
      remote: remote2
      revision: v1.3
    - name: proj3
      url: https://github.com/user/project-three
      revision: abcde413a111
```

In this manifest:

- **proj1** has remote `remote1`, so its Git fetch URL is `https://git.example.com/base1/proj1`. The remote `url-base` is appended with a `/` and the project name to form the URL.

  Locally, this project will be cloned at path `extra/project-1` relative to the west workspace’s root directory, since it has an explicit `path` attribute with this value.

  Since the project has no revision specified, master is used by default. The current tip of this branch will be fetched and checked out as a detached HEAD when west next updates this project.

- **proj2** has a remote and a `repo-path`, so its fetch URL is `https://git.example.com/base2/my-path`. The `repo-path` attribute, if present, overrides the default `name` when forming the fetch URL.

  Since the project has no `path` attribute, its `name` is used by default. It will be cloned into a directory named `proj2`. The commit pointed to by the `v1.3` tag will be checked out when west updates the project.

- **proj3** has an explicit `url`, so it will be fetched from `https://github.com/user/project-three`.

  Its local path defaults to its `name`, `proj3`. Commit `abcde413a111` will be checked out when it is next updated.
The available project keys and their usage are in the following table. Sometimes we'll refer to the defaults subsection; it will be described next.

<table>
<thead>
<tr>
<th>Key(s)</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>name</td>
<td>Mandatory; a unique name for the project. The name cannot be one of the reserved values “west” or “manifest”. The name must be unique in the manifest file.</td>
</tr>
<tr>
<td>description</td>
<td>Optional, an informational description of the project. Added in west v1.2.0.</td>
</tr>
<tr>
<td>remote, url</td>
<td>Mandatory (one of the two, but not both). If the project has a remote, that remote's url-base will be combined with the project's name (or repo-path, if it has one) to form the fetch URL instead. If the project has a url, that's the complete fetch URL for the remote Git repository. If the project has neither, the defaults section must specify a remote, which will be used as the project's remote. Otherwise, the manifest is invalid.</td>
</tr>
<tr>
<td>repo-path</td>
<td>Optional. If given, this is concatenated on to the remote's url-base instead of the project's name to form its fetch URL. Projects may not have both url and repo-path attributes.</td>
</tr>
<tr>
<td>revision</td>
<td>Optional. The Git revision that west update should check out. This will be checked out as a detached HEAD by default, to avoid conflicting with local branch names. If not given, the revision value from the defaults subsection will be used if present. A project revision can be a branch, tag, or SHA. The default revision is master if not otherwise specified. Using HEAD~0¹ as the revision will cause west to keep the current state of the project.</td>
</tr>
<tr>
<td>path</td>
<td>Optional. Relative path specifying where to clone the repository locally, relative to the top directory in the west workspace. If missing, the project's name is used as a directory name.</td>
</tr>
<tr>
<td>clone-depth</td>
<td>Optional. If given, a positive integer which creates a shallow history in the cloned repository limited to the given number of commits. This can only be used if the revision is a branch or tag.</td>
</tr>
<tr>
<td>west-commands</td>
<td>Optional. If given, a relative path to a YAML file within the project which describes additional west commands provided by that project. This file is named west-commands.yml by convention. See Extensions for details.</td>
</tr>
<tr>
<td>import</td>
<td>Optional. If true, imports projects from manifest files in the given repository into the current manifest. See Manifest Imports for details.</td>
</tr>
<tr>
<td>groups</td>
<td>Optional, a list of groups the project belongs to. See Project Groups for details.</td>
</tr>
<tr>
<td>submodules</td>
<td>Optional. You can use this to make west update also update Git submodules defined by the project. See Git Submodules in Projects for details.</td>
</tr>
<tr>
<td>userdata</td>
<td>Optional. The value is an arbitrary YAML value. See Repository user data.</td>
</tr>
</tbody>
</table>

**Defaults** The defaults subsection can provide default values for project attributes. In particular, the default remote name and revision can be specified here. Another way to write the same manifest we have been describing so far using defaults is:

```yaml
manifest:
  defaults:
    remote: remote1
    revision: v1.3
```

¹ In git, HEAD is a reference, whereas HEAD~<n> is a valid revision but not a reference. West fetches references, such as refs/heads/main or HEAD, and commits not available locally, but will not fetch commits if they are already available. HEAD~0 is resolved to a specific commit that is locally available, and therefore west will simply checkout the locally available commit, identified by HEAD~0.
remotes:
- name: remote1
  url-base: https://git.example.com/base1
- name: remote2
  url-base: https://git.example.com/base2

projects:
- name: proj1
  description: the first example project
  path: extra/project-1
  revision: master
- name: proj2
  description: A multi-line description of the second example project.
  repo-path: my-path
  remote: remote2
- name: proj3
  url: https://github.com/user/project-three
  revision: abcde413a111

The available defaults keys and their usage are in the following table.

<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>remote</td>
<td>Optional. This will be used for a project's remote if it does not have a url or remote key set.</td>
</tr>
<tr>
<td>revision</td>
<td>Optional. This will be used for a project's revision if it does not have one set. If not given, the default is master.</td>
</tr>
</tbody>
</table>

**Self**  The self subsection can be used to control the manifest repository itself.

As an example, let's consider this snippet from the zephyr repository's west.yml:

```yaml
manifest:
  # ...
  self:
    path: zephyr
    west-commands: scripts/west-commands.yml
```

This ensures that the zephyr repository is cloned into path zephyr, though as explained above that would have happened anyway if cloning from the default manifest URL, https://github.com/zephyrproject-rtos/zephyr. Since the zephyr repository does contain extension commands, its self entry declares the location of the corresponding west-commands.yml relative to the repository root.

The available self keys and their usage are in the following table.
<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>path</td>
<td>Optional. The path <code>west init</code> should clone the manifest repository into, relative to the <code>west workspace topdir</code>. If not given, the basename of the path component in the manifest repository URL will be used by default. For example, if the URL is <code>https://git.example.com/project-repo</code>, the manifest repository would be cloned to the directory <code>project-repo</code>.</td>
</tr>
<tr>
<td>west-commands</td>
<td>Optional. This is analogous to the same key in a project sequence element.</td>
</tr>
<tr>
<td>import</td>
<td>Optional. This is also analogous to the <code>projects</code> key, but allows importing projects from other files in the manifest repository. See <em>Manifest Imports</em>.</td>
</tr>
</tbody>
</table>

**Version** The version subsection declares that the manifest file uses features which were introduced in some version of west. Attempts to load the manifest with older versions of west will fail with an error message that explains the minimum required version of west which is needed.

Here is an example:

```yaml
manifest:
  # Marks that this file uses version 0.10 of the west manifest file format.
  # An attempt to load this manifest file with west v0.8.0 will fail with an error message saying that west v0.10.0 or later is required.
  version: "0.10"
```

The pykwalify schema `manifest-schema.yml` in the west source code repository is used to validate the manifest section.

Here is a table with the valid version values, along with information about the manifest file features that were introduced in that version.
<table>
<thead>
<tr>
<th>version</th>
<th>New features</th>
</tr>
</thead>
<tbody>
<tr>
<td>&quot;0.7&quot;</td>
<td>Initial support for the version feature. All manifest file features that are not otherwise mentioned in this table were introduced in west v0.7.0 or earlier.</td>
</tr>
<tr>
<td>&quot;0.8&quot;</td>
<td>Support for import: path-prefix: (Option 3: Mapping)</td>
</tr>
<tr>
<td>&quot;0.9&quot;</td>
<td><strong>Use of west v0.9.x is discouraged.</strong> This schema version is provided to allow users to explicitly request compatibility with west v0.9.0. However, west v0.10.0 and later have incompatible behavior for features that were introduced in west v0.9.0. You should ignore version “0.9” if possible.</td>
</tr>
</tbody>
</table>
| "0.10" | Support for:  
|         | - submodules: in projects: ([Git Submodules in Projects])  
|         | - manifest: group-filter:, and groups: in projects: ([Project Groups])  
|         | - The import: feature now supports allowlist: and blocklist:: these are respectively recommended as replacements for older names as part of a general Zephyr-wide inclusive language change. The older key names are still supported for backwards compatibility. ([Manifest Imports, Option 3: Mapping]) |
| "0.12" | Support for userdata: in projects: ([Repository user data]) |
| "0.13" | Support for self: userdata: ([Repository user data]) |
| "1.0"  | Identical to “0.13”, but available for use by users that do not wish to use a "0.x" version field. |
| "1.2"  | Support for description: in projects: ([Projects]) |

**Note:** Versions of west without any new features in the manifest file format do not change the list of valid version values. For example, version: "0.11" is **not** valid, because west v0.11.x did not introduce new manifest file format features.

Quoting the version value as shown above forces the YAML parser to treat it as a string. Without quotes, 0.10 in YAML is just the floating point value 0.1. You can omit the quotes if the value is the same when cast to string, but it's best to include them. Always use quotes if you're not sure.

If you do not include a version in your manifest, each new release of west assumes that it should try to load it using the features that were available in that release. This may result in error messages that are harder to understand if that version of west is too old to load the manifest.

**Group-filter**  See [Project Groups](#).

**Active and Inactive Projects**

Projects defined in the west manifest can be **inactive** or **active**. The difference is that an inactive project is generally ignored by west. For example, `west update` will not update inactive projects, and `west list` will not print information about them by default. As another example, any [Manifest Imports](#) in an inactive project will be ignored by west.

There are two ways to make a project inactive:

1. Using the `manifest.project-filter` configuration option. If a project is made active or inactive using this option, then the rules related to making a project inactive using its `groups:` are ignored. That is, if a regular expression in `manifest.project-filter` applies to a project, the project's groups have no effect on whether it is active or inactive.

See the entry for this option in [Built-in Configuration Options](#) for details.
2. Otherwise, if a project has groups, and they are all disabled, then the project is inactive. See the following section for details.

Project Groups

You can use the `groups:` and `group-filter:` keys briefly described above to place projects into groups, and to enable or disable groups.

For example, this lets you run a `west forall` command only on the projects in the group by using `west forall --group`. This can also let you make projects inactive; see the previous section for more information on inactive projects.

The next section introduces project groups. The following section describes Enabled and Disabled Project Groups. There are some basic examples in Project Group Examples. Finally, Group Filters and Imports provides a simplified overview of how `group-filter` interacts with the Manifest Imports feature.

Groups Basics

The `groups:` and `group-filter:` keys appear in the manifest like this:

```
manifest:
  projects:
    - name: some-project
      groups: ...
      group-filter: ...
```

The `groups` key's value is a list of group names. Group names are strings.

You can enable or disable project groups using `group-filter`. Projects whose groups are all disabled, and which are not otherwise made active by a `manifest.project-filter` configuration option, are inactive.

For example, in this manifest fragment:

```
manifest:
  projects:
    - name: project-1
      groups:
        - groupA
    - name: project-2
      groups:
        - groupB
        - groupC
    - name: project-3
```

The projects are in these groups:

- `project-1`: one group, named `groupA`
- `project-2`: two groups, named `groupB` and `groupC`
- `project-3`: no groups

Project group names must not contain commas (,), colons (:), or whitespace.

Group names must not begin with a dash (-) or the plus sign (+), but they may contain these characters elsewhere in their names. For example, `foo-bar` and `foo+bar` are valid groups, but `-foobar` and `+foobar` are not.

Group names are otherwise arbitrary strings. Group names are case sensitive.

As a restriction, no project may use both `import:` and `groups:`. (This is necessary to avoid some pathological edge cases.)
Enabled and Disabled Project Groups  All project groups are enabled by default. You can enable or disable groups in both your manifest file and Configuration.

Within a manifest file, manifest: group-filter: is a YAML list of groups to enable and disable.

To enable a group, prefix its name with a plus sign (+). For example, groupA is enabled in this manifest fragment:

```yaml
manifest:
  group-filter: [+groupA]
```

Although this is redundant for groups that are already enabled by default, it can be used to override settings in an imported manifest file. See Group Filters and Imports for more information.

To disable a group, prefix its name with a dash (-). For example, groupA and groupB are disabled in this manifest fragment:

```yaml
manifest:
  group-filter: [-groupA,-groupB]
```

Note: Since group-filter is a YAML list, you could have written this fragment as follows:

```yaml
manifest:
  group-filter:
    - -groupA
    - -groupB
```

However, this syntax is harder to read and therefore discouraged.

In addition to the manifest file, you can control which groups are enabled and disabled using the manifest.group-filter configuration option. This option is a comma-separated list of groups to enable and/or disable.

To enable a group, add its name to the list prefixed with +. To disable a group, add its name prefixed with -. For example, setting manifest.group-filter to +groupA,-groupB enables groupA, and disables groupB.

The value of the configuration option overrides any data in the manifest file. You can think of this as if the manifest.group-filter configuration option is appended to the manifest: group-filter: list from YAML, with “last entry wins” semantics.

Project Group Examples This section contains example situations involving project groups and active projects. The examples use both manifest: group-filter: YAML lists and manifest. group-filter configuration lists, to show how they work together.

Note that the defaults and remotes data in the following manifests isn't relevant except to make the examples complete and self-contained.

Note: In all of the examples that follow, the manifest.project-filter option is assumed to be unset.

Example 1: no disabled groups  The entire manifest file is:

```yaml
manifest:
  projects:
    - name: foo
groups:
```

(continues on next page)
The manifest.group-filter configuration option is not set (you can ensure this by running west config -D manifest.group-filter).

No groups are disabled, because all groups are enabled by default. Therefore, all three projects (foo, bar, and baz) are active. Note that there is no way to make project baz inactive, since it has no groups.

**Example 2: Disabling one group via manifest**  The entire manifest file is:

```json
manifest:
  projects:
    - name: foo
      groups:
        - groupA
      - name: bar
        groups:
          - groupA
          - groupB
  group-filter: [-groupA]
  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
  url-base: https://git.example.com
```

The manifest.group-filter configuration option is not set (you can ensure this by running west config -D manifest.group-filter).

Since groupA is disabled, project foo is inactive. Project bar is active, because groupB is enabled.

**Example 3: Disabling multiple groups via manifest**  The entire manifest file is:

```json
manifest:
  projects:
    - name: foo
      groups:
        - groupA
    - name: bar
      groups:
        - groupA
        - groupB
  group-filter: [-groupA,-groupB]
```

(continues on next page)
The manifest.group-filter configuration option is not set (you can ensure this by running `west config -D manifest.group-filter`). Both `foo` and `bar` are inactive, because all of their groups are disabled.

**Example 4: Disabling a group via configuration**  The entire manifest file is:

```
manifest:
  projects:
    - name: foo
      groups:
        - groupA
    - name: bar
      groups:
        - groupA
        - groupB
  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
      url-base: https://git.example.com
```

The manifest.group-filter configuration option is set to `-groupA` (you can ensure this by running `west config manifest.group-filter -- -groupA`; the extra `--` is required so the argument parser does not treat `-groupA` as a command line option `-g` with value `roupA`).

Project `foo` is inactive because `groupA` has been disabled by the manifest.group-filter configuration option. Project `bar` is active because `groupB` is enabled.

**Example 5: Overriding a disabled group via configuration**  The entire manifest file is:

```
manifest:
  projects:
    - name: foo
      groups:
    - name: bar
      groups:
    - name: baz
      groups:
  group-filter: [-groupA]
  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
      url-base: https://git.example.com
```

The manifest.group-filter configuration option is set to `+groupA` (you can ensure this by running `west config manifest.group-filter +groupA`).
In this case, groupA is enabled: the manifest.group-filter configuration option has higher precedence than the manifest: group-filter: [-groupA] content in the manifest file. Therefore, projects foo and bar are both active.

Example 6: Overriding multiple disabled groups via configuration

The entire manifest file is:

```manifest:
  projects:
    - name: foo
    - name: bar
      groups:
        - groupA
        - groupB
        groups:
          - name: baz
            groups:
              - groupA
              - groupB

  group-filter: [-groupA,-groupB]

  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
      url-base: https://git.example.com
```

The manifest.group-filter configuration option is set to +groupA,+groupB (you can ensure this by running west config manifest.group-filter "+groupA,+groupB"). In this case, both groupA and groupB are enabled, because the configuration value overrides the manifest file for both groups. Therefore, projects foo and bar are both active.

Example 7: Disabling multiple groups via configuration

The entire manifest file is:

```manifest:
  projects:
    - name: foo
    - name: bar
      groups:
        - groupA
        - groupB
        groups:
          - name: baz
            groups:
              - groupA
              - groupB

  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
      url-base: https://git.example.com
```

The manifest.group-filter configuration option is set to -groupA,-groupB (you can ensure this by running west config manifest.group-filter -- "-groupA,-groupB"). In this case, both groupA and groupB are disabled. Therefore, projects foo and bar are both inactive.
Group Filters and Imports  This section provides a simplified description of how the manifest: group-filter: value behaves when combined with Manifest Imports. For complete details, see Manifest Import Details.

**Warning:** The below semantics apply to west v0.10.0 and later. West v0.9.x semantics are different, and combining group-filter with import in west v0.9.x is discouraged.

In short:

- if you only import one manifest, any groups it disables in its group-filter are also disabled in your manifest
- you can override this in your manifest file's manifest: group-filter: value, your workspace's manifest.group-filter configuration option, or both

Here are some examples.

**Example 1: no overrides**  You are using this parent/west.yml manifest:

```yaml
# parent/west.yml:
manifest:
  projects:
    - name: child
      url: https://git.example.com/child
      import: true
    - name: project-1
      url: https://git.example.com/project-1
      groups:
        - unstable
```

And child/west.yml contains:

```yaml
# child/west.yml:
manifest:
  group-filter: [-unstable]
  projects:
    - name: project-2
      url: https://git.example.com/project-2
    - name: project-3
      url: https://git.example.com/project-3
      groups:
        - unstable
```

Only child and project-2 are active in the resolved manifest.

The unstable group is disabled in child/west.yml, and that is not overridden in parent/west.yml. Therefore, the final group-filter for the resolved manifest is [-unstable].

Since project-1 and project-3 are in the unstable group and are not in any other group, they are inactive.

**Example 2: overriding an imported group-filter via manifest**  You are using this parent/west.yml manifest:

```yaml
# parent/west.yml:
manifest:
  group-filter: [+unstable,-optional]
  projects:
    - name: child
```

(continues on next page)
And child/west.yml contains:

```yaml
# child/west.yml:
manifest:
  group-filter: [-unstable]
  projects:
    - name: project-2
      url: https://git.example.com/project-2
      groups:
        - optional
    - name: project-3
      url: https://git.example.com/project-3
      groups:
        - unstable
```

Only the child, project-1, and project-3 projects are active.

The [-unstable] group filter in child/west.yml is overridden in parent/west.yml, so the unstable group is enabled. Since project-1 and project-3 are in the unstable group, they are active.

The same parent/west.yml file disables the optional group, so project-2 is inactive.

The final group filter specified by parent/west.yml is [+unstable, -optional].

**Example 3: overriding an imported group-filter via configuration** You are using this parent/west.yml manifest:

```yaml
# parent/west.yml:
manifest:
  projects:
    - name: child
      url: https://git.example.com/child
      import: true
    - name: project-1
      url: https://git.example.com/project-1
      groups:
        - unstable
```

And child/west.yml contains:

```yaml
# child/west.yml:
manifest:
  group-filter: [-unstable]
  projects:
    - name: project-2
      url: https://git.example.com/project-2
      groups:
        - optional
    - name: project-3
      url: https://git.example.com/project-3
      groups:
        - unstable
```

If you run:
Then only the child, project-1, and project-3 projects are active.

The `-unstable` group filter in `child/west.yml` is overridden in the `manifest.group-filter` configuration option, so the unstable group is enabled. Since project-1 and project-3 are in the unstable group, they are active.

The same configuration option disables the optional group, so project-2 is inactive.

The final group filter specified by `parent/west.yml` and the `manifest.group-filter` configuration option is `+[unstable,-optional]`.

Git Submodules in Projects

You can use the `submodules` keys briefly described above to force `west update` to also handle any Git submodules configured in project's git repository. The `submodules` key can appear inside `projects`, like this:

```
manifest:
  projects:
    - name: some-project
      submodules: ...
```

The `submodules` key can be a boolean or a list of mappings. We'll describe these in order.

**Option 1: Boolean**  This is the easiest way to use submodules.

If submodules is true as a `projects` attribute, `west update` will recursively update the project's Git submodules whenever it updates the project itself. If it's false or missing, it has no effect.

For example, let's say you have a source code repository `foo`, which has some submodules, and you want `west update` to keep all of them in sync, along with another project named `bar` in the same workspace.

You can do that with this manifest file:

```
manifest:
  projects:
    - name: foo
      submodules: true
    - name: bar
```

Here, `west update` will initialize and update all submodules in `foo`. If `bar` has any submodules, they are ignored, because `bar` does not have a `submodules` value.

**Option 2: List of mappings**  The `submodules` key may be a list of mappings, one list element for each desired submodule. Each submodule listed is updated recursively. You can still track and update unlisted submodules with `git` commands manually; present or not they will be completely ignored by `west`.

The `path` key must match exactly the path of one submodule relative to its parent west project, as shown in the output of `git submodule status`. The `name` key is optional and not used by `west` for now; it's not passed to `git submodule` commands either. The `name` key was briefly mandatory in `west` version 0.9.0, but was made optional in 0.9.1.

For example, let's say you have a source code repository `foo`, which has many submodules, and you want `west update` to keep some but not all of them in sync, along with another project named `bar` in the same workspace.

You can do that with this manifest file:
Here, `west update` will recursively initialize and update just the submodules in `foo` with paths `path/to/foo-first-sub` and `path/to/foo-second-sub`. Any submodules in `bar` are still ignored.

**Repository user data**

West versions v0.12 and later support an optional `userdata` key in projects.

West versions v0.13 and later supports this key in the `manifest: self:` section.

It is meant for consumption by programs that require user-specific project metadata. Beyond parsing it as YAML, `west` itself ignores the value completely.

The key's value is arbitrary YAML. West parses the value and makes it accessible to programs using `west-apis` as the `userdata` attribute of the corresponding `west.manifest.Project` object.

Example manifest fragment:

```yaml
manifest:
  projects:
    - name: foo
      submodules:
        - path: path/to/foo-first-sub
        - name: foo-second-sub
          path: path/to/foo-second-sub
        - name: bar
```

Example Python usage:

```python
manifest = west.manifest.Manifest.from_file()

foo, bar, baz = manifest.get_projects(['foo', 'bar', 'baz'])

foo.userdata  # None
bar.userdata  # 'a-string'
baz.userdata  # {'key': 'value'}
manifest.userdata  # 'blub'
```

**Manifest Imports**

You can use the `import` key briefly described above to include projects from other manifest files in your `west.yml`. This key can be either a project or `self` section attribute:

```yaml
manifest:
  projects:
    - name: some-project
      import: ...
  self:
    import: ...
```
You can use a “self: import:” to load additional files from the repository containing your west.yml. You can use a “project: … import:” to load additional files defined in that project’s Git history.

West resolves the final manifest from individual manifest files in this order:

1. imported files in self
2. your west.yml file
3. imported files in projects

During resolution, west ignores projects which have already been defined in other files. For example, a project named foo in your west.yml makes west ignore other projects named foo imported from your projects list.

The import key can be a boolean, path, mapping, or sequence. We’ll describe these in order, using examples:

- **Boolean**
  - Example 1.1: Downstream of a Zephyr release
  - Example 1.2: “Rolling release” Zephyr downstream
  - Example 1.3: Downstream of a Zephyr release, with module fork

- **Relative path**
  - Example 2.1: Downstream of a Zephyr release with explicit path
  - Example 2.2: Downstream with directory of manifest files
  - Example 2.3: Continuous Integration overrides

- **Mapping with additional configuration**
  - Example 3.1: Downstream with name allowlist
  - Example 3.2: Downstream with path allowlist
  - Example 3.3: Downstream with path blocklist
  - Example 3.4: Import into a subdirectory

- **Sequence of paths and mappings**
  - Example 4.1: Downstream with sequence of manifest files
  - Example 4.2: Import order illustration

A more formal description of how this works is last, after the examples.

**Troubleshooting Note** If you’re using this feature and find west’s behavior confusing, try re-solving your manifest to see the final results after imports are done.

**Option 1: Boolean** This is the easiest way to use import.

If import is true as a projects attribute, west imports projects from the west.yml file in that project’s root directory. If it’s false or missing, it has no effect. For example, this manifest would import west.yml from the p1 git repository at revision v1.0:

```manifest
# ...
projects:
  - name: p1
    revision: v1.0
    import: true  # Import west.yml from p1’s v1.0 git tag
    - name: p2
```

(continues on next page)
It's an error to set `import` to either `true` or `false` inside `self`, like this:

```yaml
manifest:
  # ...
  self:
    import: true  # Error
```

**Example 1.1: Downstream of a Zephyr release**  You have a source code repository you want to use with Zephyr v1.14.1 LTS. You want to maintain the whole thing using west. You don’t want to modify any of the mainline repositories.

In other words, the west workspace you want looks like this:

```plaintext
my-downstream/
├── .west/ # west directory
├── zephyr/ # mainline zephyr repository
│   └── west.yml # the v1.14.1 version of this file is imported
├── modules/ # modules from mainline zephyr
│   └── [...other directories..]
├── [ ... other projects ...] # other mainline repositories
├── my-repo/ # your downstream repository
│   └── west.yml # main manifest importing zephyr/west.yml v1.14.1
└── [...other files..]
```

You can do this with the following `my-repo/west.yml`:

```yaml
# my-repo/west.yml:
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: v1.14.1
      import: true
```

You can then create the workspace on your computer like this, assuming `my-repo` is hosted at https://git.example.com/my-repo:

```
west init -m https://git.example.com/my-repo my-downstream
cd my-downstream
west update
```

After `west init`, `my-downstream/my-repo` will be cloned.

After `west update`, all of the projects defined in the `zephyr` repository’s `west.yml` at revision v1.14.1 will be cloned into `my-downstream` as well.

You can add and commit any code to `my-repo` you please at this point, including your own Zephyr applications, drivers, etc. See *Application Development*.

**Example 1.2: “Rolling release” Zephyr downstream**  This is similar to *Example 1.1: Downstream of a Zephyr release*, except we’ll use `revision: main` for the `zephyr` repository:

```markdown
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```
# my-repo/west.yml:
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: main
      import: true

You can create the workspace in the same way:

west init -m https://git.example.com/my-repo my-downstream
cd my-downstream
west update

This time, whenever you run west update, the special manifest-rev branch in the zephyr repository will be updated to point at a newly fetched main branch tip from the URL https://github.com/zephyrproject-rtos/zephyr.

The contents of zephyr/west.yml at the new manifest-rev will then be used to import projects from Zephyr. This lets you stay up to date with the latest changes in the Zephyr project. The cost is that running west update will not produce reproducible results, since the remote main branch can change every time you run it.

It's also important to understand that west ignores your working tree’s zephyr/west.yml entirely when resolving imports. West always uses the contents of imported manifests as they were committed to the latest manifest-rev when importing from a project.

You can only import manifest from the file system if they are in your manifest repository's working tree. See Example 2.2: Downstream with directory of manifest files for an example.

Example 1.3: Downstream of a Zephyr release, with module fork  This manifest is similar to the one in Example 1.1: Downstream of a Zephyr release, except it:

- is a downstream of Zephyr 2.0
- includes a downstream fork of the modules/hal/nordic module which was included in that release

# my-repo/west.yml:
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
    - name: my-remote
      url-base: https://git.example.com
  projects:
    - name: hal_nordic
      # higher precedence
      remote: my-remote
      path: modules/hal/nordic
      revision: my-sha
    - name: zephyr
      remote: zephyrproject-rtos
      revision: v2.0.0
      import: true
      # imported projects have lower precedence

# subset of zephyr/west.yml contents at v2.0.0:
manifest:
  defaults:
    remote: zephyrproject-rtos
remotes:
  - name: zephyrproject-rtos
    url-base: https://github.com/zephyrproject-rtos

projects:
  # ...
  - name: hal_nordic           # lower precedence, values ignored
    path: modules/hal/nordic
    revision: another-sha

With this manifest file, the project named hal_nordic:

- is cloned from https://git.example.com/hal_nordic instead of https://github.com/zephyrproject-rtos/hal_nordic.
- is updated to commit my-sha by west update, instead of the mainline commit another-sha

In other words, when your top-level manifest defines a project, like hal_nordic, west will ignore any other definition it finds later on while resolving imports.

This does mean you have to copy the path: modules/hal/nordic value into my-repo/west.yml when defining hal_nordic there. The value from zephyr/west.yml is ignored entirely. See Resolving Manifests for troubleshooting advice if this gets confusing in practice.

When you run west update, west will:

- update zephyr's manifest-rev to point at the v2.0.0 tag
- import zephyr/west.yml at that manifest-rev
- locally check out the v2.0.0 revisions for all zephyr projects except hal_nordic
- update hal_nordic to my-sha instead of another-sha

Option 2: Relative path  The import value can also be a relative path to a manifest file or a directory containing manifest files. The path is relative to the root directory of the projects or self repository the import key appears in.

Here is an example:

manifest:
  projects:
    - name: project-1
      revision: v1.0
      import: west.yml
    - name: project-2
      revision: main
      import: p2-manifests
  self:
    import: submanifests

This will import the following:

- the contents of project-1/west.yml at manifest-rev, which points at tag v1.0 after running west update
- any YAML files in the directory tree project-2/p2-manifests at the latest commit in the main branch, as fetched by west update, sorted by file name
- YAML files in submanifests in your manifest repository, as they appear on your file system, sorted by file name

Notice how projects imports get data from Git using manifest-rev, while self imports get data from your file system. This is because as usual, west leaves version control for your manifest repository up to you.
Example 2.1: Downstream of a Zephyr release with explicit path  This is an explicit way to write an equivalent manifest to the one in Example 1.1: Downstream of a Zephyr release.

```yaml
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: v1.14.1
      import: west.yml
```

The setting `import: west.yml` means to use the file `west.yml` inside the `zephyr` project. This example is contrived, but shows the idea.

This can be useful in practice when the name of the manifest file you want to import is not `west.yml`.

Example 2.2: Downstream with directory of manifest files  Your Zephyr downstream has a lot of additional repositories. So many, in fact, that you want to split them up into multiple manifest files, but keep track of them all in a single manifest repository, like this:

```
# my-repo/
  └── submanifests
      ├── 01-libraries.yml
      │   └── 02-vendor-hals.yml
      │   └── 03-applications.yml
      └── west.yml
```

You want to add all the files in `my-repo/submanifests` to the main manifest file, `my-repo/west.yml`, in addition to projects in `zephyr/west.yml`. You want to track the latest development code in the Zephyr repository's main branch instead of using a fixed revision.

Here's how:

```
# my-repo/west.yml:
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: main
      import: true
  self:
    import: submanifests
```

Manifest files are imported in this order during resolution:

1. `my-repo/submanifests/01-libraries.yml`
2. `my-repo/submanifests/02-vendor-hals.yml`
3. `my-repo/submanifests/03-applications.yml`
4. `my-repo/west.yml`
5. `zephyr/west.yml`

Note: The `.yml` file names are prefixed with numbers in this example to make sure they are imported in the specified order.
You can pick arbitrary names. West sorts files in a directory by name before importing.

Notice how the manifests in submanifests are imported before my-repo/west.yml and zephyr/west.yml. In general, an import in the self section is processed before the manifest files in projects and the main manifest file.

This means projects defined in my-repo/submanifests take highest precedence. For example, if 01-libraries.yml defines hal_nordic, the project by the same name in zephyr/west.yml is simply ignored. As usual, see Resolving Manifests for troubleshooting advice.

This may seem strange, but it allows you to redefine projects “after the fact”, as we’ll see in the next example.

**Example 2.3: Continuous Integration overrides**  Your continuous integration system needs to fetch and test multiple repositories in your west workspace from a developer's forks instead of your mainline development trees, to see if the changes all work well together.

Starting with **Example 2.2: Downstream with directory of manifest files**, the CI scripts add a file 00-ci.yml in my-repo/submanifests, with these contents:

```yaml
# my-repo/submanifests/00-ci.yml:
manifest:
  projects:
    - name: a-vendor-hal
      url: https://github.com/a-developer/hal
      revision: a-pull-request-branch
    - name: an-application
      url: https://github.com/a-developer/application
      revision: another-pull-request-branch
```

The CI scripts run west update after generating this file in my-repo/submanifests. The projects defined in 00-ci.yml have higher precedence than other definitions in my-repo/submanifests, because the name 00-ci.yml comes before the other file names.

Thus, west update always checks out the developer's branches in the projects named a-vendor-hal and an-application, even if those same projects are also defined elsewhere.

**Option 3: Mapping**  The import key can also contain a mapping with the following keys:

- **file**: Optional. The name of the manifest file or directory to import. This defaults to west.yml if not present.
- **name-allowlist**: Optional. If present, a name or sequence of project names to include.
- **path-allowlist**: Optional. If present, a path or sequence of project paths to match against. This is a shell-style globbing pattern, currently implemented with pathlib. Note that this means case sensitivity is platform specific.
- **name-blocklist**: Optional. Like name-allowlist, but contains project names to exclude rather than include.
- **path-blocklist**: Optional. Like path-allowlist, but contains project paths to exclude rather than include.
- **path-prefix**: Optional (new in v0.8.0). If given, this will be prepended to the project's path in the workspace, as well as the paths of any imported projects. This can be used to place these projects in a subdirectory of the workspace.

Allowlists override blocklists if both are given. For example, if a project is blocked by path, then allowed by name, it will still be imported.
**Example 3.1: Downstream with name allowlist**  Here is a pair of manifest files, representing a mainline and a downstream. The downstream doesn't want to use all the mainline projects, however. We'll assume the mainline west.yml is hosted at https://git.example.com/mainline/manifest.

```yaml
# mainline west.yml:
manifest:
  projects:
    - name: mainline-app      # included
      path: examples/app
      url: https://git.example.com/mainline/app
    - name: lib
      path: libraries/lib
      url: https://git.example.com/mainline/lib
    - name: lib2                # included
      path: libraries/lib2
      url: https://git.example.com/mainline/lib2

# downstream west.yml:
manifest:
  projects:
    - name: mainline
      url: https://git.example.com/mainline/manifest
    - name: downstream-app
      url: https://git.example.com/downstream/app
    - name: lib
      path: libraries/lib3
      url: https://git.example.com/downstream/lib3
    - name: mainline-app       # imported
      path: examples/app
      url: https://git.example.com/mainline/app
    - name: lib2                # imported
      path: libraries/lib2
      url: https://git.example.com/mainline/lib2
```

An equivalent manifest in a single file would be:

```yaml
manifest:
  projects:
    - name: mainline
      url: https://git.example.com/mainline/manifest
    - name: downstream-app
      url: https://git.example.com/downstream/app
    - name: lib
      path: libraries/lib3
      url: https://git.example.com/downstream/lib3
    - name: mainline-app       # imported
      path: examples/app
      url: https://git.example.com/mainline/app
    - name: lib2                # imported
      path: libraries/lib2
      url: https://git.example.com/mainline/lib2
```

If an allowlist had not been used, the lib project from the mainline manifest would have been imported.

**Example 3.2: Downstream with path allowlist**  Here is an example showing how to allowlist mainline's libraries only, using path-allowlist.

```yaml
# mainline west.yml:
manifest:
  projects:
    - name: app
```
path: examples/app
url: https://git.example.com/mainline/app
  - name: lib
    path: libraries/lib  # included
    url: https://git.example.com/mainline/lib
  - name: lib2
    path: libraries/lib2  # included
    url: https://git.example.com/mainline/lib2

# downstream west.yml:
manifest:
  projects:
    - name: mainline
      url: https://git.example.com/mainline/manifest
      import:
        path-allowlist: libraries/*
    - name: app
      url: https://git.example.com/downstream/app
    - name: lib3
      path: libraries/lib3
      url: https://git.example.com/downstream/lib3

An equivalent manifest in a single file would be:

manifest:
  projects:
    - name: lib  # imported
      path: libraries/lib
      url: https://git.example.com/mainline/lib
    - name: lib2  # imported
      path: libraries/lib2
      url: https://git.example.com/mainline/lib2
    - name: mainline
      url: https://git.example.com/mainline/manifest
    - name: app
      url: https://git.example.com/downstream/app
    - name: lib3
      path: libraries/lib3
      url: https://git.example.com/downstream/lib3

**Example 3.3: Downstream with path blocklist**  Here's an example showing how to block all vendor HALs from mainline by common path prefix in the workspace, add your own version for the chip you’re targeting, and keep everything else.

# mainline west.yml:
manifest:
defaults:
  remote: mainline
remotes:
  - name: mainline
    url-base: https://git.example.com/mainline
projects:
  - name: app
  - name: lib
    path: libraries/lib
  - name: lib2
    path: libraries/lib2
  - name: hal_foo
    path: modules/hals/foo  # excluded
An equivalent manifest in a single file would be:

```
manifest:
  defaults:
    remote: example
  remotes:
    - name: example
      url-base: https://git.example.com
  projects:
    - name: bar
      # imported
    - name: baz
      # imported
    - name: hal_foo
      path: modules/hals/foo
      url: https://git.example.com/downstream/hal_foo
```

### Example 3.4: Import into a subdirectory

You want to import a manifest and its projects, placing everything into a subdirectory of your *west workspace*.

For example, suppose you want to import this manifest from project foo, adding this project and its projects bar and baz to your workspace:

```
# foo/west.yml:
manifest:
  defaults:
    remote: example
  remotes:
    - name: example
      url-base: https://git.example.com
  projects:
    - name: bar
      # imported
    - name: baz
      # imported
    - name: hal_foo
      path: modules/hals/foo
      url: https://git.example.com/downstream/hal_foo
```

Instead of importing these into the top level workspace, you want to place all three project repositories in an *external-code* subdirectory, like this:

```
workspace/
  └── external-code/
      └── foo/
```

You can do this using this manifest:

```
manifest:
  projects:
    - name: foo
      url: https://git.example.com/foo
      import:
        path-prefix: external-code
```

An equivalent manifest in a single file would be:

```
# foo/west.yml:
manifest:
  defaults:
    remote: example
  remotes:
    - name: example
      url-base: https://git.example.com
  projects:
    - name: foo
      path: external-code/foo
    - name: bar
      path: external-code/bar
    - name: baz
      path: external-code/baz
```

**Option 4: Sequence**  The `import` key can also contain a sequence of files, directories, and mappings.

**Example 4.1: Downstream with sequence of manifest files**  This example manifest is equivalent to the manifest in **Example 2.2: Downstream with directory of manifest files**, with a sequence of explicitly named files.

```
# my-repo/west.yml:
manifest:
  # ...
  projects:
    - name: zephyr
      url: https://github.com/zephyrproject-rtos/zephyr
      import: west.yml
    self:
      import:
        - submanifests/01-libraries.yml
        - submanifests/02-vendor-hals.yml
        - submanifests/03-applications.yml
```

**Example 4.2: Import order illustration**  This more complicated example shows the order that west imports manifest files:

```
# my-repo/west.yml
manifest:
  # ...
  projects:
    - name: my-library
```

(continues on next page)
For this example, west resolves imports in this order:

1. The listed files in my-repo/submanifests are first, in the order they occur (e.g. libraries.yml comes before applications.yml, since this is a sequence of files), since the self: import: is always imported first.

2. my-repo/west.yml is next (with projects my-library etc. as long as they weren’t already defined somewhere in submanifests).

3. zephyr/west.yml is after that, since that’s the first import key in the projects list in my-repo/west.yml.

4. Files in another-manifest-repo/submanifests are last (sorted by file name), since that’s the final project import.

**Manifest Import Details**

This section describes how west resolves a manifest file that uses import a bit more formally.

**Overview**

The import key can appear in a west manifest’s projects and self sections. The general case looks like this:

```yaml
# Top-level manifest file.
manifest:
  projects:
    - name: foo
      import: ...
      # import-1
    - name: bar
      import: ...
      # import-2
    # ...
    - name: baz
      import: ...
      # import-N
  self:
    import: ...
    # self-import
```

Import keys are optional. If any of import-1, ..., import-N are missing, west will not import additional manifest data from that project. If self-import is missing, no additional files in the manifest repository (beyond the top-level file) are imported.

The ultimate outcomes of resolving manifest imports are:

- a projects list, which is produced by combining the projects defined in the top-level file with those defined in imported files.
a set of extension commands, which are drawn from the west-commands keys in the top-level file and any imported files

- a group-filter list, which is produced by combining the top-level and any imported filters

Importing is done in this order:

1. Manifests from self-import are imported first.
2. The top-level manifest file's definitions are handled next.
3. Manifests from import-1, ..., import-N, are imported in that order.

When an individual import key refers to multiple manifest files, they are processed in this order:

- If the value is a relative path naming a directory (or a map whose file is a directory), the manifest files it contains are processed in lexicographic order – i.e., sorted by file name.
- If the value is a sequence, its elements are recursively imported in the order they appear.

This process recurses if necessary. E.g., if import-1 produces a manifest file that contains an import key, it is resolved recursively using the same rules before its contents are processed further.

The following sections describe these outcomes.

Projects

This section describes how the final projects list is created.

Projects are identified by name. If the same name occurs in multiple manifests, the first definition is used, and subsequent definitions are ignored. For example, if import-1 contains a project named bar, that is ignored, because the top-level west.yml has already defined a project by that name.

The contents of files named by import-1 through import-N are imported from Git at the latest manifest-rev revisions in their projects. These revisions can be updated to the values rev-1 through rev-N by running west update. If any manifest-rev reference is missing or out of date, west update also fetches project data from the remote fetch URL and updates the reference.

Also note that all imported manifests, from the root manifest to the repository which defines a project P, must be up to date in order for west to update P itself. For example, this means west update P would update manifest-rev in the baz project if baz/west.yml defines P, as well as updating the manifest-rev branch in the local git clone of P. Confusingly, updating baz may result in the removal of P from baz/west.yml, which “should” cause west update P to fail with an unrecognized project!

For this reason, it’s not possible to run west update P if P is defined in an imported manifest; you must update this project along with all the others with a plain west update.

By default, west won’t fetch any project data over the network if a project’s revision is a SHA or tag which is already available locally, so updating the extra projects shouldn’t take too much time unless it’s really needed. See the documentation for the update.fetch configuration option for more information.

Extensions

All extension commands defined using west-commands keys discovered while handling imports are available in the resolved manifest.

If an imported manifest file has a west-commands: definition in its self: section, the extension commands defined there are added to the set of available extensions at the time the manifest is imported. They will thus take precedence over any extension commands with the same names added later on.
Group filters   The resolved manifest has a group-filter value which is the result of concatenating the group-filter values in the top-level manifest and any imported manifests.

Manifest files which appear earlier in the import order have higher precedence and are therefore concatenated later into the final group-filter.

In other words, let:

• the submanifest resolved from self-import have group filter self-filter
• the top-level manifest file have group filter top-filter
• the submanifests resolved from import-1 through import-N have group filters filter-1 through filter-N respectively

The final resolved group-filter value is then filterN + ... + filter-2 + filter-1 + top-filter + self-filter, where + here refers to list concatenation.

Important: The order that filters appear in the above list matters.
The last filter element in the final concatenated list “wins” and determines if the group is enabled or disabled.

For example, in [-foo] + [+foo], group foo is enabled. However, in [+foo] + [-foo], group foo is disabled.

For simplicity, west and this documentation may elide concatenated group filter elements which are redundant using these rules. For example, [+foo] + [-foo] could be written more simply as [-foo], for the reasons given above. As another example, [-foo] + [+foo] could be written as the empty list [], since all groups are enabled by default.

Manifest Command

The west manifest command can be used to manipulate manifest files. It takes an action, and action-specific arguments.

The following sections describe each action and provides a basic signature for simple uses. Run west manifest --help for full details on all options.

Resolving Manifests   The --resolve action outputs a single manifest file equivalent to your current manifest and all its imported manifests:

```
west manifest --resolve [-o outfile]
```

The main use for this action is to see the “final” manifest contents after performing any imports.

To print detailed information about each imported manifest file and how projects are handled during manifest resolution, set the maximum verbosity level using -v:

```
west -v manifest --resolve
```

Freezing Manifests   The --freeze action outputs a frozen manifest:

```
west manifest --freeze [-o outfile]
```

A “frozen” manifest is a manifest file where every project’s revision is a SHA. You can use --freeze to produce a frozen manifest that’s equivalent to your current manifest file. The -o option specifies an output file; if not given, standard output is used.
Validating Manifests  The `--validate` action either succeeds if the current manifest file is valid, or fails with an error:

```
west manifest --validate
```

The error message can help diagnose errors.

Here, “invalid” means that the syntax of the manifest file doesn’t follow the rules documented on this page.

If your manifest is valid but it’s not working the way you want it to, turning up the verbosity with `--v` is a good way to get detailed information about what decisions west made about your manifest, and why:

```
w west -v manifest --validate
```

Get the manifest path  The `--path` action prints the path to the top level manifest file:

```
w west manifest --path
```

The output is something like /path/to/workspace/west.yml. The path format depends on your operating system.

2.11.8  Configuration

This page documents west’s configuration file system, the `west config` command, and configuration options used by built-in commands. For API documentation on the `west.configuration` module, see west-apis-configuration.

West Configuration Files

West’s configuration file syntax is INI-like; here is an example file:

```
[manifest]
path = zephyr

[zephyr]
base = zephyr
```

Above, the manifest section has option path set to zephyr. Another way to say the same thing is that manifest.path is zephyr in this file.

There are three types of configuration file:

1. System: Settings in this file affect west’s behavior for every user logged in to the computer. Its location depends on the platform:
   - Linux: /etc/westconfig
   - macOS: /usr/local/etc/westconfig
   - Windows: %PROGRAMDATA%\west\config

2. Global (per user): Settings in this file affect how west behaves when run by a particular user on the computer:
   - All platforms: the default is .westconfig in the user’s home directory.
   - Linux note: if the environment variable XDG_CONFIG_HOME is set, then $XDG_CONFIG_HOME/west/config is used.

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• Windows note: the following environment variables are tested to find the home directory:
  %HOME%, then %USERPROFILE%, then a combination of %HOMEDRIVE% and %HOMEPATH%.

3. **Local**: Settings in this file affect west's behavior for the current *west workspace*. The file is
  `.west/config`, relative to the workspace's root directory.

A setting in a file which appears lower down on this list overrides an earlier setting. For example, if `color.ui` is true in the system's configuration file, but false in the workspace's, then the final value is false. Similarly, settings in the user configuration file override system settings, and so on.

**west config**

The built-in `config` command can be used to get and set configuration values. You can pass `west config` the options `--system`, `--global`, or `--local` to specify which configuration file to use. Only one of these can be used at a time. If none is given, then writes default to `--local`, and reads show the final value after applying overrides.

Some examples for common uses follow; run `west config --h` for detailed help, and see *Built-in Configuration Options* for more details on built-in options.

To set `manifest.path` to `some-other-manifest`:

```
west config manifest.path some-other-manifest
```

Doing the above means that commands like `west update` will look for the `west manifest` inside the `some-other-manifest` directory (relative to the workspace root directory) instead of the directory given to `west init`, so be careful!

To read `zephyr.base`, the value which will be used as `ZEPHYR_BASE` if it is unset in the calling environment (also relative to the workspace root):

```
wes t config zephyr.base
```

You can switch to another zephyr repository without changing `manifest.path` – and thus the behavior of commands like `west update` – using:

```
west config zephyr.base some-other-zephyr
```

This can be useful if you use commands like `git worktree` to create your own zephyr directories, and want commands like `west build` to use them instead of the zephyr repository specified in the manifest. (You can go back to using the directory in the upstream manifest by running `west config zephyr.base zephyr`.)

To set `color.ui` to false in the global (user-wide) configuration file, so that west will no longer print colored output for that user when run in any workspace:

```
wes t config --global color.ui false
```

To undo the above change:

```
wes t config --global color.ui true
```

**Built-in Configuration Options**

The following table documents configuration options supported by west's built-in commands. Configuration options supported by Zephyr’s extension commands are documented in the pages for those commands.
<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>color.ui</td>
<td>Boolean. If true (the default), then west output is colorized when stdout is a terminal.</td>
</tr>
<tr>
<td>commands.allow_extensions</td>
<td>Boolean, default true, disables Extensions if false</td>
</tr>
<tr>
<td>grep.color</td>
<td>String, default empty. Set this to never to disable west grep color output. If set, west grep passes the value to the grep tool's --color option.</td>
</tr>
<tr>
<td>grep.tool</td>
<td>String, one of &quot;git-grep&quot; (default), &quot;ripgrep&quot;, or &quot;grep&quot;. The grep tool that west grep should use.</td>
</tr>
<tr>
<td>grep.&lt;TOOL&gt;-args</td>
<td>String, default empty. The &lt;TOOL&gt; part is a pattern that can be any grep.tool value, so grep.ripgrep-args is an example configuration option.</td>
</tr>
<tr>
<td>grep.&lt;TOOL&gt;-path</td>
<td>String, default empty. The &lt;TOOL&gt; part is a pattern that can be any grep.tool value, so grep.ripgrep-path is an example configuration option. The path to the corresponding tool that west grep should use instead of searching for the command. Run west help grep for details.</td>
</tr>
<tr>
<td>manifest.file</td>
<td>String, default west.yml. Relative path from the manifest repository root directory to the manifest file used by west init and other commands which parse the manifest.</td>
</tr>
<tr>
<td>manifest.group-filter</td>
<td>String, default empty. A comma-separated list of project groups to enable and disable within the workspace. Prefix enabled groups with + and disabled groups with -. For example, the value &quot;+foo,-bar&quot; enables group foo and disables bar. See Project Groups.</td>
</tr>
<tr>
<td>manifest.path</td>
<td>String, relative path from the manifest repository root directory to the manifest file used by west init and other commands which parse the manifest. Set locally by west init.</td>
</tr>
<tr>
<td>manifest.project-filter</td>
<td>Comma-separated list of strings.</td>
</tr>
</tbody>
</table>

The option's value is a comma-separated list of regular expressions, each prefixed with + or -, like this:

```
+re1,-re2,-re3
```

Project names are matched against each regular expression (re1, re2, re3, ...) in the list, in order. If the entire project name matches the regular expression, that element of the list either deactivates or activates the project. The project is deactivated if the element begins with -. The project is activated if the element begins with +. (Project names cannot contain , if this option is used, so the regular expressions do not need to contain a literal , character.)

If a project's name matches multiple regular expressions in the list, the result from the last regular expression is used. For example, if manifest.project-filter is:

```
-hal_,-*,+hal_foo
```

Then a project named hal_bar is inactive, but a project named hal_foo is active.

If a project is made inactive or active by a list element, the project is active or not regardless of whether any or all of its groups are disabled. (This is currently the only way to make a project that has no groups inactive.)

Otherwise, i.e. if a project does not match any regular expressions in the list, it is active or inactive according to the usual rules related to its groups (see Project Group Examples for examples in that case).

Within an element of a manifest.project-filter list, leading and trailing whitespace are ignored. That means these example values are equivalent:

```
+foo,-bar
```

-foo,-bar

Any empty elements are ignored. That means these example values are equivalent:

```
+foo,-bar
```

-foo,-bar

---

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2.11.9 Extensions

West is “pluggable”: you can add your own commands to west without editing its source code. These are called west extension commands, or just “extensions” for short. Extensions show up in the west --help output in a special section for the project which defines them. This page provides general information on west extension commands, and has a tutorial for writing your own.

Some commands you can run when using west with Zephyr, like the ones used to build, flash, and debug and the ones described here, are extensions. That’s why help for them shows up like this in west --help:

<table>
<thead>
<tr>
<th>Commands from project at “zephyr”:</th>
</tr>
</thead>
<tbody>
<tr>
<td>completion: display shell completion scripts</td>
</tr>
<tr>
<td>boards: display information about supported boards</td>
</tr>
<tr>
<td>build: compile a Zephyr application</td>
</tr>
<tr>
<td>sign: sign a Zephyr binary for bootloader chain-loading</td>
</tr>
<tr>
<td>flash: flash and run a binary on a board</td>
</tr>
<tr>
<td>debug: flash and interactively debug a Zephyr application</td>
</tr>
<tr>
<td>debugserver: connect to board and launch a debug server</td>
</tr>
<tr>
<td>attach: interactively debug a board</td>
</tr>
</tbody>
</table>

See zephyr/scripts/west-commands.yml and the zephyr/scripts/west_commands directory for the implementation details.

Disabling Extension Commands

To disable support for extension commands, set the commands.allow_extensions configuration option to false. To set this globally for whenever you run west, use:

```
west config --global commands.allow_extensions false
```

If you want to, you can then re-enable them in a particular west workspace with:

```
west config --local commands.allow_extensions true
```

Note that the files containing extension commands are not imported by west unless the commands are explicitly run. See below for details.

Adding a West Extension

There are three steps to adding your own extension:

1. Write the code implementing the command.
2. Add information about it to a west-commands.yml file.
3. Make sure the west-commands.yml file is referenced in the west manifest.

Note that west ignores extension commands whose names are the same as a built-in command.

**Step 1: Implement Your Command**  Create a Python file to contain your command implementation (see the “Meta > Requires” information on the west PyPI page for details on the currently supported versions of Python). You can put it in anywhere in any project tracked by your west manifest, or the manifest repository itself. This file must contain a subclass of the west.commands.WestCommand class; this class will be instantiated and used when your extension is run.

Here is a basic skeleton you can use to get started. It contains a subclass of WestCommand, with implementations for all the abstract methods. For more details on the west APIs you can use, see west-apis.
Basic example of a west extension.''

```python
from textwrap import dedent  # just for nicer code indentation
from west.commands import WestCommand  # your extension must subclass this
from west import log  # use this for user output

class MyCommand(WestCommand):
    def __init__(self):
        super().__init__(
            'my-command-name',  # gets stored as self.name
            'one-line help for what my-command-name does',  # self.help
            # self.description:
            dedent(''
                A multi-line description of my-command.
            ''),
            # You can split this up into multiple paragraphs and they'll get
            # reflowed for you. You can also pass
            # formatter_class=argparse.RawDescriptionHelpFormatter when calling
            # parser_adder.add_parser() below if you want to keep your line
            # endings.'''))

    def do_add_parser(self, parser_adder):
        # This is a bit of boilerplate, which allows you full control over the
        # type of argparse handling you want. The "parser_adder" argument is
        # the return value of an argparse.ArgumentParser.add_subparsers() call.
        parser = parser_adder.add_parser(
            self.name,  # gets stored as self.name
            help=self.help,
            description=self.description)

        # Add some example options using the standard argparse module API.
        parser.add_argument('-o', '--optional', help='an optional argument')
        parser.add_argument('required', help='a required argument')

        return parser  # gets stored as self.parser

    def do_run(self, args, unknown_args):
        # This gets called when the user runs the command, e.g.:
        #
        # $ west my-command-name -o FOO BAR
        # --optional is FOO
        # required is BAR
        log.info('--optional is', args.optional)
        log.info('required is', args.required)
```

You can ignore the second argument to do_run() (unknown_args above), as WestCommand will reject unknown arguments by default. If you want to be passed a list of unknown arguments instead, add accepts_unknown_args=True to the super().__init__() arguments.

**Step 2: Add or Update Your west-commands.yml** You now need to add a west-commands.yml file to your project which describes your extension to west.

Here is an example for the above class definition, assuming it's in my_west_extension.py at the project root directory:

```yaml
west-commands:
  - file: my_west_extension.py
```

(continues on next page)
The top level of this YAML file is a map with a `west-commands` key. The key's value is a sequence of “command descriptors”. Each command descriptor gives the location of a file implementing west extensions, along with the names of those extensions, and optionally the names of the classes which define them (if not given, the class value defaults to the same thing as name).

Some information in this file is redundant with definitions in the Python code. This is because west won’t import `my_west_extension.py` until the user runs `west my-command-name`, since:

- It allows users to run `west update` with a manifest from an untrusted source, then use other west commands without your code being imported along the way. Since importing a Python module is shell-equivalent, this provides some peace of mind.

- It’s a small optimization, since your code will only be imported if it is needed.

So, unless your command is explicitly run, west will just load the `west-commands.yml` file to get the basic information it needs to display information about your extension to the user in `west --help` output, etc.

If you have multiple extensions, or want to split your extensions across multiple files, your `west-commands.yml` will look something like this:

```yaml
west-commands:
  - file: my_west_extension.py
    commands:
      - name: my-command-name
        class: MyCommand
        help: one-line help for what my-command-name does
  - file: another_file.py
    commands:
      - name: command2
        help: another cool west extension
      - name: a-third-command
        class: ThirdCommand
        help: a third command in the same file as command2
```

Above:

- `my_west_extension.py` defines extension `my-command-name` with class `MyCommand`
- `another_file.py` defines two extensions:
  1. `command2` with class `command2`
  2. `a-third-command` with class `ThirdCommand`

See the file `west-commands-schema.yml` in the west repository for a schema describing the contents of a `west-commands.yml`.

**Step 3: Update Your Manifest** Finally, you need to specify the location of the `west-commands.yml` you just edited in your west manifest. If your extension is in a project, add it like this:

```yaml
manifest:
  # [... other contents ...]

projects:
  - name: your-project
    west-commands: path/to/west-commands.yml
  # [... other projects ...]
```
Where `path/to/west-commands.yml` is relative to the root of the project. Note that the name `west-commands.yml`, while encouraged, is just a convention; you can name the file something else if you need to.

Alternatively, if your extension is in the manifest repository, just do the same thing in the manifest's `self` section, like this:

```yaml
manifest:
  # [...] other contents ...]
  self:
    west-commands: path/to/west-commands.yml
```

That’s it; you can now run `west my-command-name`. Your command’s name, help, and the project which contains its code will now also show up in the `west --help` output. If you share the updated repositories with others, they’ll be able to use it, too.

## 2.11.10 Building, Flashing and Debugging

Zephyr provides several `west` extension commands for building, flashing, and interacting with Zephyr programs running on a board: `build`, `flash`, `debug`, `debugserver` and `attach`.

For information on adding board support for the flashing and debugging commands, see `Flash and debug support` in the board porting guide.

### Building: `west build`

**Tip:** Run `west build -h` for a quick overview.

The `build` command helps you build Zephyr applications from source. You can use `west config` to configure its behavior.

Its default behavior tries to “do what you mean”:

- If there is a Zephyr build directory named `build` in your current working directory, it is incrementally re-compiled. The same is true if you run `west build` from a Zephyr build directory.
- Otherwise, if you run `west build` from a Zephyr application’s source directory and no build directory is found, a new one is created and the application is compiled in it.

**Basics** The easiest way to use `west build` is to go to an application’s root directory (i.e. the folder containing the application’s `CMakeLists.txt`) and then run:

```
west build -b <BOARD>
```

Where `<BOARD>` is the name of the board you want to build for. This is exactly the same name you would supply to CMake if you were to invoke it with: `cmake -DBOARD=<BOARD>`.

**Tip:** You can use the `west boards` command to list all supported boards.

A build directory named `build` will be created, and the application will be compiled there after `west build` runs CMake to create a build system in that directory. If `west build` finds an existing build directory, the application is incrementally re-compiled there without re-running CMake. You can force CMake to run again with `--cmake`.
You don’t need to use the `--board` option if you’ve already got an existing build directory; `west build` can figure out the board from the CMake cache. For new builds, the `--board` option, `BOARD` environment variable, or `build.board` configuration option are checked (in that order).

**Sysbuild (multi-domain builds)**  
`Sysbuild (System build)` can be used to create a multi-domain build system combining multiple images for a single or multiple boards.

Use `--sysbuild` to select the `Sysbuild (System build)` build infrastructure with `west build` to build multiple domains.

More detailed information regarding the use of sysbuild can be found in the `Sysbuild (System build)` guide.

**Tip:** The `build.sysbuild` configuration option can be enabled to tell `west build` to default build using sysbuild. `--no-sysbuild` can be used to disable sysbuild for a specific build.

`west build` will build all domains through the top-level build folder of the domains specified by sysbuild.

A single domain from a multi-domain project can be built by using `--domain` argument.

**Examples**  
Here are some `west build` usage examples, grouped by area.

**Forcing CMake to Run Again**  
To force a CMake re-run, use the `--cmake` (or `-c`) option:

```
west build -c
```

**Setting a Default Board**  
To configure `west build` to build for the `reel_board` by default:

```
west config build.board reel_board
```

(You can use any other board supported by Zephyr here; it doesn’t have to be `reel_board`.)

**Setting Source and Build Directories**  
To set the application source directory explicitly, give its path as a positional argument:

```
wes t build -b <BOARD> path/to/source/directory
```

To set the build directory explicitly, use `--build-dir` (or `-d`):

```
wes t build -b <BOARD> --build-dir path/to/build/directory
```

To change the default build directory from `build`, use the `build.dir-fmt` configuration option. This lets you name build directories using format strings, like this:

```
wes t config build.dir-fmt "build/{board}/{app}"
```

With the above, running `west build -b reel_board samples/hello_world` will use build directory `build/reel_board/hello_world`. See `Configuration Options` for more details on this option.
Setting the Build System Target  To specify the build system target to run, use --target (or -t).

For example, on host platforms with QEMU, you can use the run target to build and run the hello_world sample for the emulated qemu_x86 board in one command:

```
west build -b qemu_x86 -t run samples/hello_world
```

As another example, to use -t to list all build system targets:

```
west build -t help
```

As a final example, to use -t to run the pristine target, which deletes all the files in the build directory:

```
west build -t pristine
```

Pristine Builds  A pristine build directory is essentially a new build directory. All byproducts from previous builds have been removed.

To force west build make the build directory pristine before re-running CMake to generate a build system, use the --pristine=always (or -p=always) option.

Giving --pristine or -p without a value has the same effect as giving it the value always. For example, these commands are equivalent:

```
west build -p -b reel_board samples/hello_world
west build -p=always -b reel_board samples/hello_world
```

By default, west build makes no attempt to detect if the build directory needs to be made pristine. This can lead to errors if you do something like try to reuse a build directory for a different --board.

Using --pristine=auto makes west build detect some of these situations and make the build directory pristine before trying the build.

Tip: You can run west config build.pristine always to always do a pristine build, or west config build.pristine never to disable the heuristic. See the west build Configuration Options for details.

Verbose Builds  To print the CMake and compiler commands run by west build, use the global west verbosity option, -v:

```
west -v build -b reel_board samples/hello_world
```

One-Time CMake Arguments  To pass additional arguments to the CMake invocation performed by west build, pass them after a -- at the end of the command line.

Important: Passing additional CMake arguments like this forces west build to re-run the CMake build configuration step, even if a build system has already been generated. This will make incremental builds slower (but still much faster than building from scratch).

After using -- once to generate the build directory, use west build -d <build-dir> on subsequent runs to do incremental builds.
Alternatively, make your CMake arguments permanent as described in the next section; it will not slow down incremental builds.

For example, to use the Unix Makefiles CMake generator instead of Ninja (which `west build` uses by default), run:

```
west build -b reel_board -- -G'Unix Makefiles'
```

To use Unix Makefiles and set `CMAKE_VERBOSE_MAKEFILE` to ON:

```
west build -b reel_board -- -G'Unix Makefiles' -DCMAKE_VERBOSE_MAKEFILE=ON
```

Notice how the `--` only appears once, even though multiple CMake arguments are given. All command-line arguments to `west build` after a `--` are passed to CMake.

To set `DTC_OVERLAY_FILE` to enable-modem.overlay, using that file as a devicetree overlay:

```
w west build -b reel_board -- -DDTC_OVERLAY_FILE=enable-modem.overlay
```

To merge the `file.conf` Kconfig fragment into your build's `.config`:

```
w west build -- -DEXTRA_CONF_FILE=file.conf
```

### Permanent CMake Arguments

The previous section describes how to add CMake arguments for a single `west build` command. If you want to save CMake arguments for `west build` to use every time it generates a new build system instead, you should use the `build.cmake-args` configuration option. Whenever `west build` runs CMake to generate a build system, it splits this option's value according to shell rules and includes the results in the `cmake` command line.

Remember that, by default, `west build` tries to avoid generating a new build system if one is present in your build directory. Therefore, you need to either delete any existing build directories or do a pristine build to make sure it will take effect.

For example, to always enable `CMAKE_EXPORT_COMPILE_COMMANDS`, you can run:

```
w west config build.cmake-args -- -DCMAKE_EXPORT_COMPILE_COMMANDS=ON
```

(The extra `--` is used to force the rest of the command to be treated as a positional argument. Without it, `west config` would treat the `~DVAR=VAL` syntax as a use of its `~D` option.)

To enable `CMAKE_VERBOSE_MAKEFILE`, so CMake always produces a verbose build system:

```
w west config build.cmake-args -- -DCMAKE_VERBOSE_MAKEFILE=ON
```

To save more than one argument in `build.cmake-args`, use a single string whose value can be split into distinct arguments (`west build` uses the Python function `shlex.split()` internally to split the value).

For example, to enable both `CMAKE.Export_COMPILE_COMMANDS` and `CMAKE_VERBOSE_MAKEFILE`:

```
w west config build.cmake-args -- "-DCMAKE_EXPORT_COMPILE_COMMANDS=ON -DCMAKE_VERBOSE_MAKEFILE=ON"
```

If you want to save your CMake arguments in a separate file instead, you can combine CMake's `-C <initial-cache>` option with `build.cmake-args`. For instance, another way to set the options used in the previous example is to create a file named `~/my-cache.cmake` with the following contents:

```bash
set(CMAKE.Export_COMPILE_COMMANDS ON CACHE BOOL"
set(CMAKE_VERBOSE_MAKEFILE ON CACHE BOOL"
```

Then run:

```
w west config build.cmake-args -C ~/my-cache.cmake
```
See the `cmake(1)` manual page and the `set()` command documentation for more details.

**Build tool arguments**  Use `-o` to pass options to the underlying build tool.
This works with both `ninja` (*the default*) and `make` based build systems.
For example, to pass `-dexplain` to `ninja`:

```
west build -o=-dexplain
```

As another example, to pass `--keep-going` to `make`:

```
west build -o==--keep-going
```

Note that using `-o=--foo` instead of `-o --foo` is required to prevent `--foo` from being treated as a `west build` option.

**Build parallelism**  By default, `ninja` uses all of your cores to build, while `make` uses only one.
You can control this explicitly with the `-j` option supported by both tools.
For example, to build with 4 cores:

```
west build -o=-j4
```

The `-o` option is described further in the previous section.

**Build a single domain**  In a multi-domain build with `hello_world` and `MCUboot`, you can use
`--domain hello_world` to only build this domain:

```
west build --sysbuild --domain hello_world
```

The `--domain` argument can be combined with the `--target` argument to build the specific target
for the target, for example:

```
west build --sysbuild --domain hello_world --target help
```

**Use a snippet**  See [Using Snippets](#).

**Configuration Options**  You can `configure` `west build` using these options.
### Options

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>build.board</td>
<td>String. If given, this is the board used by <code>west build</code> when <code>--board</code> is not given and <code>BOARD</code> is unset in the environment.</td>
</tr>
<tr>
<td>build.board_warn</td>
<td>Boolean, default true. If false, disables warnings when <code>west build</code> can't figure out the target board.</td>
</tr>
<tr>
<td>build.cmake-args</td>
<td>String. If present, the value will be split according to shell rules and passed to CMake whenever a new build system is generated. See <em>Permanent CMake Arguments</em>.</td>
</tr>
</tbody>
</table>
| build.dir-fmt | String, default build. The build folder format string, used by `west` whenever it needs to create or locate a build folder. The currently available arguments are:  
  - board: The board name  
  - source_dir: The relative path from the current working directory to the source directory. If the current working directory is inside the source directory this will be set to an empty string.  
  - app: The name of the source directory. |
| build.generator | String, default Ninja. The CMake Generator to use to create a build system. (To set a generator for a single build, see the above example) |
| build.guess-dir | String, instructs `west` whether to try to guess what build folder to use when `build.dir-fmt` is in use and not enough information is available to resolve the build folder name. Can take these values:  
  - never (default): Never try to guess, bail out instead and require the user to provide a build folder with `-d`.  
  - runners: Try to guess the folder when using any of the ‘runner’ commands. These are typically all commands that invoke an external tool, such as flash and debug. |
| build.pristine | String. Controls the way in which `west build` may clean the build folder before building. Can take the following values:  
  - never (default): Never automatically make the build folder pristine.  
  - auto: `west build` will automatically make the build folder pristine before building, if a build system is present and the build would fail otherwise (e.g. the user has specified a different board or application from the one previously used to make the build directory).  
  - always: Always make the build folder pristine before building, if a build system is present. |
| build.sysbuild | Boolean, default false. If true, build application using the sysbuild infrastructure. |

### Flashing: `west flash`

**Tip:** Run `west flash -h` for additional help.

### Basics

From a Zephyr build directory, re-build the binary and flash it to your board:

```sh
west flash
```

Without options, the behavior is the same as `ninja flash` (or `make flash`, etc.).
To specify the build directory, use `--build-dir` (or `-d`):

```
west flash --build-dir path/to/build/directory
```

If you don't specify the build directory, `west flash` searches for one in build, then the current working directory. If you set the `build.dir-fmt` configuration option (see Setting Source and Build Directories), `west flash` searches there instead of build.

**Choosing a Runner** If your board's Zephyr integration supports flashing with multiple programs, you can specify which one to use using the `--runner` (or `-r`) option. For example, if West flashes your board with `nrfjprog` by default, but it also supports JLink, you can override the default with:

```
west flash --runner jlink
```

You can override the default flash runner at build time by using the `BOARD_FLASH_RUNNER` CMake variable, and the debug runner with `BOARD_DEBUG_RUNNER`.

For example:

```
# Set the default runner to "jlink", overriding the board's
# usual default.
west build [...] -- -DBOARD_FLASH_RUNNER=jlink
```

See **One-Time CMake Arguments** and **Permanent CMake Arguments** for more information on setting CMake arguments.

See **Flash and debug runners** below for more information on the runner library used by West. The list of runners which support flashing can be obtained with `west flash -H`; if run from a build directory or with `--build-dir`, this will print additional information on available runners for your board.

**Configuration Overrides** The CMake cache contains default values West uses while flashing, such as where the board directory is on the file system, the path to the zephyr binaries to flash in several formats, and more. You can override any of this configuration at runtime with additional options.

For example, to override the HEX file containing the Zephyr image to flash (assuming your runner expects a HEX file), but keep other flash configuration at default values:

```
w west flash --hex-file path/to/some/other.hex
```

The `west flash -h` output includes a complete list of overrides supported by all runners.

**Runner-Specific Overrides** Each runner may support additional options related to flashing. For example, some runners support an `--erase` flag, which mass-erases the flash storage on your board before flashing the Zephyr image.

To view all of the available options for the runners your board supports, as well as their usage information, use `--context` (or `-H`):

```
w west flash --context
```

**Important:** Note the capital H in the short option name. This re-runs the build in order to ensure the information displayed is up to date!
When running West outside of a build directory, `west flash -H` just prints a list of runners. You can use `west flash -H -r <runner-name>` to print usage information for options supported by that runner.

For example, to print usage information about the jlink runner:

```
west flash -H -r jlink
```

**Multi-domain flashing**  When a *Sysbuild (multi-domain builds)* folder is detected, then `west flash` will flash all domains in the order defined by syssbuild.

It is possible to flash the image from a single domain in a multi-domain project by using `--domain`.

For example, in a multi-domain build with `hello_world` and `MCUboot`, you can use the `--domain hello_world` domain to only flash only the image from this domain:

```
west flash --domain hello_world
```

**Debugging: `west debug`, `west debugserver`**

**Tip:** Run `west debug -h` or `west debugserver -h` for additional help.

**Basics**  From a Zephyr build directory, to attach a debugger to your board and open up a debug console (e.g. a GDB session):

```
w west debug
```

To attach a debugger to your board and open up a local network port you can connect a debugger to (e.g. an IDE debugger):

```
w west debugserver
```

Without options, the behavior is the same as `ninja debug` and `ninja debugserver` (or `make debug`, etc.).

To specify the build directory, use `--build-dir` (or `-d`):

```
w west debug --build-dir path/to/build/directory
west debugserver --build-dir path/to/build/directory
```

If you don't specify the build directory, these commands search for one in `build`, then the current working directory. If you set the `build-dir-fmt` configuration option (see *Setting Source and Build Directories*), `west debug` searches there instead of `build`.

**Choosing a Runner**  If your board's Zephyr integration supports debugging with multiple programs, you can specify which one to use using the `--runner` (or `-r`) option. For example, if West debugs your board with `pyocd-gdbserver` by default, but it also supports JLink, you can override the default with:

```
w west debug --runner jlink
west debugserver --runner jlink
```

See *Flash and debug runners* below for more information on the `runner` library used by West. The list of runners which support debugging can be obtained with `west debug -H`; if run from a build directory or with `--build-dir`, this will print additional information on available runners for your board.
**Configuration Overrides** The CMake cache contains default values West uses for debugging, such as where the board directory is on the file system, the path to the zephyr binaries containing symbol tables, and more. You can override any of this configuration at runtime with additional options.

For example, to override the ELF file containing the Zephyr binary and symbol tables (assuming your runner expects an ELF file), but keep other debug configuration at default values:

```
west debug --elf-file path/to/some/other.elf
west debugserver --elf-file path/to/some/other.elf
```

The `west debug -h` output includes a complete list of overrides supported by all runners.

**Runner-Specific Overrides** Each runner may support additional options related to debugging. For example, some runners support flags which allow you to set the network ports used by debug servers.

To view all of the available options for the runners your board supports, as well as their usage information, use `--context` (or `-H`):

```
west debug --context
```

(The command `west debugserver --context` will print the same output.)

**Important:** Note the capital H in the short option name. This re-runs the build in order to ensure the information displayed is up to date!

When running West outside of a build directory, `west debug -H` just prints a list of runners. You can use `west debug -H -r <runner-name>` to print usage information for options supported by that runner.

For example, to print usage information about the jlink runner:

```
west debug -H -r jlink
```

**Multi-domain debugging** `west debug` can only debug a single domain at a time. When a `Sys-build (multi-domain builds)` folder is detected, `west debug` will debug the default domain specified by sysbuild.

The default domain will be the application given as the source directory. See the following example:

```
west build --sysbuild path/to/source/directory
```

For example, when building `hello_world` with MCUboot using sysbuild, `hello_world` becomes the default domain:

```
west build --sysbuild samples/hello_world
```

So to debug `hello_world` you can do:

```
west debug
```

or:

```
west debug --domain hello_world
```

If you wish to debug MCUboot, you must explicitly specify MCUboot as the domain to debug:
Flash and debug runners

The flash and debug commands use Python wrappers around various Flash & Debug Host Tools. These wrappers are all defined in a Python library at scripts/west_commands/runners. Each wrapper is called a runner. Runners can flash and/or debug Zephyr programs.

The central abstraction within this library is ZephyrBinaryRunner, an abstract class which represents runners. The set of available runners is determined by the imported subclasses of ZephyrBinaryRunner. ZephyrBinaryRunner is available in the runners.core module; individual runner implementations are in other submodules, such as runners.nrfjprog, runners.openocd, etc.

Hacking

This section documents the runners.core module used by the flash and debug commands. This is the core abstraction used to implement support for these features.

Warning: These APIs are provided for reference, but they are more “shared code” used to implement multiple extension commands than a stable API.

Developers can add support for new ways to flash and debug Zephyr programs by implementing additional runners. To get this support into upstream Zephyr, the runner should be added into a new or existing runners module, and imported from runners/__init__.py.

Note: The test cases in scripts/west_commands/tests add unit test coverage for the runners package and individual runner classes.

Please try to add tests when adding new runners. Note that if your changes break existing test cases, CI testing on upstream pull requests will fail.

Zephyr binary runner core interfaces

This provides the core ZephyrBinaryRunner class meant for public use, as well as some other helpers for concrete runner classes.

```python
class runners.core.BuildConfiguration(build_dir: str)
    This helper class provides access to build-time configuration.
    Configuration options can be read as if the object were a dict, either object['CONFIG_FOO']
    or object.get('CONFIG_FOO').
    Kconfig configuration values are available (parsed from .config).
    getboolean(option)
        If a boolean option is explicitly set to y or n, returns its value. Otherwise, falls back to False.

class runners.core.DeprecatedAction(option_strings, dest, nargs=None, const=None,
    default=None, type=None, choices=None, required=False, help=None, metavar=None)

class runners.core.FileType(value, names=None, *, module=None, qualname=None,
    type=None, start=1, boundary=None)```
exception runners.core.MissingProgram(program)
    FileNot FoundError subclass for missing program dependencies.

    No significant changes from the parent FileNotFoundError; this is useful for explicitly sig-
    naling that the file in question is a program that some class requires to proceed.

    The filename attribute contains the missing program.

class runners.core.NetworkPortHelper
    Helper class for dealing with local IP network ports.

    get_unused_ports(starting_from)
        Find unused network ports, starting at given values.
        starting_from is an iterable of ports the caller would like to use.

        The return value is an iterable of ports, in the same order; using the given values if
        they were unused, or the next sequentially available unused port otherwise.

        Ports may be bound between this call’s check and actual usage, so callers still need to
        handle errors involving returned ports.

class runners.core.RunnerCaps(commands: ~typing.Set[str] = <factory>,
    dev_id: bool = False,
    flash_addr: bool = False, erase: bool = False, reset: bool =
    False, tool_opt: bool = False, file: bool = False)

    This class represents a runner class’s capabilities.

    Each capability is represented as an attribute with the same name. Flag attributes are True
    or False.

    Available capabilities:
    • commands: set of supported commands; default is {'flash', 'debug', 'debugserver', 'at-
      tach'}.
    • dev_id: whether the runner supports device identifiers, in the form of an -i, –dev-id
      option. This is useful when the user has multiple debuggers connected to a single com-
      puter, in order to select which one will be used with the command provided.
    • flash_addr: whether the runner supports flashing to an arbitrary address. Default is
      False. If true, the runner must honor the –dt-flash option.
    • erase: whether the runner supports an –erase option, which does a mass-erase of the
      entire addressable flash on the target before flashing. On multi-core SoCs, this may
      only erase portions of flash specific to the actual target core. (This option can be useful
      for things like clearing out old settings values or other subsystem state that may affect
      the behavior of the zephyr image. It is also sometimes needed by SoCs which have
      flash-like areas that can’t be sector erased by the underlying tool before flashing; UICR
      on nRF SoCs is one example.)
    • reset: whether the runner supports a –reset option, which resets the device after a
      flash operation is complete.
    • tool_opt: whether the runner supports a –tool-opt (-O) option, which can be given mul-
      tiple times and is passed on to the underlying tool that the runner wraps.
    • file: whether the runner supports a –file option, which specifies exactly the file that
      should be used to flash, overriding any default discovered in the build directory.

class runners.core.RunnerConfig(build_dir: str, board_dir: str, elf_file: str | None,
    exe_file: str | None, bin_file: str | None, uF2_file: str | None,
    file: str | None, file_type: FileType | None =
    FileType.OTHER, gdb: str | None = None, openocd: str | None = None,
    openocd_search: List[str] = [])

    Runner execution-time configuration.
This is a common object shared by all runners. Individual runners can register specific configuration options using their do_add_parser() hooks.

```
bin_file: str | None
    Alias for field number 5
board_dir: str
    Alias for field number 1
build_dir: str
    Alias for field number 0
elf_file: str | None
    Alias for field number 2
exe_file: str | None
    Alias for field number 3
file: str | None
    Alias for field number 7
file_type: FileType | None
    Alias for field number 8
gdb: str | None
    Alias for field number 9
hex_file: str | None
    Alias for field number 4
openocd: str | None
    Alias for field number 10
openocd_search: List[str]
    Alias for field number 11
uf2_file: str | None
    Alias for field number 6
```

class runners.core.ZephyrBinaryRunner(cfg: RunnerConfig)
Abstract superclass for binary runners (flashers, debuggers).

**Note:** this class's API has changed relatively rarely since it was added, but it is not considered a stable Zephyr API, and may change without notice.

With some exceptions, boards supported by Zephyr must provide generic means to be flashed (have a Zephyr firmware binary permanently installed on the device for running) and debugged (have a breakpoint debugger and program loader on a host workstation attached to a running target).

This is supported by four top-level commands managed by the Zephyr build system:

- ‘flash’: flash a previously configured binary to the board, start execution on the target, then return.
- ‘debug’: connect to the board via a debugging protocol, program the flash, then drop the user into a debugger interface with symbol tables loaded from the current binary, and block until it exits.
- ‘debugserver’: connect via a board-specific debugging protocol, then reset and halt the target. Ensure the user is now able to connect to a debug server with symbol tables loaded from the binary.
- ‘attach’: connect to the board via a debugging protocol, then drop the user into a debugger interface with symbol tables loaded from the current binary, and block until it exits. Unlike ‘debug’, this command does not program the flash.
This class provides an API for these commands. Every subclass is called a ‘runner’ for short. Each runner has a name (like ‘pyocd’), and declares commands it can handle (like ‘flash’). Boards (like ‘nrf52dk_nrf52832’) declare which runner(s) are compatible with them to the Zephyr build system, along with information on how to configure the runner to work with the board.

The build system will then place enough information in the build directory to create and use runners with this class’s create() method, which provides a command line argument parsing API. You can also create runners by instantiating subclasses directly.

In order to define your own runner, you need to:

1. Define a ZephyrBinaryRunner subclass, and implement its abstract methods. You may need to override capabilities().
2. Make sure the Python module defining your runner class is imported, e.g. by editing this package’s __init__.py (otherwise, get_runners() won’t work).
3. Give your runner's name to the Zephyr build system in your board’s board.cmake.

Additional advice:

- If you need to import any non-standard-library modules, make sure to catch ImportError and defer complaints about it to a RuntimeError if one is missing. This avoids affecting users that don’t require your runner, while still making it clear what went wrong to users that do require it that don’t have the necessary modules installed.
- If you need to ask the user something (e.g. using input()), do it in your create() class-method, not do_run(). That ensures your __init__() really has everything it needs to call do_run(), and also avoids calling input() when not instantiating within a command line application.
- Use self.logger to log messages using the standard library's logging API; your logger is named “runner.<your-runner-name()>

For command-line invocation from the Zephyr build system, runners define their own argparser-based interface through the common add_parser() (and runner-specific do_add_parser() it delegates to), and provide a way to create instances of themselves from a RunnerConfig and parsed runner-specific arguments via create().

Runners use a variety of host tools and configuration values, the user interface to which is abstracted by this class. Each runner subclass should take any values it needs to execute one of these commands in its constructor. The actual command execution is handled in the run() method.

```python
classmethod add_parser(parser)
    Adds a sub-command parser for this runner.
    The given object, parser, is a sub-command parser from the argparse module. For more
details, refer to the documentation for argparse.ArgumentParser.add_subparsers().

    The lone common optional argument is:
    • –dt-flash (if the runner capabilities includes flash_addr)
    Runner-specific options are added through the do_add_parser() hook.

@property build_conf: BuildConfiguration
    Get a BuildConfiguration for the build directory.

call(cmd: List[str], **kwargs) → int
    Subclass subprocess.call() wrapper.
    Subclasses should use this method to run command in a subprocess and get its return
code, rather than using subprocess directly, to keep accurate debug logs.
```
classmethod capabilities() → RunnerCaps
   Returns a RunnerCaps representing this runner's capabilities.
   This implementation returns the default capabilities.
   Subclasses should override appropriately if needed.

cfg
   RunnerConfig for this instance.

check_call(cmd: List[str], **kwargs)
   Subclass subprocess.check_call() wrapper.
   Subclasses should use this method to run command in a subprocess and check that it
   executed correctly, rather than using subprocess directly, to keep accurate debug logs.

check_output(cmd: List[str], **kwargs) → bytes
   Subclass subprocess.check_output() wrapper.
   Subclasses should use this method to run command in a subprocess and check that it
   executed correctly, rather than using subprocess directly, to keep accurate debug logs.

classmethod create(cfg: RunnerConfig, args: Namespace) → ZephyrBinaryRunner
   Create an instance from command-line arguments.
   • cfg: runner configuration (pass to superclass __init__)
   • args: arguments parsed from execution environment, as specified by add_parser().

classmethod dev_id_help() → str
   Get the ArgParse help text for the –dev-id option.

abstract classmethod do_add_parser(parser)
   Hook for adding runner-specific options.

abstract classmethod do_create(cfg: RunnerConfig, args: Namespace) → ZephyrBinaryRunner
   Hook for instance creation from command line arguments.

abstract do_run(command: str, **kwargs)
   Concrete runner; run() delegates to this. Implement in subclasses.
   In case of an unsupported command, raise a ValueError.

ensure_output(output_type: str) → None
   Ensure self.cfg has a particular output artifact.
   For example, ensure_output('bin') ensures that self.cfg.bin_file refers to an existing file.
   Errors out if it's missing or undefined.

   Parameters
   output_type – string naming the output type

static flash_address_from_build_conf(build_conf: BuildConfiguration)
   If CONFIG_HAS_FLASH_LOAD_OFFSET is not in build_conf, return
   the CONFIG_FLASH_BASE_ADDRESS value. Otherwise, return CONFIG_FLASH_BASE_ADDRESS + CONFIG_FLASH_LOAD_OFFSET.

static get_flash_address(args: Namespace, build_conf: BuildConfiguration, default: int = 0) → int
   Helper method for extracting a flash address.
   If args.dt_flash is true, returns the address obtained from ZephyrBinaryRunner.flash_address_from_build_conf(build_conf).
   Otherwise (when args.dt_flash is False), the default value is returned.
static get_runners() → List[Type[ZephyrBinaryRunner]]
Get a list of all currently defined runner classes.

logger
logging.Logger for this instance.

abstract classmethod name() → str
Return this runner's user-visible name.
When choosing a name, pick something short and lowercase, based on the name of the tool (like openocd, jlink, etc.) or the target architecture/board (like xtensa etc.).
popen_ignore_int(cmd: List[str], **kwargs) → Popen
Spawn a child command, ensuring it ignores SIGINT.
The returned subprocess.Popen object must be manually terminated.
static require(program: str, path: str | None = None) → str
Require that a program is installed before proceeding.
Parameters
• program – name of the program that is required, or path to a program binary.
• path – PATH where to search for the program binary. By default check on the system PATH.
If program is an absolute path to an existing program binary, this call succeeds. Otherwise, try to find the program by name on the system PATH or in the given PATH, if provided.
If the program can be found, its path is returned. Otherwise, raises MissingProgram.
run(command: str, **kwargs)
Runs command (`flash', `debug', `debugserver', `attach').
This is the main entry point to this runner.
run_client(client, **kwargs)
Run a client that handles SIGINT.
run_server_and_client(server, client, **kwargs)
Run a server that ignores SIGINT, and a client that handles it.
This routine portably:
• creates a Popen object for the server command which ignores SIGINT
• runs client in a subprocess while temporarily ignoring SIGINT
• cleans up the server after the client exits.
• the keyword arguments, if any, will be passed down to both server and client subprocess calls
It's useful to e.g. open a GDB server and client.

property thread_info_enabled: bool
Returns True if self.build_conf has CONFIG_DEBUG_THREAD_INFO enabled.

classmethod tool_opt_help() → str
Get the ArgParse help text for the –tool-opt option.
Doing it By Hand

If you prefer not to use West to flash or debug your board, simply inspect the build directory for the binaries output by the build system. These will be named something like `zephyr/zephyr.elf`, `zephyr/zephyr.hex`, etc., depending on your board’s build system integration. These binaries may be flashed to a board using alternative tools of your choice, or used for debugging as needed, e.g. as a source of symbol tables.

By default, these West commands rebuild binaries before flashing and debugging. This can of course also be accomplished using the usual targets provided by Zephyr’s build system (in fact, that's how these commands do it).

### 2.11.11 Signing Binaries

The `west sign` extension command can be used to sign a Zephyr application binary for consumption by a bootloader using an external tool. In some configurations, `west sign` is also used to invoke an external, post-processing tool that “stitches” the final components of the image together. Run `west sign -h` for command line help.

**MCUboot / imgtool**

The Zephyr build system has special support for signing binaries for use with the MCUboot bootloader using the `imgtool` program provided by its developers. You can both build and sign this type of application binary in one step by setting some Kconfig options. If you do, `west flash` will use the signed binaries.

If you use this feature, you don’t need to run `west sign` yourself; the build system will do it for you.

Here is an example workflow, which builds and flashes MCUboot, as well as the `hello_world` application for chain-loading by MCUboot. Run these commands from the `zephyrproject` workspace you created in the Getting Started Guide.

```bash
west build -b YOUR_BOARD bootloader/mcuboot/boot/zephyr -d build-mcuboot
west build -b YOUR_BOARD zephyr/samples/hello_world -d build-hello-signed -- 
   -DCONFIG_BOOTLOADER_MCUBOOT=y 
   -DCONFIG_MCUBOOT_SIGNATURE_KEY_FILE="bootloader/mcuboot/root-rsa-2048.pem"
west flash -d build-mcuboot
west flash -d build-hello-signed
```

Notes on the above commands:

- `YOUR_BOARD` should be changed to match your board
- The `CONFIG_MCUBOOT_SIGNATURE_KEY_FILE` value is the insecure default provided and used by MCUboot for development and testing
- You can change the `hello_world` application directory to any other application that can be loaded by MCUboot, such as the `smp-svr` sample.

For more information on these and other related configuration options, see:

- `CONFIG_BOOTLOADER_MCUBOOT`: build the application for loading by MCUboot
- `CONFIG_MCUBOOT_SIGNATURE_KEY_FILE`: the key file to use with `west sign`. If you have your own key, change this appropriately
- `CONFIG_MCUBOOT_EXTRA_IMGTOOL_ARGS`: optional additional command line arguments for `imgtool`
• **CONFIG_MCUBOOT_GENERATE_CONFIRMED_IMAGE**: also generate a confirmed image, which may be more useful for flashing in production environments than the OTA-able default image

• On Windows, if you get “Access denied” issues, the recommended fix is to run `pip3 install imgtool`, then retry with a pristine build directory.

If your `west flash runner` uses an image format supported by imgtool, you should see something like this on your device’s serial console when you run `west flash -d build-mcuboot`:

```plaintext
*** Booting Zephyr OS build zephyr-v2.3.0-2310-gcebac69c8ae1 ***
[00:00:00.004,669] <inf> mcuboot: Starting bootloader
[00:00:00.011,169] <inf> mcuboot: Primary image: magic=unset, swap_type=0x1, copy_done=0x3,
   → image_ok=0x3
[00:00:00.021,636] <inf> mcuboot: Boot source: none
[00:00:00.027,313] <wrn> mcuboot: Failed reading image headers; Image=0
[00:00:00.035,064] <err> mcuboot: Unable to find bootable image
```

Then, you should see something like this when you run `west flash -d build-hello-signed`:

```plaintext
*** Booting Zephyr OS build zephyr-v2.3.0-2310-gcebac69c8ae1 ***
[00:00:00.004,669] <inf> mcuboot: Starting bootloader
[00:00:00.011,169] <inf> mcuboot: Primary image: magic=unset, swap_type=0x1, copy_done=0x3,
   → image_ok=0x3
[00:00:00.021,636] <inf> mcuboot: Boot source: none
[00:00:00.027,374] <inf> mcuboot: Swap type: none
[00:00:00.115,142] <inf> mcuboot: Bootloader chainload address offset: 0xc000
[00:00:00.123,168] <inf> mcuboot: Jumping to the first image slot
*** Booting Zephyr OS build zephyr-v2.3.0-2310-gcebac69c8ae1 ***
Hello World! nrf52840dk_nrf52840
```

Whether `west flash` supports this feature depends on your runner. The `nrfjprog` and `pyocd` runners work with the above flow. If your runner does not support this flow and you would like to, please send a patch or file an issue for adding support.

### Extending signing externally

The signing script used when running `west flash` can be extended or replaced to change features or introduce different signing mechanisms. By default with MCUboot enabled, signing is setup by the `cmake/mcuboot.cmake` file in Zephyr which adds extra post build commands for generating the signed images. The file used for signing can be replaced from a sysbuild scope (if being used) or from a zephyr/zephyr module scope, the priority of which is:

- Sysbuild
- Zephyr property
- Default MCUboot script (if enabled)

From sysbuild, `-D<target>_SIGNING_SCRIPT` can be used to set a signing script for a specific image or `-DSIGNING_SCRIPT` can be used to set a signing script for all images, for example:

```
west build -b <board> <application> -DSIGNING_SCRIPT=<file>
```

The zephyr property method is achieved by adjusting the `SIGNING_SCRIPT` property on the `zephyr_property_target`, ideally from a module by using:

```cmake
if(CONFIG_BOOTLOADER_MCUBOOT)
    set_target_properties(zephyr_property_target PROPERTIES SIGNING_SCRIPT ${CMAKE_CURRENT_LIST_DIR}/custom_signing.cmake)
endif()
```

---

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This will include the custom signing CMake file instead of the default Zephyr one when projects are built with MCUboot signing support enabled. The base Zephyr MCUboot signing file can be used as a reference for creating a new signing system or extending the default behaviour.

**rimage**

rimage configuration uses a different approach that does not rely on Kconfig or CMake but on `west config` instead, similar to Permanent CMake Arguments.

Signing involves a number of “wrapper” scripts stacked on top of each other: `west flash` invokes `west build` which invokes `cmake` and `ninja` which invokes `west sign` which invokes `imgtool` or `rimage`. As long as the signing parameters desired are the default ones and fairly static, these indirections are not a problem. On the other hand, passing `imgtool` or `rimage` options through all these layers can causes issues typical when the layers don't abstract anything. First, this usually requires boilerplate code in each layer. Quoting whitespace or other special characters through all the wrappers can be difficult. Reproducing a lower `west sign` command to debug some build-time issue can be very time-consuming: it requires at least enabling and searching verbose build logs to find which exact options were used. Copying these options from the build logs can be unreliable: it may produce different results because of subtle environment differences. Last and worst: new signing feature and options are impossible to use until more boilerplate code has been added in each layer.

To avoid these issues, `rimage` parameters can bet set in `west config` instead. Here's a workspace/`.west/config` example:

```
[sign]
# Not needed when invoked from CMake
tool = rimage

[rimage]
# Quoting is optional and works like in Unix shells
# Not needed when rimage can be found in the default PATH
path = "~/home/me/zworkspace/build-rimage/rimage"

# Not needed when using the default development key
extra-args = "-i 4 -k 'keys/key argument with space.pem'"
```

In order to support quoting, values are parsed by Python's `shlex.split()` like in One-Time CMake Arguments.

The `extra-args` are passed directly to the `rimage` command. The example above has the same effect as appending them on command line after `--` like this: `west sign --tool rimage -- -i 4 -k 'keys/key argument with space.pem'`. In case both are used, the command-line arguments go last.

### 2.11.12 Additional Zephyr extension commands

This page documents miscellaneous Zephyr Extensions.

**Listing boards: `west boards`**

The boards command can be used to list the boards that are supported by Zephyr without having to resort to additional sources of information.

It can be run by typing:

```
wester boards
```
This command lists all supported boards in a default format. If you prefer to specify the display format yourself you can use the `--format` (or `-f`) flag:

```
w west boards -f "{arch}:{name}"```

Additional help about the formatting options can be found by running:

```
w west boards -h```

**Shell completion scripts: west completion**

The completion extension command outputs shell completion scripts that can then be used directly to enable shell completion for the supported shells.

It currently supports the following shells:

- bash
- zsh

Additional instructions are available in the command's help:

```
w west help completion```

**Installing CMake packages: west zephyr-export**

This command registers the current Zephyr installation as a CMake config package in the CMake user package registry.

In Windows, the CMake user package registry is found in `HKEY_CURRENT_USER\Software\Kitware\CMake\Packages`.

In Linux and MacOS, the CMake user package registry is found in `~/.cmake/packages`.

You may run this command when setting up a Zephyr workspace. If you do, application CMakeLists.txt files that are outside of your workspace will be able to find the Zephyr repository with the following:

```
find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})```

See `share/zephyr-package/cmake` for details.

**Software bill of materials: west spdx**

This command generates SPDX 2.2 tag-value documents, creating relationships from source files to the corresponding generated build files. SPDX-License-Identifier comments in source files are scanned and filled into the SPDX documents.

To use this command:

1. Pre-populate a build directory `BUILD_DIR` like this:
   ```
w west spdx --init -d BUILD_DIR```

   This step ensures the build directory contains CMake metadata required for SPDX document generation.

2. Enable `CONFIG_BUILD_OUTPUT_META` in your project.

3. Build your application using this pre-created build directory, like so:
west build -d BUILD_DIR [...]

4. Generate SPDX documents using this build directory:

west spdx -d BUILD_DIR

This generates the following SPDX bill-of-materials (BOM) documents in BUILD_DIR/spdx/:

- **app.spdx**: BOM for the application source files used for the build
- **zephyr.spdx**: BOM for the specific Zephyr source code files used for the build
- **build.spdx**: BOM for the built output files

Each file in the bill-of-materials is scanned, so that its hashes (SHA256 and SHA1) can be recorded, along with any detected licenses if an `SPDX-License-Identifier` comment appears in the file.

SPDX Relationships are created to indicate dependencies between CMake build targets, build targets that are linked together, and source files that are compiled to generate the built library files.

`west spdx` accepts these additional options:

- **-n PREFIX**: a prefix for the Document Namespaces that will be included in the generated SPDX documents. See SPDX specification clause 6 for details. If `-n` is omitted, a default namespace will be generated according to the default format described in section 2.5 using a random UUID.
- **-s SPDX_DIR**: specifies an alternate directory where the SPDX documents should be written instead of BUILD_DIR/spdx/.
- **--analyze-includes**: in addition to recording the compiled source code files (e.g. .c, .S) in the bills-of-materials, also attempt to determine the specific header files that are included for each .c file.
  
  This takes longer, as it performs a dry run using the C compiler for each .c file using the same arguments that were passed to it for the actual build.
- **--include-sdk**: with --analyze-includes, also create a fourth SPDX document, sdk.spdx, which lists header files included from the SDK.

**Working with binary blobs**: `west blobs`

The `blobs` command allows users to interact with `binary blobs` declared in one or more `modules` via their `module.yml` file.

The `blobs` command has three sub-commands, used to list, fetch or clean (i.e. delete) the binary blobs themselves.

You can list binary blobs while specifying the format of the output:

```
west blobs list -f '{module}: {type} {path}'
```

For the full set of variables available in `-f/--format` run `west blobs -h`.

Fetching blobs works in a similar manner:

```
west blobs fetch
```

Note that, as described in the modules section, fetched blobs are stored in a zephyr/blobs/ folder relative to the root of the corresponding module repository.

As does deleting them:
Additionally the tool allows you to specify the modules you want to list, fetch or clean blobs for by typing the module names as a command-line parameter.

**Twister wrapper:** `west twister`

This command is a wrapper for `twister`. Twister can then be invoked via west as follows:

```bash
west twister -help
west twister -T tests/ztest/base
```

**Working with binary descriptors:** `west bindesc`

The `bindesc` command allows users to read binary descriptors of executable files. It currently supports `.bin`, `.hex`, `.elf` and `.uf2` files as input.

You can search for a specific descriptor in an image, for example:

```bash
west bindesc search KERNEL_VERSION_STRING build/zephyr/zephyr.bin
```

You can search for a custom descriptor by type and ID, for example:

```bash
west bindesc custom_search STR 0x200 build/zephyr/zephyr.bin
```

You can dump all of the descriptors in an image using:

```bash
west bindesc dump build/zephyr/zephyr.bin
```

You can list all known standard descriptor names using:

```bash
west bindesc list
```

### 2.11.13 History and Motivation

West was added to the Zephyr project to fulfill two fundamental requirements:

- The ability to work with multiple Git repositories
- The ability to provide an extensible and user-friendly command-line interface for basic Zephyr workflows

During the development of west, a set of Design Constraints were identified to avoid the common pitfalls of tools of this kind.

**Requirements**

Although the motivation behind splitting the Zephyr codebase into multiple repositories is outside of the scope of this page, the fundamental requirements, along with a clear justification of the choice not to use existing tools and instead develop a new one, do belong here.

The basic requirements are:

- **R1**: Keep externally maintained code in separately maintained repositories outside of the main zephyr repository, without requiring users to manually clone each of the external repositories
• **R2**: Provide a tool that both Zephyr users and distributors can make use of to benefit from and extend

• **R3**: Allow users and downstream distributions to override or remove repositories without having to make changes to the zephyr repository

• **R4**: Support both continuous tracking and commit-based (bisectable) project updating

### Rationale for a custom tool

Some of west’s features are similar to those provided by Git Submodules and Google’s repo.

Existing tools were considered during west’s initial design and development. None were found suitable for Zephyr’s requirements. In particular, these were examined in detail:

• Google repo
  – Does not cleanly support using zephyr as the manifest repository (**R4**)
  – Python 2 only
  – Does not play well with Windows
  – Assumes Gerrit is used for code review

• Git submodules
  – Does not fully support **R1**, since the externally maintained repositories would still need to be inside the main zephyr Git tree
  – Does not support **R3**, since downstream copies would need to either delete or replace submodule definitions
  – Does not support continuous tracking of the latest HEAD in external repositories (**R4**)
  – Requires hardcoding of the paths/locations of the external repositories

### Multiple Git Repositories

Zephyr intends to provide all required building blocks needed to deploy complex IoT applications. This in turn means that the Zephyr project is much more than an RTOS kernel, and is instead a collection of components that work together. In this context, there are a few reasons to work with multiple Git repositories in a standardized manner within the project:

• Clean separation of Zephyr original code and imported projects and libraries

• Avoidance of license incompatibilities between original and imported code

• Reduction in size and scope of the core Zephyr codebase, with additional repositories containing optional components instead of being imported directly into the tree

• Safety and security certifications

• Enforcement of modularization of the components

• Out-of-tree development based on subsets of the supported boards and SoCs

See **Basics** for information on how west workspaces manage multiple git repositories.

### Design Constraints

West is:
• **Optional**: it is always possible to drop back to “raw” command-line tools, i.e. use Zephyr without using west (although west itself might need to be installed and accessible to the build system). It may not always be convenient to do so, however. (If all of west’s features were already available, there would be no reason to develop it.)

• **Compatible with CMake**: building, flashing and debugging, and emulator support will always remain compatible with direct use of CMake.

• **Cross-platform**: West is written in Python 3, and works on all platforms supported by Zephyr.

• **Usable as a Library**: whenever possible, west features are implemented as libraries that can be used standalone in other programs, along with separate command line interfaces that wrap them. West itself is a Python package named west; its libraries are implemented as subpackages.

• **Conservative about features**: no features will be accepted without strong and compelling motivation.

• **Clearly specified**: West’s behavior in cases where it wraps other commands is clearly specified and documented. This enables interoperability with third party tools, and means Zephyr developers can always find out what is happening “under the hood” when using west.

See Zephyr issue #6205 and for more details and discussion.

### 2.11.14 Moving to West

To convert a “pre-west” Zephyr setup on your computer to west, follow these steps. If you are starting from scratch, use the *Getting Started Guide* instead. See *Troubleshooting West* for advice on common issues.

1. Install west.
   
   On Linux:
   
   ```bash
   pip3 install --user -U west
   ```

   On Windows and macOS:
   
   ```bash
   pip3 install -U west
   ```

   For details, see *Installing west*.

2. Move your zephyr repository to a new zephyrproject parent directory, and change directory there.

   On Linux and macOS:
   
   ```bash
   mkdir zephyrproject
   mv zephyr zephyrproject
   cd zephyrproject
   ```

   On Windows cmd.exe:
   
   ```bash
   mkdir zephyrproject
   move zephyr zephyrproject
   chdir zephyrproject
   ```

   The name zephyrproject is recommended, but you can choose any name with no spaces anywhere in the path.

3. Create a *west workspace* using the zephyr repository as a local manifest repository:
west init -l zephyr

This creates zephyrproject/.west, marking the root of your workspace, and does some other setup. It will not change the contents of the zephyr repository in any way.

4. Clone the rest of the repositories used by zephyr:

west update

Make sure to run this command whenever you pull zephyr. Otherwise, your local repositories will get out of sync. (Run west list for current information on these repositories.)

You are done: zephyrproject is now set up to use west.

2.11.15 Using Zephyr without west

This page provides information on using Zephyr without west. This is not recommended for beginners due to the extra effort involved. In particular, you will have to do work “by hand” to replace these features:

• cloning the additional source code repositories used by Zephyr in addition to the main zephyr repository, and keeping them up to date
• specifying the locations of these repositories to the Zephyr build system
• flashing and debugging without understanding detailed usage of the relevant host tools

Note: If you have previously installed west and want to stop using it, uninstall it first:

pip3 uninstall west

Otherwise, Zephyr's build system will find it and may try to use it.

Getting the Source

In addition to downloading the zephyr source code repository itself, you will need to manually clone the additional projects listed in the west manifest file inside that repository.

mkdir zephyrproject
cd zephyrproject
git clone https://github.com/zephyrproject-rtos/zephyr
# clone additional repositories listed in zephyr/west.yml,
# and check out the specified revisions as well.

As you pull changes in the zephyr repository, you will also need to maintain those additional repositories, adding new ones as necessary and keeping existing ones up to date at the latest revisions.

Building applications

You can build a Zephyr application using CMake and Ninja (or make) directly without west installed if you specify any modules manually.

cmake -Bbuild -GNinja -DZEPHYR_MODULES=module1;module2;... samples/hello_world
ninja -Cbuild
When building with west installed, the Zephyr build system will use it to set `ZEPHYR_MODULES`.

If you don't have west installed and your application does not need any of these repositories, the build will still work. If you don't have west installed and your application does need one of these repositories, you must set `ZEPHYR_MODULES` yourself as shown above.

See [Modules (External projects)] for more details.

Similarly, if your application requires binary blobs and you are not using west, you will need to download and place those blobs in the right places instead of using west blobs. See [Binary Blobs] for more details.

### Flashing and Debugging

Running build system targets like `ninja flash`, `ninja debug`, etc. is just a call to the corresponding `west command`. For example, `ninja flash` calls `west flash`¹. If you don't have west installed on your system, running those targets will fail. You can of course still flash and debug using any [Flash & Debug Host Tools] which work for your board (and which those west commands wrap).

If you want to use these build system targets but do not want to install west on your system using `pip`, it is possible to do so by manually creating a `west workspace`:

```
# cd into zephyrproject if not already there
git clone https://github.com/zephyrproject-rtos/west.git .west/west
```

Then create a file `.west/config` with the following contents:

```ini
[manifest]
path = zephyr

[zephyr]
base = zephyr
```

After that, and in order for `ninja` to be able to invoke `west` to flash and debug, you must specify the west directory. This can be done by setting the environment variable `WEST_DIR` to point to `zephyrproject/.west/west` before running CMake to set up a build directory.

For details on west's Python APIs, see west-apis.

### 2.12 Testing

#### 2.12.1 Test Framework

The Zephyr Test Framework (Ztest) provides a simple testing framework intended to be used during development. It provides basic assertion macros and a generic test structure.

The framework can be used in two ways, either as a generic framework for integration testing, or for unit testing specific modules.

---

¹ Note that `west build` invokes `ninja` among other tools. There's no recursive invocation of either `west` or `ninja` involved by default, however, as `west build` does not invoke `ninja flash`, `debug`, etc. The one exception is if you specifically run one of these build system targets with a command line like `west build -t flash`. In that case, `west` is run twice: once for `west build`, and in a subprocess, again for `west flash`. Even in this case, `ninja` is only run once, as `ninja flash`. This is because these build system targets depend on an up to date build of the Zephyr application, so it's compiled before `west flash` is run.
Creating a test suite

Using Ztest to create a test suite is as easy as calling the ZTEST_SUITE. The macro accepts the following arguments:

- **suite_name** - The name of the suite. This name must be unique within a single binary.
- **ztest_suite_predicate_t** - An optional predicate function to allow choosing when the test will run. The predicate will get a pointer to the global state passed in through ztest_run_all() and should return a boolean to decide if the suite should run.
- **ztest_suite_setup_t** - An optional setup function which returns a test fixture. This will be called and run once per test suite run.
- **ztest_suite_before_t** - An optional before function which will run before every single test in this suite.
- **ztest_suite_after_t** - An optional after function which will run after every single test in this suite.
- **ztest_suite_teardown_t** - An optional teardown function which will run at the end of all the tests in the suite.

Below is an example of a test suite using a predicate:

```c
#include <zephyr/ztest.h>
#include "test_state.h"

static bool predicate(const void *global_state) {
    return ((const struct test_state*)global_state)->x == 5;
}

ZTEST_SUITE(alternating_suite, predicate, NULL, NULL, NULL, NULL);
```

Adding tests to a suite

There are 4 macros used to add a test to a suite, they are:

- **ZTEST** (suite_name, test_name) - Which can be used to add a test by test_name to a given suite by suite_name.
- **ZTEST_USER** (suite_name, test_name) - Which behaves the same as ZTEST, only that when CONFIG_USERSPACE is enabled, then the test will be run in a userspace thread.
- **ZTEST_F** (suite_name, test_name) - Which behaves the same as ZTEST, only that the test function will already include a variable named fixture with the type <suite_name>_fixture.
- **ZTEST_USER_F** (suite_name, test_name) - Which combines the fixture feature of ZTEST_F with the userspace threading for the test.

Test fixtures  Test fixtures can be used to help simplify repeated test setup operations. In many cases, tests in the same suite will require some initial setup followed by some form of reset between each test. This is achieved via fixtures in the following way:

```c
#include <zephyr/ztest.h>

struct my_suite_fixture {
    size_t max_size;
    size_t size;
    uint8_t buff[1];
}
```

(continues on next page)
static void *my_suite_setup(void)
{
    /* Allocate the fixture with 256 byte buffer */
    struct my_suite_fixture *fixture = malloc(sizeof(struct my_suite_fixture) + 255);
    zassume_not_null(fixture, NULL);
    fixture->max_size = 256;
    return fixture;
}

static void my_suite_before(void *f)
{
    struct my_suite_fixture *fixture = (struct my_suite_fixture *)f;
    memset(fixture->buff, 0, fixture->max_size);
    fixture->size = 0;
}

static void my_suite_teardown(void *f)
{
    free(f);
}

ZTEST_SUITE(my_suite, NULL, my_suite_setup, my_suite_before, NULL, my_suite_teardown);

ZTEST_F(my_suite, test_feature_x)
{
    zassert_equal(0, fixture->size);
    zassert_equal(256, fixture->max_size);
}

Using memory allocated by a test fixture in a userspace thread, such as during execution of 
ZTEST_USER or ZTEST_USER_F, requires that memory to be declared userspace accessible. This is 
because the fixture memory is owned and initialized by kernel space. The Ztest framework provides 
the ZTEST_DMEM and ZTEST_BMEM macros for use of such user/kernel space shared memory.

Advanced features

Test result expectations Some tests were made to be broken. In cases where the test is ex-
pected to fail or skip due to the nature of the code, it's possible to annotate the test as such. For 
example:

```
#include <zephyr/ztest.h>

ZTEST_SUITE(my_suite, NULL, NULL, NULL, NULL, NULL);

ZTEST_EXPECT_FAIL(my_suite, test_fail);
ZTEST(my_suite, test_fail)
{
    /** This will fail the test */
    zassert_true(false, NULL);
}

ZTEST_EXPECT_SKIP(my_suite, test_skip);
ZTEST(my_suite, test_skip)
{
    /** This will skip the test */
```

(continues on next page)
In this example, the above tests should be marked as failed and skipped respectively. Instead, Ztest will mark both as passed due to the expectation.

**Test rules**  Test rules are a way to run the same logic for every test and every suite. There are a lot of cases where you might want to reset some state for every test in the binary (regardless of which suite is currently running). As an example, this could be to reset mocks, reset emulators, flush the UART, etc.:

```c
#include <zephyr/fff.h>
#include <zephyr/ztest.h>
#include "test_mocks.h"

DEFINE_FFF_GLOBALS;
DEFINE_FAKE_VOID_FUN(my_weak_func);

static void fff_reset_rule_before(const struct ztest_unit_test *test, void *fixture)
{
    ARG_UNUSED(test);
    ARG_UNUSED(fixture);
    RESET_FAKE(my_weak_func);
}

ZTEST_RULE(fff_reset_rule, fff_reset_rule_before, NULL);
```

**A custom test_main**  While the Ztest framework provides a default test_main() function, it's possible that some applications will want to provide custom behavior. This is particularly true if there's some global state that the tests depend on and that state either cannot be replicated or is difficult to replicate without starting the process over. For example, one such state could be a power sequence. Assuming there's a board with several steps in the power-on sequence a test suite can be written using the predicate to control when it would run. In that case, the test_main() function can be written as follows:

```c
#include <zephyr/ztest.h>
#include "my_test.h"

void test_main(void)
{
    struct power_sequence_state state;

    /* Only suites that use a predicate checking for phase == PWR_PHASE_0 will run. */
    state.phase = PWR_PHASE_0;
    ztest_run_all(&state, false, 1, 1);

    /* Only suites that use a predicate checking for phase == PWR_PHASE_1 will run. */
    state.phase = PWR_PHASE_1;
    ztest_run_all(&state, false, 1, 1);

    /* Only suites that use a predicate checking for phase == PWR_PHASE_2 will run. */
    state.phase = PWR_PHASE_2;
    ztest_run_all(&state, false, 1, 1);
}
```
Quick start - Integration testing

A simple working base is located at `samples/subsys/testsuite/integration`. Just copy the files to `tests/` and edit them for your needs. The test will then be automatically built and run by the twister script. If you are testing the `bar` component of `foo`, you should copy the sample folder to `tests/foo/bar`. It can then be tested with:

```
./scripts/twister -s tests/foo/bar/test-identifier
```

In the example above `tests/foo/bar` signifies the path to the test and the `test-identifier` references a test defined in the `testcase.yaml` file.

To run all tests defined in a test project, run:

```
./scripts/twister -T tests/foo/bar/
```

The sample contains the following files:

CMakeLists.txt

```cmake
# SPDX-License-Identifier: Apache-2.0

cmake_minimum_required(VERSION 3.20.0)
find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})
project(integration)

FILE(GLOB app_sources src/*.c)
target_sources(app PRIVATE ${app_sources})
```

testcase.yaml

```yaml
tests:
  # section.subsection
  sample.testing.ztest:
    build_only: true
    platform_allow:
      - native_posix
      - native_sim
    integration_platforms:
      - native_sim
    tags: test_framework
```

prj.conf

```ini
CONFIG_ZTEST=y
```

src/main.c (see best practices)

```c
/*
 * Copyright (c) 2016 Intel Corporation
 *
 * SPDX-License-Identifier: Apache-2.0
 */

#include <zephyr/ztest.h>
```
A test case project may consist of multiple sub-tests or smaller tests that either can be testing functionality or APIs. Functions implementing a test should follow the guidelines below:

- Test cases function names should be prefix with `test_`
- Test cases should be documented using doxygen
- Test function names should be unique within the section or component being tested

For example:

```c
/**
 * @brief Test Asserts
 * This test verifies the zassert_true macro.
 */
ZTEST(my_suite, test_assert)
{
    zassert_true(1, "1 was false");
    zassert_false(0, "0 was true");
    zassert_is_null(NULL, "NULL was not NULL");
    zassert_not_null("foo", "\"foo\" was NULL");
    zassert_equal(1, 1, "1 was not equal to 1");
    zassert_equal_ptr(NULL, NULL, "NULL was not equal to NULL");
}
```

**Listing Tests**  Tests (test projects) in the Zephyr tree consist of many testcases that run as part of a project and test similar functionality, for example an API or a feature. The twister script can parse the testcases in all test projects or a subset of them, and can generate reports on a granular level, i.e. if cases have passed or failed or if they were blocked or skipped.

Twister parses the source files looking for test case names, so you can list all kernel test cases, for example, by running:

```bash
twister --list-tests -T tests/kernel
```

**Skipping Tests**  Special- or architecture-specific tests cannot run on all platforms and architectures, however we still want to count those and report them as being skipped. Because the test inventory and the list of tests is extracted from the code, adding conditionals inside the test suite...
is sub-optimal. Tests that need to be skipped for a certain platform or feature need to explicitly report a skip using `ztest_test_skip()` or `Z_TEST_SKIP_IFDEF`. If the test runs, it needs to report either a pass or fail. For example:

```c
#ifdef CONFIG_TEST1
ZTEST(common, test_test1)
{
    zassert_true(1, "true");
}
#else
ZTEST(common, test_test1)
{
    ztest_test_skip();
}
#endif
ZTEST(common, test_test2)
{
    Z_TEST_SKIP_IFDEF(CONFIG_BUGxxxxx);
    zassert_equal(1, 0, NULL);
}
ZTEST_SUITE(common, NULL, NULL, NULL, NULL, NULL);
```

**Quick start - Unit testing**

Ztest can be used for unit testing. This means that rather than including the entire Zephyr OS for testing a single function, you can focus the testing efforts into the specific module in question. This will speed up testing since only the module will have to be compiled in, and the tested functions will be called directly.

Since you won’t be including basic kernel data structures that most code depends on, you have to provide function stubs in the test. Ztest provides some helpers for mocking functions, as demonstrated below.

In a unit test, mock objects can simulate the behavior of complex real objects and are used to decide whether a test failed or passed by verifying whether an interaction with an object occurred, and if required, to assert the order of that interaction.

**Best practices for declaring the test suite**  
Twister and other validation tools need to obtain the list of subcases that a Zephyr ztest test image will expose.

**Rationale**

This all is for the purpose of traceability. It's not enough to have only a semaphore test project. We also need to show that we have testpoints for all APIs and functionality, and we trace back to documentation of the API, and functional requirements.

The idea is that test reports show results for every sub-testcase as passed, failed, blocked, or skipped. Reporting on only the high-level test project level, particularly when tests do too many things, is too vague.

Other questions:

- Why not pre-scan with CPP and then parse? or post scan the ELF file?
  - If C pre-processing or building fails because of any issue, then we won’t be able to tell the subcases.
• Why not declare them in the YAML testcase description?

A separate testcase description file would be harder to maintain than just keeping the information in the test source files themselves – only one file to update when changes are made eliminates duplication.

Stress test framework

Zephyr stress test framework (Ztress) provides an environment for executing user functions in multiple priority contexts. It can be used to validate that code is resilient to preemptions. The framework tracks the number of executions and preemptions for each context. Execution can have various completion conditions like timeout, number of executions or number of preemptions.

The framework is setting up the environment by creating the requested number of threads (each on different priority), optionally starting a timer. For each context, a user function (different for each context) is called and then the context sleeps for a randomized amount of system ticks. The framework is tracking CPU load and adjusts sleeping periods to achieve higher CPU load. In order to increase the probability of preemptions, the system clock frequency should be relatively high. The default 100 Hz on QEMU x86 is much too low and it is recommended to increase it to 100 kHz.

The stress test environment is setup and executed using \texttt{ZTRESS_EXECUTE} which accepts a variable number of arguments. Each argument is a context that is specified by \texttt{ZTRESS_TIMER} or \texttt{ZTRESS_THREAD} macros. Contexts are specified in priority descending order. Each context specifies completion conditions by providing the minimum number of executions and preemptions. When all conditions are met and the execution has completed, an execution report is printed and the macro returns. Note that while the test is executing, a progress report is periodically printed.

Execution can be prematurely completed by specifying a test timeout (\texttt{ztress_set_timeout()}) or an explicit abort (\texttt{ztress_abort()}).

User function parameters contains an execution counter and a flag indicating if it is the last execution.

The example below presents how to setup and run 3 contexts (one of which is k_timer interrupt handler context). Completion criteria is set to at least 10000 executions of each context and 1000 preemptions of the lowest priority context. Additionally, the timeout is configured to complete after 10 seconds if those conditions are not met. The last argument of each context is the initial sleep time which will be adjusted throughout the test to achieve the highest CPU load.

\begin{verbatim}
ztress_set_timeout(K_MSEC(10000));
ZTRESS_EXECUTE(ZTRESS_TIMER(foo_0, user_data_0, 10000, Z_TIMEOUT_TICKS(20)),
    ZTRESS_THREAD(foo_1, user_data_1, 10000, 0, Z_TIMEOUT_TICKS(20)),
    ZTRESS_THREAD(foo_2, user_data_2, 10000, 1000, Z_TIMEOUT_TICKS(20)));
\end{verbatim}

Configuration  Static configuration of Ztress contains:

• \texttt{ZTRESS_MAX_THREADS} - number of supported threads.
• \texttt{ZTRESS_STACK_SIZE} - Stack size of created threads.
• \texttt{ZTRESS_REPORT_PROGRESS_MS} - Test progress report interval.

API reference

Running tests
This module eases the testing process by providing helpful macros and other testing structures.

**Defines**

**ZTEST(suite, fn)**
Create and register a new unit test.

Calling this macro will create a new unit test and attach it to the declared `suite`. The suite does not need to be defined in the same compilation unit.

**Parameters**
- `suite` – The name of the test suite to attach this test
- `fn` – The test function to call.

**ZTEST_USER(suite, fn)**
Define a test function that should run as a user thread.

This macro behaves exactly the same as ZTEST, but calls the test function in user space if CONFIG_USERSPACE was enabled.

**Parameters**
- `suite` – The name of the test suite to attach this test
- `fn` – The test function to call.

**ZTEST_F(suite, fn)**
Define a test function.

This macro behaves exactly the same as ZTEST, but the function takes an argument for the fixture of type `struct suite##_fixture*` named this.

**Parameters**
- `suite` – The name of the test suite to attach this test
- `fn` – The test function to call.

**ZTEST_USER_F(suite, fn)**
Define a test function that should run as a user thread.

If CONFIG_USERSPACE is not enabled, this is functionally identical to ZTEST_F(). The test function takes a single fixture argument of type `struct suite##_fixture*` named this.

**Parameters**
- `suite` – The name of the test suite to attach this test
- `fn` – The test function to call.

**ZTEST_RULE(name, before_each_fn, after_each_fn)**
Define a test rule that will run before/after each unit test.

Functions defined here will run before/after each unit test for every test suite. Along with the callback, the test functions are provided a pointer to the test being run, and the data. This provides a mechanism for tests to perform custom operations depending on the specific test or the data (for example logging may use the test's name).

Ordering:
• Test rule's before function will run before the suite's before function. This is done to allow the test suite's customization to take precedence over the rule which is applied to all suites.

• Test rule's after function is not guaranteed to run in any particular order.

Parameters

- name – The name for the test rule (must be unique within the compilation unit)
- before_each_fn – The callback function (ztest_rule_cb) to call before each test (may be NULL)
- after_each_fn – The callback function (ztest_rule_cb) to call after each test (may be NULL)

ztest_run_test_suite(suite, shuffle, suite_iter, case_iter)
Run the specified test suite.

Parameters

- suite – Test suite to run.
- shuffle – Shuffle tests
- suite_iter – Test suite repetitions.
- case_iter – Test case repetitions.

Typedefs

typedef void (*ztest_rule_cb)(const struct ztest_unit_test *test, void *data)
Test rule callback function signature.
The function signature that can be used to register a test rule's before/after callback. This provides access to the test and the fixture data (if provided).

Param test
Pointer to the unit test in context

Param data
Pointer to the test's fixture data (may be NULL)

Functions

void ztest_test_fail(void)
Fail the currently running test.
This is the function called from failed assertions and the like. You probably don't need to call it yourself.

void ztest_test_pass(void)
Pass the currently running test.
Normally a test passes just by returning without an assertion failure. However, if the success case for your test involves a fatal fault, you can call this function from k_sys_fatal_error_handler to indicate that the test passed before aborting the thread.

void ztest_test_skip(void)
Skip the current test.
void ztest_skip_failed_assumption(void)

void ztest_simple_1cpu_before(void *data)
    A 'before' function to use in test suites that just need to start 1cpu.
    Ignores data, and calls z_test_1cpu_start()

    Parameters
    • data – The test suite’s data

void ztest_simple_1cpu_after(void *data)
    A ‘after’ function to use in test suites that just need to stop 1cpu.
    Ignores data, and calls z_test_1cpu_stop()

    Parameters
    • data – The test suite’s data

struct ztest_test_rule

struct ztest_arch_api
    #include <ztest_test.h> Structure for architecture specific APIs.

Assertions These macros will instantly fail the test if the related assertion fails. When an assertion fails, it will print the current file, line and function, alongside a reason for the failure and an optional message. If the config CONFIG_ZTEST_ASSERT_VERBOSE is 0, the assertions will only print the file and line numbers, reducing the binary size of the test.

Example output for a failed macro from zassert_equal(buf->ref, 2, "Invalid refcount"):

Assertion failed at main.c:62: test_get_single_buffer: Invalid refcount (buf->ref not equal → to 2)
Abort at unit test function

group ztest_assert
    This module provides assertions when using Ztest.

Defines

zassert(cond, default_msg, ...)
zassume(cond, default_msg, ...)
zexpect(cond, default_msg, ...)
zassert_unreachable(...)
    Assert that this function call won’t be reached.

    Parameters
    • ... – Optional message and variables to print if the assertion fails

zassert_true(cond, ...)
    Assert that cond is true.

    Parameters
    • cond – Condition to check
    • ... – Optional message and variables to print if the assertion fails
zassert_false(cond, ...)  
Assert that cond is false.

Parameters

• cond – Condition to check
• ... – Optional message and variables to print if the assertion fails

zassert_ok(cond, ...)  
Assert that cond is 0 (success)

Parameters

• cond – Condition to check
• ... – Optional message and variables to print if the assertion fails

zassert_not_ok(cond, ...)  
Assert that cond is not 0 (failure)

Parameters

• cond – Condition to check
• ... – Optional message and variables to print if the assertion fails

zassert_is_null(ptr, ...)  
Assert that ptr is NULL.

Parameters

• ptr – Pointer to compare
• ... – Optional message and variables to print if the assertion fails

zassert_not_null(ptr, ...)  
Assert that ptr is not NULL.

Parameters

• ptr – Pointer to compare
• ... – Optional message and variables to print if the assertion fails

zassert_equal(a, b, ...)  
Assert that a equals b.

a and b won’t be converted and will be compared directly.

Parameters

• a – Value to compare
• b – Value to compare
• ... – Optional message and variables to print if the assertion fails

zassert_not_equal(a, b, ...)  
Assert that a does not equal b.

a and b won’t be converted and will be compared directly.

Parameters

• a – Value to compare
• b – Value to compare
• ... – Optional message and variables to print if the assertion fails
zassert_equal_ptr(a, b, ...)
Assert that $a$ equals $b$.
$a$ and $b$ will be converted to void * before comparing.

Parameters
- $a$ – Value to compare
- $b$ – Value to compare
- ... – Optional message and variables to print if the assertion fails

zassert_within(a, b, d, ...)
Assert that $a$ is within $b$ with delta $d$.

Parameters
- $a$ – Value to compare
- $b$ – Value to compare
- $d$ – Delta
- ... – Optional message and variables to print if the assertion fails

zassert_between_inclusive(a, l, u, ...)
Assert that $a$ is greater than or equal to $l$ and less than or equal to $u$.

Parameters
- $a$ – Value to compare
- $l$ – Lower limit
- $u$ – Upper limit
- ... – Optional message and variables to print if the assertion fails

zassert_mem_equal(...)
Assert that 2 memory buffers have the same contents.
This macro calls the final memory comparison assertion macro. Using double expansion allows providing some arguments by macros that would expand to more than one values (ANSI-C99 defines that all the macro arguments have to be expanded before macro call).

Parameters
- ... – Arguments, see zassert_mem_equal__ for real arguments accepted.

zassert_mem_equal__ (buf, exp, size, ...)
Internal assert that 2 memory buffers have the same contents.

Note: This is internal macro, to be used as a second expansion. See zassert_mem_equal.
Expectations  These macros will continue test execution if the related expectation fails and subsequently fail the test at the end of its execution. When an expectation fails, it will print the current file, line, and function, alongside a reason for the failure and an optional message but continue executing the test. If the config CONFIG_ZTEST_ASSERT_VERBOSE is 0, the expectations will only print the file and line numbers, reducing the binary size of the test.

For example, if the following expectations fail:

```c
zexpect_equal(buf->ref, 2, "Invalid refcount");
zexpect_equal(buf->ref, 1337, "Invalid refcount");
```

The output will look something like:

```
START - test_get_single_buffer
   Expectation failed at main.c:62: test_get_single_buffer: Invalid refcount (buf->ref not equal to 2)
   Expectation failed at main.c:63: test_get_single_buffer: Invalid refcount (buf->ref not equal to 1337)
FAIL - test_get_single_buffer in 0.0 seconds
```

**group ztest_expect**

This module provides expectations when using Ztest.

**Defines**

**zexpect_true(cond, ...)**

Expect that `cond` is true, otherwise mark test as failed but continue its execution.

**Parameters**

- `cond` – Condition to check
- `...` – Optional message and variables to print if the expectation fails

**zexpect_false(cond, ...)**

Expect that `cond` is false, otherwise mark test as failed but continue its execution.

**Parameters**

- `cond` – Condition to check
- `...` – Optional message and variables to print if the expectation fails

**zexpect_ok(cond, ...)**

Expect that `cond` is 0 (success), otherwise mark test as failed but continue its execution.

**Parameters**

- `cond` – Condition to check
- `...` – Optional message and variables to print if the expectation fails

**zexpect_not_ok(cond, ...)**

Expect that `cond` is not 0 (failure), otherwise mark test as failed but continue its execution.

**Parameters**

- `cond` – Condition to check
- `...` – Optional message and variables to print if the expectation fails
**zexpect_is_null(ptr, ...)**  
Expect that `ptr` is NULL, otherwise mark test as failed but continue its execution.

**Parameters**  
- `ptr` – Pointer to compare  
- `...` – Optional message and variables to print if the expectation fails

**zexpect_not_null(ptr, ...)**  
Expect that `ptr` is not NULL, otherwise mark test as failed but continue its execution.

**Parameters**  
- `ptr` – Pointer to compare  
- `...` – Optional message and variables to print if the expectation fails

**zexpect_equal(a, b, ...)**  
Expect that `a` equals `b`, otherwise mark test as failed but continue its execution.  
If the expectation fails, the test will be marked as “skipped”.

**Parameters**  
- `a` – Value to compare  
- `b` – Value to compare  
- `...` – Optional message and variables to print if the expectation fails

**zexpect_not_equal(a, b, ...)**  
Expect that `a` does not equal `b`, otherwise mark test as failed but continue its execution.  
`a` and `b` won’t be converted and will be compared directly.

**Parameters**  
- `a` – Value to compare  
- `b` – Value to compare  
- `...` – Optional message and variables to print if the expectation fails

**zexpect_equal_ptr(a, b, ...)**  
Expect that `a` equals `b`, otherwise mark test as failed but continue its execution.  
`a` and `b` will be converted to `void *` before comparing.

**Parameters**  
- `a` – Value to compare  
- `b` – Value to compare  
- `...` – Optional message and variables to print if the expectation fails

**zexpect_within(a, b, delta, ...)**  
Expect that `a` is within `b` with delta `d`, otherwise mark test as failed but continue its execution.

**Parameters**  
- `a` – Value to compare  
- `b` – Value to compare  
- `delta` – Difference between `a` and `b`  
- `...` – Optional message and variables to print if the expectation fails
**zexpect_between_inclusive** \((a, \text{lower}, \text{upper}, \ldots)\)

Expect that \(a\) is greater than or equal to \(l\) and less than or equal to \(u\), otherwise mark test as failed but continue its execution.

**Parameters**

- \(a\) – Value to compare
- \(\text{lower}\) – Lower limit
- \(\text{upper}\) – Upper limit
- \(\ldots\) – Optional message and variables to print if the expectation fails

**zexpect_mem_equal** \((\text{buf}, \text{exp}, \text{size}, \ldots)\)

Expect that 2 memory buffers have the same contents, otherwise mark test as failed but continue its execution.

**Parameters**

- \(\text{buf}\) – Buffer to compare
- \(\text{exp}\) – Buffer with expected contents
- \(\text{size}\) – Size of buffers
- \(\ldots\) – Optional message and variables to print if the expectation fails

**Assumptions**

These macros will instantly skip the test or suite if the related assumption fails. When an assumption fails, it will print the current file, line, and function, alongside a reason for the failure and an optional message. If the config `CONFIG_ZTEST_ASSERT_VERBOSE` is 0, the assumptions will only print the file and line numbers, reducing the binary size of the test.

Example output for a failed macro from `zassume_equal(buf->ref, 2, "Invalid refcount")`:

```
group ztest_assume

This module provides assumptions when using Ztest.
```

**Defines**

**zassume_true** \((\text{cond}, \ldots)\)

Assume that \(\text{cond}\) is true.

If the assumption fails, the test will be marked as “skipped”.

**Parameters**

- \(\text{cond}\) – Condition to check
- \(\ldots\) – Optional message and variables to print if the assumption fails

**zassume_false** \((\text{cond}, \ldots)\)

Assume that \(\text{cond}\) is false.

If the assumption fails, the test will be marked as “skipped”.

**Parameters**

- \(\text{cond}\) – Condition to check
- \(\ldots\) – Optional message and variables to print if the assumption fails
zassume_ok(cond, ...)  
Assume that cond is 0 (success)  
If the assumption fails, the test will be marked as “skipped”.  

Parameters  
• cond – Condition to check  
• ... – Optional message and variables to print if the assumption fails

zassume_not_ok(cond, ...)  
Assume that cond is not 0 (failure)  
If the assumption fails, the test will be marked as “skipped”.  

Parameters  
• cond – Condition to check  
• ... – Optional message and variables to print if the assumption fails

zassume_is_null(ptr, ...)  
Assume that ptr is NULL.  
If the assumption fails, the test will be marked as “skipped”.  

Parameters  
• ptr – Pointer to compare  
• ... – Optional message and variables to print if the assumption fails

zassume_not_null(ptr, ...)  
Assume that ptr is not NULL.  
If the assumption fails, the test will be marked as “skipped”.  

Parameters  
• ptr – Pointer to compare  
• ... – Optional message and variables to print if the assumption fails

zassume_equal(a, b, ...)  
Assume that a equals b.  
a and b won’t be converted and will be compared directly. If the assumption fails, the test will be marked as “skipped”.  

Parameters  
• a – Value to compare  
• b – Value to compare  
• ... – Optional message and variables to print if the assumption fails

zassume_not_equal(a, b, ...)  
Assume that a does not equal b.  
a and b won’t be converted and will be compared directly. If the assumption fails, the test will be marked as “skipped”.  

Parameters  
• a – Value to compare  
• b – Value to compare  
• ... – Optional message and variables to print if the assumption fails
\texttt{zassume\_equal\_ptr(a, b, ...)}
Assume that \( a \) equals \( b \).

\( a \) and \( b \) will be converted to \texttt{void *} before comparing. If the assumption fails, the test will be marked as “skipped”.

\textbf{Parameters}

\begin{itemize}
  \item \( a \) – Value to compare
  \item \( b \) – Value to compare
  \item \( \ldots \) – Optional message and variables to print if the assumption fails
\end{itemize}

\texttt{zassume\_within(a, b, d, ...)}
Assume that \( a \) is within \( b \) with delta \( d \).

If the assumption fails, the test will be marked as “skipped”.

\textbf{Parameters}

\begin{itemize}
  \item \( a \) – Value to compare
  \item \( b \) – Value to compare
  \item \( d \) – Delta
  \item \( \ldots \) – Optional message and variables to print if the assumption fails
\end{itemize}

\texttt{zassume\_between\_inclusive(a, l, u, ...)}
Assume that \( a \) is greater than or equal to \( l \) and less than or equal to \( u \).

If the assumption fails, the test will be marked as “skipped”.

\textbf{Parameters}

\begin{itemize}
  \item \( a \) – Value to compare
  \item \( l \) – Lower limit
  \item \( u \) – Upper limit
  \item \( \ldots \) – Optional message and variables to print if the assumption fails
\end{itemize}

\texttt{zassume\_mem\_equal(...)}
Assume that 2 memory buffers have the same contents.

This macro calls the final memory comparison assumption macro. Using double expansion allows providing some arguments by macros that would expand to more than one values (ANSI-C99 defines that all the macro arguments have to be expanded before macro call).

\textbf{Parameters}

\begin{itemize}
  \item \( \ldots \) – Arguments, see \texttt{zassume\_mem\_equal\_} for real arguments accepted.
\end{itemize}

\texttt{zassume\_mem\_equal\_}(buf, exp, size, ...)
Internal assume that 2 memory buffers have the same contents.

If the assumption fails, the test will be marked as “skipped”.

\textbf{Note:} This is internal macro, to be used as a second expansion. See \texttt{zassume\_mem\_equal}.

\textbf{Parameters}

\begin{itemize}
  \item \( \text{buf} \) – Buffer to compare
  \item \( \text{exp} \) – Buffer with expected contents
\end{itemize}
• size – Size of buffers
• ... – Optional message and variables to print if the assumption fails

Ztress

group ztest_ztress

This module provides test stress when using Ztest.

Defines

ZTRESS_TIMER(handler, user_data, exec_cnt, init_timeout)

Descriptor of a k_timer handler execution context.

The handler is executed in the k_timer handler context which typically means interrupt context. This context will preempt any other used in the set.

Note: There can only be up to one k_timer context in the set and it must be the first argument of ZTRESS_EXECUTE.

Parameters

• handler – User handler of type ztress_handler.
• user_data – User data passed to the handler.
• exec_cnt – Number of handler executions to complete the test. If 0 then this is not included in completion criteria.
• init_timeout – Initial backoff time base (given in k_timeout_t). It is adjusted during the test to optimize CPU load. The actual timeout used for the timer is randomized.

ZTRESS_THREAD(handler, user_data, exec_cnt, preempt_cnt, init_timeout)

Descriptor of a thread execution context.

The handler is executed in the thread context. The priority of the thread is determined based on the order in which contexts are listed in ZTRESS_EXECUTE.

Note: thread sleeps for random amount of time. Additionally, the thread busy-waits for a random length of time to further increase randomization in the test.

Parameters

• handler – User handler of type ztress_handler.
• user_data – User data passed to the handler.
• exec_cnt – Number of handler executions to complete the test. If 0 then this is not included in completion criteria.
• preempt_cnt – Number of preemptions of that context to complete the test. If 0 then this is not included in completion criteria.
• init_timeout – Initial backoff time base (given in k_timeout_t). It is adjusted during the test to optimize CPU load. The actual timeout used for sleeping is randomized.
ZTRESS_CONTEXT_INITIALIZER(_handler, _user_data, _exec_cnt, _preempt_cnt, _t)
Initialize context structure.
For argument types see \texttt{ztress_context_data}. For more details see \texttt{ZTRESS_THREAD}.

\textbf{Parameters}
\begin{itemize}
  \item \_handler – Handler.
  \item \_user\_data – User data passed to the handler.
  \item \_exec\_cnt – Execution count limit.
  \item \_preempt\_cnt – Preemption count limit.
  \item \_t – Initial timeout.
\end{itemize}

ZTRESS_EXECUTE(…)
Setup and run stress test.
It initialises all contexts and calls \texttt{ztress_execute}.

\textbf{Parameters}
\begin{itemize}
  \item \ldots – List of contexts. Contexts are configured using \texttt{ZTRESS\_TIMER} and \\
  \texttt{ZTRESS\_THREAD} macros. \texttt{ZTRESS\_TIMER} must be the first argument if \\
  used. Each thread context has an assigned priority. The priority is assigned \\
  in a descending order (first listed thread context has the highest \\
  priority). The maximum number of supported thread contexts, including \\
  the timer context, is configurable in Kconfig (\texttt{ZTRESS\_MAX\_THREADS}).
\end{itemize}

\textbf{Typedefs}

typedef bool (*\texttt{ztress\_handler})(void *user\_data, uint32\_t cnt, bool last, int prio)
User handler called in one of the configured contexts.

\begin{itemize}
  \item \textbf{Param user\_data}
    User data provided in the context descriptor.
  \item \textbf{Param cnt}
    Current execution counter. Counted from 0.
  \item \textbf{Param last}
    Flag set to true indicates that it is the last execution because completion \\
    criteria are met, test timed out or was aborted.
  \item \textbf{Param prio}
    Context priority counting from 0 which indicates the highest priority.
\end{itemize}

\begin{itemize}
  \item \textbf{Retval true}
    continue test.
  \item \textbf{Retval false}
    stop executing the current context.
\end{itemize}

\textbf{Functions}

\begin{verbatim}
int \texttt{ztress\_execute}(struct \texttt{ztress\_context\_data} \*timer\_data, struct \texttt{ztress\_context\_data} \\
\*thread\_data, size\_t cnt)
Execute contexts.
\end{verbatim}

The test runs until all completion requirements are met or until the test times out (use \\
\texttt{ztress\_set\_timeout} to configure timeout) or until the test is aborted (\texttt{ztress\_abort}).
on test completion a report is printed (\texttt{ztress_report} is called internally).

**Parameters**

- \texttt{timer\_data} – Timer context. NULL if timer context is not used.
- \texttt{thread\_data} – List of thread contexts descriptors in priority descending order.
- \texttt{cnt} – Number of thread contexts.

**Return values**

- \texttt{-EINVAL} – If configuration is invalid.
- \texttt{0} – if test is successfully performed.

```c
void zstress_abort(void)
Abort ongoing stress test.
```

```c
void zstress_set_timeout(k_timeout_t t)
Set test timeout.
Test is terminated after timeout disregarding completion criteria. Setting is persistent between executions.
```

**Parameters**

- \texttt{t} – Timeout.

```c
void zstress_report(void)
Print last test report.
```

Report contains number of executions and preemptions for each context, initial and adjusted timeouts and CPU load during the test.

```c
int zstress_exec_count(uint32_t id)
Get number of executions of a given context in the last test.
```

**Parameters**

- \texttt{id} – Context id. 0 means the highest priority.

**Returns**

Number of executions.

```c
int zstress_preempt_count(uint32_t id)
Get number of preemptions of a given context in the last test.
```

**Parameters**

- \texttt{id} – Context id. 0 means the highest priority.

**Returns**

Number of preemptions.

```c
uint32_t zstress_optimized_ticks(uint32_t id)
Get optimized timeout base of a given context in the last test.
```

Optimized value can be used to update initial value. It will improve the test since optimal CPU load will be reach immediately.

**Parameters**

- \texttt{id} – Context id. 0 means the highest priority.

**Returns**

Optimized timeout base.
Zephyr Project Documentation, Release 3.6.0-rc3

```c
struct ztress_context_data
#include <ztress.h>
```

Mocking via FFF

Zephyr has integrated with FFF for mocking. See FFF for documentation. To use it, include the relevant header:

```c
#include <zephyr/fff.h>
```

Zephyr provides several FFF-based fake drivers which can be used as either stubs or mocks. Fake driver instances are configured via Devicetree and Configuration System (Kconfig). See the following devicetree bindings for more information:

- `zephyr,fake-can`
- `zephyr,fake-eeprom`

Zephyr also has defined extensions to FFF for simplified declarations of fake functions. See FFF Extensions.

Customizing Test Output

Customization is enabled by setting `CONFIG_ZTEST_TC_UTIL_USER_OVERRIDE` to “y” and adding a file `tc_util_user_override.h` with your overrides.

Add the line `zephyr_include_directories(my_folder)` to your project's `CMakeLists.txt` to let Zephyr find your header file during builds.

See the file `subsys/testsuite/include/zephyr/tc_util.h` to see which macros and/or defines can be overridden. These will be surrounded by blocks such as:

```c
#ifndef SOMETHING
#define SOMETHING <default implementation>
#endif /* SOMETHING */
```

Shuffling Test Sequence

By default the tests are sorted and ran in alphanumerical order. Test cases may be dependent on this sequence. Enable `CONFIG_ZTEST_SHUFFLE` to randomize the order. The output from the test will display the seed for failed tests. For native simulator builds you can provide the seed as an argument to twister with `-seed`

Static configuration of `ZTEST_SHUFFLE` contains:

- `CONFIG_ZTEST_SHUFFLE_SUITE_REPEAT_COUNT` - Number of iterations the test suite will run.
- `CONFIG_ZTEST_SHUFFLE_TEST_REPEAT_COUNT` - Number of iterations the test will run.

Test Selection

For tests built for native simulator, use command line arguments to list or select tests to run. The test argument expects a comma separated list of `suite::test`. You can substitute the test name with an `*` to run all tests within a suite.

For example
FFF Extensions

group fff_extensions

This module provides extensions to FFF for simplifying the configuration and usage of fakes.

Defines

\[
\text{RETURN\_HANDLED\_CONTEXT}\left(\text{FUNCNAME, CONTEXTTYPE, RESULTFIELD, CONTEXTPTRNAME, HANDLERBODY}\right)
\]

Wrap custom fake body to extract defined context struct.

Add extension macro for simplified creation of fake functions needing call-specific context data.

This macro enables a fake to be implemented as follows and requires no familiarity with the inner workings of FFF.

```c
struct FUNCNAME##_custom_fake_context {
    struct instance * const instance;
    int result;
};

int FUNCNAME##_custom_fake(const struct instance **instance_out) {
    RETURN_HANDLED_CONTEXT(
        FUNCNAME,
        struct FUNCNAME##_custom_fake_context,
        result,
        context,
        {
            if (context != NULL) {
                if (context->result == 0) {
                    if (instance_out != NULL) {
                        *instance_out = context->instance;
                    }
                }
                return context->result;
            }
            return FUNCNAME##_fake.return_val;
        }
    );
}
```

Parameters

- \text{FUNCNAME} – Name of function being faked
2.12.2 Test Runner (Twister)

This script scans for the set of unit test applications in the git repository and attempts to execute them. By default, it tries to build each test case on boards marked as default in the board definition file.

The default options will build the majority of the tests on a defined set of boards and will run in an emulated environment if available for the architecture or configuration being tested.

In normal use, twister runs a limited set of kernel tests (inside an emulator). Because of its limited test execution coverage, twister cannot guarantee local changes will succeed in the full build environment, but it does sufficient testing by building samples and tests for different boards and different configurations to help keep the complete code tree buildable.

When using (at least) one `-v` option, twister’s console output shows for every test how the test is run (qemu, native_sim, etc.) or whether the binary was just built. There are a few reasons why twister only builds a test and doesn’t run it:

- The test is marked as `build_only: true` in its `.yaml` configuration file.
- The test configuration has defined a harness but you don’t have it or haven’t set it up.
- The target device is not connected and not available for flashing
- You or some higher level automation invoked twister with `--build-only`.

To run the script in the local tree, follow the steps below:

Linux

```
$ source zephyr-env.sh
$ ./scripts/twister
```

Windows

```
zephyr-env.cmd
python .\scripts\twister
```

If you have a system with a large number of cores and plenty of free storage space, you can build and run all possible tests using the following options:

Linux

```
$ ./scripts/twister --all --enable-slow
```

Windows

```
python .\scripts\twister --all --enable-slow
```

This will build for all available boards and run all applicable tests in a simulated (for example QEMU) environment.

If you want to run tests on one or more specific platforms, you can use the `--platform` option, it is a platform filter for testing, with this option, test suites will only be built/run on the platforms specified. This option also supports different revisions of one same board, you can use `--platform board@revision` to test on a specific revision.
The list of command line options supported by twister can be viewed using:

Linux

```
$ ./scripts/twister --help
```

Windows

```
python ./scripts/twister --help
```

## Board Configuration

To build tests for a specific board and to execute some of the tests on real hardware or in an emulation environment such as QEMU a board configuration file is required which is generic enough to be used for other tasks that require a board inventory with details about the board and its configuration that is only available during build time otherwise.

The board metadata file is located in the board directory and is structured using the YAML markup language. The example below shows a board with a data required for best test coverage for this specific board:

```
identifier: frdm_k64f
name: NXP FRDM-K64F
type: mcu
arch: arm
toolchain:
  - zephyr
  - gnuarmemb
  - xtools
supported:
  - arduino_gpio
  - arduino_i2c
  - netif:eth
  - adc
  - i2c
  - nvs
  - spi
  - gpio
  - usb_device
  - watchdog
  - can
  - pwm
testing:
  default: true
```

**identifier:**
A string that matches how the board is defined in the build system. This same string is used when building, for example when calling `west build` or `cmake`:

```
# with west
west build -b reel_board
# with cmake
cmake -DBOARD=reel_board ..
```

**name:**
The actual name of the board as it appears in marketing material.

**type:**
Type of the board or configuration, currently we support 2 types: mcu, qemu

**simulation:**
Simulator used to simulate the platform, e.g. qemu.
arch:
  Architecture of the board

toolchain:
The list of supported toolchains that can build this board. This should match one of the values used for `ZEPHYR_TOOLCHAIN_VARIANT` when building on the command line.

ram:
  Available RAM on the board (specified in KB). This is used to match testcase requirements. If not specified we default to 128KB.

flash:
  Available FLASH on the board (specified in KB). This is used to match testcase requirements. If not specified we default to 512KB.

supported:
  A list of features this board supports. This can be specified as a single word feature or as a variant of a feature class. For example:

  ```yaml
  supported:
    - pci
  ```

  This indicates the board does support PCI. You can make a testcase build or run only on such boards, or:

  ```yaml
  supported:
    - netif:eth
    - sensor:bmi16
  ```

  A testcase can both depend on ‘eth’ to only test ethernet or on ‘netif’ to run on any board with a networking interface.

testing:
  testing relating keywords to provide best coverage for the features of this board.

default: [True|False]:
  This is a default board, it will tested with the highest priority and is covered when invoking the simplified twister without any additional arguments.

ignore_tags:
  Do not attempt to build (and therefore run) tests marked with this list of tags.

only_tags:
  Only execute tests with this list of tags on a specific platform.

timeout_multiplier: <float> (default 1)
  Multiply each test case timeout by specified ratio. This option allows to tune timeouts only for required platform. It can be useful in case naturally slow platform i.e.: HW board with power-efficient but slow CPU or simulation platform which can perform instruction accurate simulation but does it slowly.

Test Cases

Test cases are detected by the presence of a `testcase.yaml` or a `sample.yaml` files in the application's project directory. This file may contain one or more entries in the test section each identifying a test scenario.

The name of each testcase needs to be unique in the context of the overall testsuite and has to follow basic rules:

1. The format of the test identifier shall be a string without any spaces or special characters (allowed characters: alphanumeric and [\_\=]) consisting of multiple sections delimited with a dot (\.).
2. Each test identifier shall start with a section followed by a subsection separated by a dot. For example, a test that covers semaphores in the kernel shall start with kernel.semaaphore.

3. All test identifiers within a testcase.yaml file need to be unique. For example a testcase.yaml file covering semaphores in the kernel can have:
   - kernel.semaaphore: For general semaphore tests
   - kernel.semaaphore.stress: Stress testing semaphores in the kernel.

4. Depending on the nature of the test, an identifier can consist of at least two sections:
   - Ztest tests: The individual testcases in the ztest testsuite will be concatenated to identifier in the testcase.yaml file generating unique identifiers for every testcase in the suite.
   - Standalone tests and samples: This type of test should at least have 3 sections in the test identifier in the testcase.yaml (or sample.yaml) file. The last section of the name shall signify the test itself.

Test cases are written using the YAML syntax and share the same structure as samples. The following is an example test with a few options that are explained in this document.

```
tests:
  bluetooth.gatt:
    build_only: true
    platform_allow: qemu_cortex_m3 qemu_x86
    tags: bluetooth
  bluetooth.gatt.br:
    build_only: true
    extra_args: CONF_FILE="prj_br.conf"
    platform_exclude: up_squared
    platform_allow: qemu_cortex_m3 qemu_x86
    tags: bluetooth
```

A sample with tests will have the same structure with additional information related to the sample and what is being demonstrated:

```
sample:
  name: hello world
  description: Hello World sample, the simplest Zephyr application
tests:
  sample.basic.hello_world:
    build_only: true
    tags: tests
    min_ram: 16
  sample.basic.hello_world.singlethread:
    build_only: true
    extra_args: CONF_FILE=prj_single.conf
    filter: not CONFIG_DEBUG
    platform_exclude: up_squared
    platform_allow: qemu_cortex_m3 qemu_x86
    tags: tests
    min_ram: 16
```

The full canonical name for each test case is: <path to test case>/<test entry>

Each test block in the testcase meta data can define the following key/value pairs:

- **tags**: `<list of tags>` *(required)*
  A set of string tags for the testcase. Usually pertains to functional domains but can be anything. Command line invocations of this script can filter the set of tests to run based on tag.

- **skip**: `<True|False>` *(default False)*
  Skip testcase unconditionally. This can be used for broken tests.
slow: `<True|False>` (default False)
Don’t run this test case unless `--enable-slow` or `--enable-slow-only` was passed in on the command line. Intended for time-consuming test cases that are only run under certain circumstances, like daily builds. These test cases are still compiled.

extra_args: `<list of extra arguments>`
Extra arguments to pass to Make when building or running the test case.

extra_configs: `<list of extra configurations>`
Extra configuration options to be merged with a master `prj.conf` when building or running the test case. For example:

```
common:
  tags: drivers adc
tests:
  test:
    depends_on: adc
test_async:
  extra_configs:
    - CONFIG_ADC_ASYNC=y

Using namespaces, it is possible to apply a configuration only to some hardware. Currently both architectures and platforms are supported:

```
common:
  tags: drivers adc
tests:
  test:
    depends_on: adc
test_async:
  extra_configs:
    - arch:x86:CONFIG_ADC_ASYNC=y
    - platform:qemu_x86:CONFIG_DEBUG=y
```

build_only: `<True|False>` (default False)
If true, twister will not try to run the test even if the test is runnable on the platform.

This keyword is reserved for tests that are used to test if some code actually builds. A build_only test is not designed to be run in any environment and should not be testing any functionality, it only verifies that the code builds.

This option is often used to test drivers and the fact that they are correctly enabled in Zephyr and that the code builds, for example sensor drivers. Such test shall not be used to verify the functionality of the driver.

build_on_all: `<True|False>` (default False)
If true, attempt to build test on all available platforms. This is mostly used in CI for increased coverage. Do not use this flag in new tests.

depends_on: `<list of features>`
A board or platform can announce what features it supports, this option will enable the test only those platforms that provide this feature.

levels: `<list of levels>`
Test levels this test should be part of. If a level is present, this test will be selectable using the command line option `--level <level name>`

min_ram: `<integer>`
minimum amount of RAM in KB needed for this test to build and run. This is compared with information provided by the board metadata.

min_flash: `<integer>`
minimum amount of ROM in KB needed for this test to build and run. This is compared with information provided by the board metadata.
timeout: <number of seconds>
Length of time to run test before automatically killing it. Default to 60 seconds.

arch_allow: <list of arches, such as x86, arm, arc>
Set of architectures that this test case should only be run for.

arch_exclude: <list of arches, such as x86, arm, arc>
Set of architectures that this test case should not run on.

platform_allow: <list of platforms>
Set of platforms that this test case should only be run for. Do not use this option to limit testing or building in CI due to time or resource constraints, this option should only be used if the test or sample can only be run on the allowed platform and nothing else.

integration_platforms: <YML list of platforms/boards>
This option limits the scope to the listed platforms when twister is invoked with the --integration option. Use this instead of platform_allow if the goal is to limit scope due to timing or resource constraints.

platform_exclude: <list of platforms>
Set of platforms that this test case should not run on.

extra_sections: <list of extra binary sections>
When computing sizes, twister will report errors if it finds extra, unexpected sections in the Zephyr binary unless they are named here. They will not be included in the size calculation.

sysbuild: <True|False> (default False)
Build the project using sysbuild infrastructure. Only the main project's generated device-tree and Kconfig will be used for filtering tests. On device testing must use the hardware map, or west flash to load the images onto the target. The --erase option of west flash is not supported with this option. Usage of unsupported options will result in tests requiring sysbuild support being skipped.

harness: <string>
A harness keyword in the testcase.yaml file identifies a Twister harness needed to run a test successfully. A harness is a feature of Twister and implemented by Twister, some harnesses are defined as placeholders and have no implementation yet.

A harness can be seen as the handler that needs to be implemented in Twister to be able to evaluate if a test passes criteria. For example, a keyboard harness is set on tests that require keyboard interaction to reach verdict on whether a test has passed or failed, however, Twister lack this harness implementation at the moment.

Supported harnesses:

- ztest
- test
- console
- pytest
- gtest
- robot

Harnesses ztest, gtest and console are based on parsing of the output and matching certain phrases. ztest and gtest harnesses look for pass/fail/etc. frames defined in those frameworks. Use gtest harness if you've already got tests written in the gTest framework and do not wish to update them to zTest. The console harness tells Twister to parse a test's text output for a regex defined in the test's YAML file. The robot harness is used to execute Robot Framework test suites in the Renode simulation framework.

Some widely used harnesses that are not supported yet:

- keyboard
Harness \texttt{bsim} is implemented in limited way - it helps only to copy the final executable (\texttt{zephyr.exe}) from build directory to BabbleSim's bin directory ($\{BSIM\_OUT\_PATH\}/bin). This action is useful to allow BabbleSim's tests to directly run after. By default, the executable file name is (with dots and slashes replaced by underscores): \texttt{bs_<platform_name>_<test_path>_<test_scenario_name>}. This name can be overridden with the \texttt{bsim\_exe\_name} option in harness\_config section.

**platform\_key: <list of platform attributes>**

Often a test needs to only be built and run once to qualify as passing. Imagine a library of code that depends on the platform architecture where passing the test on a single platform for each arch is enough to qualify the tests and code as passing. The platform\_key attribute enables doing just that.

For example to key on (arch, simulation) to ensure a test is run once per arch and simulation (as would be most common):

\begin{verbatim}
platform_key:
- arch
- simulation
\end{verbatim}

Adding platform (board) attributes to include things such as soc name, soc family, and perhaps sets of IP blocks implementing each peripheral interface would enable other interesting uses. For example, this could enable building and running SPI tests once for each unique IP block.

**harness\_config: <harness configuration options>**

Extra harness configuration options to be used to select a board and/or for handling generic Console with regex matching. Config can announce what features it supports. This option will enable the test to run on only those platforms that fulfill this external dependency.

The following options are currently supported:

- **type: <one\_line|m\ulti\_line> (required)**
  Depends on the regex string to be matched

- **regex: <list of regular expressions> (required)**
  Strings with regular expressions to match with the test's output to confirm the test runs as expected.

- **ordered: <True|False> (default False)**
  Check the regular expression strings in orderly or randomly fashion

- **repeat: <integer>**
  Number of times to validate the repeated regex expression

- **record: <recording options> (optional)**

  - **regex: <regular expression> (required)**
    The regular expression with named subgroups to match data fields at the test's output lines where the test provides some custom data for further analysis. These records will be written into the build directory ‘recording.csv’ file as well as ‘recording’ property of the test suite object in ‘twister\_json’.

    For example, to extract three data fields ‘metric’, ‘cycles’, ‘nanoseconds’:

    \begin{verbatim}
    record:
      regex: "(?P<metric>.*):(?P<cycles>.*):cycling, (?P<nanoseconds>.*):ns"
    \end{verbatim}

- **fixture: <expression>**
  Specify a test case dependency on an external device(e.g., sensor), and identify setups that fulfill this dependency. It depends on specific test setup and board selection logic to pick the particular board(s) out of multiple boards that fulfill the dependency
in an automation setup based on fixture keyword. Some sample fixture names are i2c_hts221, i2c_bme280, i2c_FRAM, ble_hw and gpio_loop.

Only one fixture can be defined per testcase and the fixture name has to be unique across all tests in the test suite.

**pytest_root: <list of pytest testpaths> (default pytest)**

Specify a list of pytest directories, files or subtests that need to be executed when a test case begins to run. The default pytest directory is pytest. After the pytest run is finished, Twister will check if the test case passed or failed according to the pytest report. As an example, a list of valid pytest roots is presented below:

```yaml
harness_config:
  pytest_root:
    - "pytest/test_shell_help.py"
    - "../shell/pytest/test_shell.py"
    - "~/.test_shell.py"
    - "$ZEPHYR_BASE/samples/subsys/pytest/shell/pytest/test_shell.py"
    - "pytest/test_shell_help.py::test_shell2_sample"  # select pytest...
    - "pytest/test_shell_help.py::test_shell2_sample[param_a]"  # select...
  pytest parametrized subtest
```

**pytest_args: <list of arguments> (default empty)**

Specify a list of additional arguments to pass to pytest e.g.: pytest_args: ['-k=test_method', '--log-level=DEBUG']. Note that --pytest-args can be passed multiple times to pass several arguments to the pytest.

**pytest_dut_scope: <function|class|module|package|session> (default function)**

The scope for which dut and shell pytest fixtures are shared. If the scope is set to function, DUT is launched for every test case in python script. For session scope, DUT is launched only once.

**robot_test_path: <robot file path> (default empty)**

Specify a path to a file containing a Robot Framework test suite to be run.

**bsim_exe_name: <string>**

If provided, the executable filename when copying to BabbleSim's bin directory, will be bs_<platform_name>_<bsim_exe_name> instead of the default based on the test path and scenario name.

The following is an example yaml file with a few harness_config options.

```
sample:
  name: HTS221 Temperature and Humidity Monitor

commom:
  tags: sensor
  harness: console
  harness_config:
    type: multi_line
    ordered: false
    regex:
      - "Temperature:(.*)C"
      - "Relative Humidity:(.*)%"
  fixture: i2c_hts221

tests:
  test:
    tags: sensors
    depends_on: i2c
```

The following is an example yaml file with pytest harness_config options, default pytest_root name “pytest” will be used if pytest_root not specified. Please refer the
examples in samples/subsys/testsuite/pytest/.

```yaml
common:
  harness: pytest
tests:
  pytest.example.directories:
    harness_config:
      pytest_root:
        - pytest_dir1
        - $ENV_VAR/samples/test/pytest_dir2
  pytest.example.files_and_subtests:
    harness_config:
      pytest_root:
        - pytest/test_file_1.py
        - test_file_2.py::test_A
        - test_file_2.py::test_B[param_a]
```

The following is an example yaml file with robot harness_config options.

```yaml
tests:
  robot.example:
    harness: robot
    harness_config: [robot file path]
```

**filter: <expression>**

Filter whether the testcase should be run by evaluating an expression against an environment containing the following values:

```yaml
{ ARCH : <architecture>,
  PLATFORM : <platform>,
  <all CONFIG_* key/value pairs in the test's generated defconfig>,
  *<env>: any environment variable available
}
```

Twister will first evaluate the expression to find if a “limited” cmake call, i.e. using package_helper cmake script, can be done. Existence of “dt_” entries indicates devicetree is needed. Existence of “CONFIG*” entries indicates kconfig is needed. If there are no other types of entries in the expression a filtration can be done without creating a complete build system. If there are entries of other types a full cmake is required.

The grammar for the expression language is as follows:

```yaml
expression : expression 'and' expression
            | expression 'or' expression
            | 'not' expression
            | '(' expression ')'
symbol '==' constant
symbol '!=' constant
symbol '<' NUMBER
symbol '>' NUMBER
symbol '>=' NUMBER
symbol '<=' NUMBER
symbol 'in' list
symbol ':' STRING
symbol;
```

```yaml
list : '[' list_contents ']'
```

```yaml
list_contents : constant (',', constant)*
```

```yaml
constant : NUMBER | STRING;
```
For the case where \( \text{expression} ::= \text{symbol} \), it evaluates to true if the symbol is defined to a non-empty string.

Operator precedence, starting from lowest to highest:

- or (left associative)
- and (left associative)
- not (right associative)
- all comparison operators (non-associative)

`arch_allow`, `arch_exclude`, `platform_allow`, `platform_exclude` are all syntactic sugar for these expressions. For instance:

```plaintext
arch_exclude = x86 arc
```

Is the same as:

```plaintext
filter = not ARCH in ["x86", "arc"]
```

The `:` operator compiles the string argument as a regular expression, and then returns a true value only if the symbol's value in the environment matches. For example, if `CONFIG_SOC="stm32f107xc"` then

```plaintext
filter = CONFIG_SOC : "stm.*"
```

Would match it.

**required_snippets:** `<list of needed snippets>`

Snippets are supported in twister for test cases that require them. As with normal applications, twister supports using the base zephyr snippet directory and test application directory for finding snippets. Listed snippets will filter supported tests for boards (snippets must be compatible with a board for the test to run on them, they are not optional).

The following is an example yaml file with 2 required snippets.

```yaml
tests:
  snippet.example:
    required_snippets:
      - cdc-acm-console
      - user-snippet-example
```

The set of test cases that actually run depends on directives in the testcase filed and options passed in on the command line. If there is any confusion, running with `-v` or examining the discard report (`twister_discard.csv`) can help show why particular test cases were skipped.

Metrics (such as pass/fail state and binary size) for the last code release are stored in `scripts/release/twister_last_release.csv`. To update this, pass the `--all --release` options.

To load arguments from a file, add `+` before the file name, e.g., `+file_name`. File content must be one or more valid arguments separated by line break instead of white spaces.

Most everyday users will run with no arguments.

**Managing tests timeouts**

There are several parameters which control tests timeouts on various levels:

- `timeout` option in each test case. See `here` for more details.
- `timeout_multiplier` option in board configuration. See `here` for more details.
• `--timeout-multiplier` twister option which can be used to adjust timeouts in exact twister run. It can be useful in case of simulation platform as simulation time may depend on the host speed & load or we may select different simulation method (i.e. cycle accurate but slower one), etc...

Overall test case timeout is a multiplication of these three parameters.

**Running in Integration Mode**

This mode is used in continuous integration (CI) and other automated environments used to give developers fast feedback on changes. The mode can be activated using the `--integration` option of twister and narrows down the scope of builds and tests if applicable to platforms defined under the integration keyword in the testcase definition file (testcase.yaml and sample.yaml).

**Running tests on custom emulator**

Apart from the already supported QEMU and other simulated environments, Twister supports running any out-of-tree custom emulator defined in the board’s board.cmake. To use this type of simulation, add the following properties to `custom_board/custom_board.yaml`:

```yaml
simulation: custom
simulation_exec: <name_of_emu_binary>
```

This tells Twister that the board is using a custom emulator called `<name_of_emu_binary>`, make sure this binary exists in the PATH.

Then, in `custom_board/board.cmake`, set the supported emulation platforms to custom:

```
set(SUPPORTED_EMU_PLATFORMS custom)
```

Finally, implement the `run_custom` target in `custom_board/board.cmake`. It should look something like this:

```cemake
add_custom_target(run_custom
COMMAND
  <name_of_emu_binary to invoke during 'run'>
  <any args to be passed to the command, i.e. ${BOARD}, ${APPLICATION_BINARY_DIR}/zephyr/
    --zephyr.elf>
  WORKING_DIRECTORY ${APPLICATION_BINARY_DIR}
  DEPENDS ${logical_target_for_zephyr_elf}
  USES_TERMINAL
)
```

**Running Tests on Hardware**

Beside being able to run tests in QEMU and other simulated environments, twister supports running most of the tests on real devices and produces reports for each run with detailed FAIL/PASS results.

**Executing tests on a single device** To use this feature on a single connected device, run twister with the following new options:

```
Linux

scripts/twister --device-testing --device-serial /dev/ttyACM0 \
  --device-serial-baud 115200 -p frdm_k64f -T tests/kernel
```
Windows

```bash
python .\scripts\twister --device-testing --device-serial COM1 \--device-serial-baud 115200 -p frdm_k64f -T tests/kernel
```

The `--device-serial` option denotes the serial device the board is connected to. This needs to be accessible by the user running `twister`. You can run this on only one board at a time, specified using the `--platform` option.

The `--device-serial-baud` option is only needed if your device does not run at 115200 baud.

To support devices without a physical serial port, use the `--device-serial-pty` option. In this cases, log messages are captured for example using a script. In this case you can run `twister` with the following options:

Linux

```bash
scripts/twister --device-testing --device-serial-pty "script.py" \-p intel_adsp_cavs25 -T tests/kernel
```

Windows

**Note:** Not supported on Windows OS

The script is user-defined and handles delivering the messages which can be used by `twister` to determine the test execution status.

The `--device-flash-timeout` option allows to set explicit timeout on the device flash operation, for example when device flashing takes significantly large time.

The `--device-flash-with-test` option indicates that on the platform the flash operation also executes a test case, so the flash timeout is increased by a test case timeout.

### Executing tests on multiple devices

To build and execute tests on multiple devices connected to the host PC, a hardware map needs to be created with all connected devices and their details such as the serial device, baud and their IDs if available. Run the following command to produce the hardware map:

Linux

```bash
./scripts/twister --generate-hardware-map map.yml
```

Windows

```bash
python .\scripts\twister --generate-hardware-map map.yml
```

The generated hardware map file (map.yml) will have the list of connected devices, for example:

**Linux**

```yaml
- connected: true
  id: OSHW000082254e4500128002ab98002784d100097969900
  platform: unknown
  product: DAPLink CMSIS-DAP
  runner: pyocd
  serial: /dev/cu.usbmodem146114202
- connected: true
  id: 000683759358
  platform: unknown
  product: J-Link
  runner: unknown
  serial: /dev/cu.usbmodem0006837593581
```
Any options marked as unknown need to be changed and set with the correct values, in the above example the platform names, the products and the runners need to be replaced with the correct values corresponding to the connected hardware. In this example we are using a reel_board and an nrf52840dk_nrf52840:

Linux

The baud entry is only needed if not running at 115200.

If the map file already exists, then new entries are added and existing entries will be updated. This way you can use one single master hardware map and update it for every run to get the correct serial devices and status of the devices.

With the hardware map ready, you can run any tests by pointing to the map

Linux
The above command will result in twister building tests for the platforms defined in the hardware map and subsequently flashing and running the tests on those platforms.

**Note:** Currently only boards with support for pyocd, nrfjprog, jlink, openocd, or dediprog are supported with the hardware map features. Boards that require other runners to flash the Zephyr binary are still work in progress.

Hardware map allows to set `--device-flash-timeout` and `--device-flash-with-test` command line options as `flash-timeout` and `flash-with-test` fields respectively. These hardware map values override command line options for the particular platform.

Serial PTY support using `--device-serial-pty` can also be used in the hardware map:

```
- connected: true
  id: None
  platform: intel_adsp_cavs25
  product: None
  runner: intel_adsp
  serial_pty: path/to/script.py
  runner_params:
    - --remote-host=remote_host_ip_addr
    - --key=/path/to/key.pem
```

The runner_params field indicates the parameters you want to pass to the west runner. For some boards the west runner needs some extra parameters to work. It is equivalent to following west and twister commands.

**Linux**

```
west flash --remote-host remote_host_ip_addr --key /path/to/key.pem
twister -p intel_adsp_cavs25 --device-testing --device-serial-pty script.py
--west-flash="--remote-host=remote_host_ip_addr,--key=/path/to/key.pem"
```

**Windows**

**Note:** Not supported on Windows OS

**Note:** For serial PTY, the “--generate-hardware-map” option cannot scan it out and generate a correct hardware map automatically. You have to edit it manually according to above example. This is because the serial port of the PTY is not fixed and being allocated in the system at runtime.

**Fixtures** Some tests require additional setup or special wiring specific to the test. Running the tests without this setup or test fixture may fail. A testcase can specify the fixture it needs which can then be matched with hardware capability of a board and the fixtures it supports via the command line or using the hardware map file.

Fixtures are defined in the hardware map file as a list:
When running twister with `--device-testing`, the configured fixture in the hardware map file will be matched to testcases requesting the same fixtures and these tests will be executed on the boards that provide this fixture.

Fixtures can also be provided via twister command option `--fixture`, this option can be used multiple times and all given fixtures will be appended as a list. And the given fixtures will be assigned to all boards, this means that all boards set by current twister command can run those testcases which request the same fixtures.

**Notes**

It may be useful to annotate board descriptions in the hardware map file with additional information. Use the `notes` keyword to do this. For example:

```yaml
- connected: false
  fixtures:
    - gpio_loopback
      id: 0240000026334e450015400f5e0e00b4eb1000097969900
      platform: frdm_k64f
      product: DAPLink CMSIS-DAP
      runner: pyocd
      serial: /dev/ttyACM9
```

(continues on next page)
gpio_loopback

id: 00063290670

notes: An nrf5340dk_nrf5340 is detected as an nrf52840dk_nrf52840 with no serial port, and three serial ports with an unknown platform. The board id of the serial ports is not the same as the board id of the development kit. If you regenerate this file you will need to update serial to reference the third port, and platform to nrf5340dk_nrf5340_cpuapp or another supported board target.

platform: nrf52840dk_nrf52840
product: J-Link
runner: jlink
serial: null

Overriding Board Identifier   When (re-)generated the hardware map file will contain an id keyword that serves as the argument to --board-id when flashing. In some cases the detected ID is not the correct one to use, for example when using an external J-Link probe. The probe_id keyword overrides the id keyword for this purpose. For example:

- connected: false
  id: 022900005d9ebc6000000000000000000000000097969905
  platform: mimxrt1060_evk
  probe_id: 000609301751
  product: DAPLink CMSIS-DAP
  runner: jlink
  serial: null

Quarantine   Twister allows user to provide configuration files defining a list of tests or platforms to be put under quarantine. Such tests will be skipped and marked accordingly in the output reports. This feature is especially useful when running larger test suits, where a failure of one test can affect the execution of other tests (e.g. putting the physical board in a corrupted state).

To use the quarantine feature one has to add the argument --quarantine-list <PATH_TO_QUARANTINE_YAML> to a twister call. Multiple quarantine files can be used. The current status of tests on the quarantine list can also be verified by adding --quarantine-verify to the above argument. This will make twister skip all tests which are not on the given list.

A quarantine yaml has to be a sequence of dictionaries. Each dictionary has to have scenarios and platforms entries listing combinations of scenarios and platforms to put under quarantine. In addition, an optional entry comment can be used, where some more details can be given (e.g. link to a reported issue). These comments will also be added to the output reports.

When quarantining a class of tests or many scenarios in a single testsuite or when dealing with multiple issues within a subsystem, it is possible to use regular expressions, for example, kernel.* would quarantine all kernel tests.

An example of entries in a quarantine yaml:

- scenarios:
  - sample.basic.helloworld

  comment: "Link to the issue: https://github.com/zephyrproject-rtos/zephyr/pull/33287"

- scenarios:
  - kernel.common
  - kernel.common.(misra|tls)
  - kernel.common.nano64

  platforms:
  - .*_cortex_.*
  - native_sim

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To exclude a platform, use the following syntax:

```yaml
- platforms:
  - qemu_x86
  comment: "broken qemu"
```

Additionally you can quarantine entire architectures or a specific simulator for executing tests.

**Test Configuration**

A test configuration can be used to customize various aspects of twister and the default enabled options and features. This allows tweaking the filtering capabilities depending on the environment and makes it possible to adapt and improve coverage when targeting different sets of platforms.

The test configuration also adds support for test levels and the ability to assign a specific test to one or more levels. Using command line options of twister it is then possible to select a level and just execute the tests included in this level.

Additionally, the test configuration allows defining level dependencies and additional inclusion of tests into a specific level if the test itself does not have this information already.

In the configuration file you can include complete components using regular expressions and you can specify which test level to import from the same file, making management of levels easier.

To help with testing outside of upstream CI infrastructure, additional options are available in the configuration file, which can be hosted locally. As of now, those options are available:

- Ability to ignore default platforms as defined in board definitions (Those are mostly emulation platforms used to run tests in upstream CI)
- Option to specify your own list of default platforms overriding what upstream defines.
- Ability to override `build_on_all` options used in some testcases. This will treat tests or sample as any other just build for default platforms you specify in the configuration file or on the command line.
- Ignore some logic in twister to expand platform coverage in cases where default platforms are not in scope.

**Platform Configuration** The following options control platform filtering in twister:

- `override_default_platforms`: override default key a platform sets in board configuration and instead use the list of platforms provided in the configuration file as the list of default platforms. This option is set to False by default.
- `increased_platform_scope`: This option is set to True by default, when disabled, twister will not increase platform coverage automatically and will only build and run tests on the specified platforms.
- `default_platforms`: A list of additional default platforms to add. This list can either be used to replace the existing default platforms or can extend it depending on the value of `override_default_platforms`.

And example platforms configuration:

```yaml
platforms:
  override_default_platforms: true
  increased_platform_scope: false
  default_platforms:
    - qemu_x86
```
Test Level Configuration  The test configuration allows defining test levels, level dependencies and additional inclusion of tests into a specific test level if the test itself does not have this information already.

In the configuration file you can include complete components using regular expressions and you can specify which test level to import from the same file, making management of levels simple.

And example test level configuration:

```yaml
levels:
  - name: my-test-level
    description: >
      my custom test level
    adds:
      - kernel.threads.*
      - kernel.timer.behavior
      - arch.interrupt
      - boards.*
```

Combined configuration  To mix the Platform and level configuration, you can take an example as below:

An example platforms plus level configuration:

```yaml
platforms:
  override_default_platforms: true
  default_platforms:
    - frdm_k64f
levels:
  - name: smoke
    description: >
      A plan to be used verifying basic zephyr features.
  - name: unit
    description: >
      A plan to be used verifying unit test.
  - name: integration
    description: >
      A plan to be used verifying integration.
  - name: acceptance
    description: >
      A plan to be used verifying acceptance.
  - name: system
    description: >
      A plan to be used verifying system.
  - name: regression
    description: >
      A plan to be used verifying regression.
```

To run with above test_config.yaml file, only default_platforms with given test level test cases will run.

Linux

```bash
scripts/twister --test-config=<path to>/test_config.yaml
-T tests --level="smoke"
```

Running in Tests in Random Order

Enable ZTEST framework's CONFIG_ZTEST_SHUFFLE config option to run your tests in random order. This can be beneficial for identifying dependencies between test cases. For native_sim plat-
forms, you can provide the seed to the random number generator by providing \(-\text{seed}=\text{value}\) as an argument to twister. See \textit{Shuffling Test Sequence} for more details.

**Robot Framework Tests**

Zephyr supports \textit{Robot Framework} as one of solutions for automated testing.

Robot files allow you to express interactive test scenarios in human-readable text format and execute them in simulation or against hardware. At this moment Zephyr integration supports running Robot tests in the \textit{Renode} simulation framework.

To execute a Robot test suite with twister, run the following command:

\textbf{Linux}

```
./scripts/twister --platform hifive1 --test samples/subsys/shell/shell_module/sample.\rightarrow shell.shell_module.robot
```

\textbf{Windows}

```
python ./scripts\twister --platform hifive1 --test samples/subsys/shell/shell_module/sample.\rightarrow shell.shell_module.robot
```

It's also possible to run it by \textit{west} directly, with:

```
$ \text{ROBOT\_FILES=shell}\_module.robot \text{west build -p -b hifive1 -s samples/subsys/shell/shell_\rightarrow module -t run_renode_test}
```

\textbf{Writing Robot tests} For the list of keywords provided by the Robot Framework itself, refer to the official Robot documentation.

Information on writing and running Robot Framework tests in Renode can be found in the testing section of Renode documentation. It provides a list of the most commonly used keywords together with links to the source code where those are defined.

It's possible to extend the framework by adding new keywords expressed directly in Robot test suite files, as an external Python library or, like Renode does it, dynamically via XML-RPC. For details see the extending Robot Framework section in the official Robot documentation.

\textbf{Running a single testsuite} To run a single testsuite instead of a whole group of test you can run:

```
$ twister -p qemu_riscv32 -s tests/kernel/interrupt/arch.shared_interrupt
```

\textbf{2.12.3 Integration with pytest test framework}

\textit{Please mind that integration of twister with pytest is still work in progress. Not every platform type is supported in pytest (yet). If you find any issue with the integration or have an idea for an improvement, please, let us know about it and open a GitHub issue/enhancement.}

\textbf{Introduction}

Pytest is a python framework that \textit{“makes it easy to write small, readable tests, and can scale to support complex functional testing for applications and libraries”} (https://docs.pytest.org/en/7.3.x/). Python is known for its free libraries and ease of using it for scripting. In addition, pytest utilizes the concept of plugins and fixtures, increasing its expendability and reusability.
A pytest plugin `pytest-twister-harness` was introduced to provide an integration between pytest and twister, allowing Zephyr's community to utilize pytest functionality with keeping twister as the main framework.

**Integration with twister**

By default, there is nothing to be done to enable pytest support in twister. The plugin is developed as a part of Zephyr's tree. To enable install-less operation, twister first extends `PYTHONPATH` with path to this plugin, and then during pytest call, it appends the command with `-p pytest_harness.plugin` argument. If one prefers to use the installed version of the plugin, they must add `--allow-installed-plugin` flag to twister's call.

Pytest-based test suites are discovered the same way as other twister tests, i.e., by a presence of `testcase/sample.yaml`. Inside, a keyword `harness` tells twister how to handle a given test. In the case of `harness: pytest`, most of twister workflow (test suites discovery, parallelization, building and reporting) remains the same as for other harnesses. The change happens during the execution step. The below picture presents a simplified overview of the integration.

![Integration Diagram](image-url)
If harness: pytest is used, twister delegates the test execution to pytest, by calling it as a subprocess. Required parameters (such as build directory, device to be used, etc.) are passed through a CLI command. When pytest is done, twister looks for a pytest report (results.xml) and sets the test result accordingly.

**How to create a pytest test**

An example folder containing a pytest test, application source code and Twister configuration .yaml file can look like the following:

```
test_foo/
├─── pytest/
│ └─── test_foo.py
├─── src/
│ └─── main.c
├─── CMakeList.txt
├─── prj.conf
└─── testcase.yaml
```

An example of a pytest test is given at `samples/subsys/testsuite/pytest/shell/pytest/test_shell.py`. Using the configuration provided in the `testcase.yaml` file, Twister builds the application from `src` and then, if the .yaml file contains a `harness: pytest` entry, it calls pytest in a separate subprocess. A sample configuration file may look like this:

```
tests:
  some.foo.test:
    harness: pytest
    tags: foo
```

By default, pytest tries to look for tests in a pytest directory located next to a directory with binary sources. A keyword `pytest_root` placed under `harness_config` section in .yaml file can be used to point to other files, directories or subtests (more info [here](#)).

Pytest scans the given locations looking for tests, following its default discovery rules.

**Passing extra arguments** There are two ways for passing extra arguments to the called pytest subprocess:

1. From .yaml file, using `pytest_args` placed under `harness_config` section - more info [here](#).
2. Through Twister command line interface as `--pytest-args` argument. This can be particularly useful when one wants to select a specific testcase from a test suite. For instance, one can use a command:

   ```
   $./scripts/twister --platform native_sim -T samples/subsys/testsuite/pytest/shell \
   -s samples/subsys/testsuite/pytest/shell/sample.pytest.shell \
   --pytest-args='--k test_shell_print_version'
   ```

**Fixtures**

**dut** Give access to a DeviceAdapter type object, that represents Device Under Test. This fixture is the core of pytest harness plugin. It is required to launch DUT (initialize logging, flash device, connect serial etc). This fixture yields a device prepared according to the requested type (native, qemu, hardware, etc.). All types of devices share the same API. This allows for writing tests which are device-type-agnostic. Scope of this fixture is determined by the `pytest_dut_scope` keyword placed under `harness_config` section (more info [here](#)).
from twister_harness import DeviceAdapter

def test_sample(dut: DeviceAdapter):
    dut.readlines_until('Hello world')

def test_shell(shell: Shell):
    shell.exec_command('help')

class DeviceAdapter:

    def __init__(self, device_config: DeviceConfig):
        This class defines a common interface for all device types (hardware, simulator, QEMU)
        used in tests to gathering device output and send data to it.

        launch() -> None
        Start by closing previously running application (no effect if not needed). Then, flash
        and run test application. Finally, start an internal reader thread capturing an output
        from a device.

        connect() -> None
        Connect to device - allow for output gathering.
**readline** *(timeout: float | None) → str*
Read line from device output. If timeout is not provided, then use base_timeout.

**readlines** *(print_output: bool) → list[str]*
Read all available output lines produced by device from internal buffer.

**readlines_until** *(regex: str | None, num_of_lines: int | None, timeout: float | None) → list[str]*
Read available output lines produced by device from internal buffer until following conditions:
1. If regex is provided - read until regex regex is found in read line (or until timeout).
2. If num_of_lines is provided - read until number of read lines is equal to num_of_lines (or until timeout).
3. If none of above is provided - return immediately lines collected so far in internal buffer.
   If timeout is not provided, then use base_timeout.

**write** *(data: bytes) → None*
Write data bytes to device.

**disconnect** *(device: DeviceAdapter, prompt: str = 'uart:~$', timeout: float | None) → None*
Disconnect device - block output gathering.

**close** *(device: DeviceAdapter) → None*
Disconnect, close device and close reader thread.

### Shell

**class twister_harness.Shell** *(device: DeviceAdapter, prompt: str = 'uart:~$', timeout: float | None) → None*
Helper class that provides methods used to interact with shell application.

**exec_command** *(command: str, timeout: float | None) → list[str]*
Send shell command to a device and return response. Passed command is extended by double enter sings - first one to execute this command on a device, second one to receive next prompt what is a signal that execution was finished. Method returns print-out of the executed command.

**wait_for_prompt** *(timeout: float | None) → bool*
Send every 0.5 second “enter” command to the device until shell prompt statement will occur (return True) or timeout will be exceeded (return False).

### Examples of pytest tests in the Zephyr project

- pytest_shell
- MCUmgr tests - tests/boot/with_mcumgr
- LwM2M tests - tests/net/lib/lwm2m/interop
- GDB stub tests - tests/subsys/debug/gdbstub
FAQ

How to flash/run application only once per pytest session?

dut is a fixture responsible for flashing/running application. By default, its scope is set as function. This can be changed by adding to .yaml file pytest_dut_scope keyword placed under harness_config section:

```yaml
harness: pytest
harness_config:
  pytest_dut_scope: session
```

More info can be found here.

How to run only one particular test from a python file?

This can be achieved in several ways. In .yaml file it can be added using a pytest_root entry placed under harness_config with list of tests which should be run:

```yaml
harness: pytest
harness_config:
  pytest_root:
    - "pytest/test_shell.py::test_shell_print_help"
```

Particular tests can be also chosen by pytest -k option (more info about pytest keyword filter can be found here). It can be applied by adding -k filter in pytest_args in .yaml file:

```yaml
harness: pytest
harness_config:
  pytest_args: 
    - "-k test_shell_print_help"
```

or by adding it to Twister command overriding parameters from the .yaml file:

```
$ ./scripts/twister ... --pytest-args=''-k test_shell_print_help'
```

How to get information about used device type in test?

This can be taken from dut fixture (which represents DeviceAdapter object):

```python
device_type: str = dut.device_config.type
if device_type == 'hardware':
...
elif device_type == 'native':
...
```

How to rerun locally pytest tests without rebuilding application by Twister?

This can be achieved by running Twister once again with --test-only argument added to Twister command. Another way is running Twister with highest verbosity level (-vv) and then copy-pasting from logs command dedicated for spawning pytest (log started by Running pytest command: ...).

Is this possible to run pytest tests in parallel?
Basically pytest-harness-plugin wasn’t written with intention of running pytest tests in parallel. Especially those one dedicated for hardware. There was assumption that parallelization of tests is made by Twister, and it is responsible for managing available sources (jobs and hardwares). If anyone is interested in doing this for some reasons (for example via pytest-xdist plugin) they do so at their own risk.

Limitations

- Not every platform type is supported in the plugin (yet).

### 2.12.4 Generating coverage reports

With Zephyr, you can generate code coverage reports to analyze which parts of the code are covered by a given test or application.

You can do this in two ways:

- In a real embedded target or QEMU, using Zephyr’s gcov integration
- Directly in your host computer, by compiling your application targeting the POSIX architecture

**Test coverage reports in embedded devices or QEMU**

**Overview**  
GCC GCOV is a test coverage program used together with the GCC compiler to analyze and create test coverage reports for your programs, helping you create more efficient, faster running code and discovering untested code paths

In Zephyr, gcov collects coverage profiling data in RAM (and not to a file system) while your application is running. Support for gcov collection and reporting is limited by available RAM size and so is currently enabled only for QEMU emulation of embedded targets.

**Details**  
There are 2 parts to enable this feature. The first is to enable the coverage for the device and the second to enable in the test application. As explained earlier the code coverage with gcov is a function of RAM available. Therefore ensure that the device has enough RAM when enabling the coverage for it. For example a small device like frdm_k64f can run a simple test application but the more complex test cases which consume more RAM will crash when coverage is enabled.

To enable the device for coverage, select `CONFIG_HAS_COVERAGE_SUPPORT` in the Kconfig.board file.

To report the coverage for the particular test application set `CONFIG_COVERAGE`.

**Steps to generate code coverage reports**  
These steps will produce an HTML coverage report for a single application.

1. Build the code with `CONFIG_COVERAGE=y`.

   ```bash
   west build -b mps2_an385 -- -DCONFIG_COVERAGE=y -DCONFIG_COVERAGE_DUMP=y
   ```

2. Capture the emulator output into a log file. You may need to terminate the emulator with `Ctrl-A X` for this to complete after the coverage dump has been printed:

   ```bash
   ninja -Cbuild run | tee log.log
   ```

   or
3. Generate the gcov .gcda and .gcno files from the log file that was saved:

```bash
$ python3 scripts/gen_gcov_files.py -i log.log
```

4. Find the gcov binary placed in the SDK. You will need to pass the path to the gcov binary for the appropriate architecture when you later invoke gcovr:

```bash
$ find $ZEPHYR_SDK_INSTALL_DIR -iregex ".*gcov"
```

5. Create an output directory for the reports:

```bash
$ mkdir -p gcov_report
```

6. Run gcovr to get the reports:

```bash
$ gcovr -r $ZEPHYR_BASE . --html -o gcov_report/coverage.html --html-details --gcov-executable <gcov_path_in_SDK>
```

### Coverage reports using the POSIX architecture

When compiling for the POSIX architecture, you utilize your host native tooling to build a native executable which contains your application, the Zephyr OS, and some basic HW emulation. That means you can use the same tools you would while developing any other desktop application.

To build your application with gcc's gcov, simply set CONFIG_COVERAGE before compiling it. When you run your application, gcov coverage data will be dumped into the respective gcda and gcno files. You may postprocess these with your preferred tools. For example:

```bash
west build -b native_sim samples/hello_world --DCONFIG_COVERAGE=y
```

```bash
$ /build/zephyr/zephyr.exe
# Press Ctrl+C to exit
lcov --capture --directory ./ --output-file lcov.info -q --rc lcov_branch_coverage=1
genhtml lcov.info --output-directory lcov_html -q --ignore-errors source --branch-coverage --highlight --legend
```

**Note:** You need a recent version of lcov (at least 1.14) with support for intermediate text format. Such packages exist in recent Linux distributions.

Alternatively, you can use gcovr (at least version 4.2).

### Coverage reports using Twister

Zephyr's **twister script** can automatically generate a coverage report from the tests which were executed. You just need to invoke it with the --coverage command line option.

For example, you may invoke:

```bash
$ twister --coverage -p qemu_x86 -T tests/kernel
```

or:
$ twister --coverage -p native_sim -T tests/bluetooth

which will produce twister-out/coverage/index.html report as well as the coverage data collected by gcovr tool in twister-out/coverage.json.

Other reports might be chosen with --coverage-tool and --coverage-formats command line options.

The process differs for unit tests, which are built with the host toolchain and require a different board:

$ twister --coverage -p unit_testing -T tests/unit

which produces a report in the same location as non-unit testing.

Using different toolchains Twister looks at the environment variable ZEPHYR_TOOLCHAIN_VARIANT to check which gcov tool to use by default. The following are used as the default for the Twister --gcov-tool argument default:

<table>
<thead>
<tr>
<th>Toolchain</th>
<th>--gcov-tool value</th>
</tr>
</thead>
<tbody>
<tr>
<td>host</td>
<td>gcov</td>
</tr>
<tr>
<td>llvm</td>
<td>llvm-cov gcov</td>
</tr>
<tr>
<td>zephyr</td>
<td>gcov</td>
</tr>
</tbody>
</table>

2.12.5 BabbleSim

BabbleSim and Zephyr

In the Zephyr project we use the BabbleSim simulator to test some of the Zephyr radio protocols, including the BLE stack, 802.15.4, and some of the networking stack.

BabbleSim is a physical layer simulator, which in combination with the Zephyr bsim boards can be used to simulate a network of BLE and 15.4 devices. When we build Zephyr targeting a bsim board we produce a Linux executable, which includes the application, Zephyr OS, and models of the HW.

When there is radio activity, this Linux executable will connect to the BabbleSim Phy simulation to simulate the radio channel.

In the BabbleSim documentation you can find more information on how to get and build the simulator. In the nrf52_bsim and nrf5340bsim boards documentation you can find more information about how to build Zephyr targeting these particular boards, and a few examples.

Types of tests

Tests without radio activity: bsim tests with twister The bsim boards can be used without radio activity, and in that case, it is not necessary to connect them to a physical layer simulation. Thanks to this, these target boards can be used just like native_sim with twister, to run all standard Zephyr twister tests, but with models of a real SOC HW, and their drivers.

Tests with radio activity When there is radio activity, BabbleSim tests require at the very least a physical layer simulation running, and most, more than 1 simulated device. Due to this, these tests are not build and run with twister, but with a dedicated set of tests scripts.

These tests are kept in the tests/bsim/ folder. There you can find a README with more information about how to build and run them, as well as the convention they follow.
There are two main sets of tests of these type:

- **Self checking embedded application/tests**: In which some of the simulated devices applications are built with some checks which decide if the test is passing or failing. These embedded applications tests use the bs_tests system to report the pass or failure, and in many cases to build several tests into the same binary.

- **Test using the EDTT tool**: in which a EDTT (python) test controls the embedded applications over an RPC mechanism, and decides if the test passes or not. Today these tests include a very significant subset of the BT qualification test suite.

More information about how different tests types relate to BabbleSim and the bsim boards can be found in the bsim boards tests section.

### Test coverage and BabbleSim

As the nrf52_bsim and nrf5340bsim boards are based on the POSIX architecture, you can easily collect test coverage information.

You can use the script `tests/bsim/generate_coverage_report.sh` to generate an html coverage report from tests.

Check the page on coverage generation for more info.

### 2.12.6 ZTest Deprecated APIs

Ztest is currently being migrated to a new API, this documentation provides information about the deprecated APIs which will eventually be removed. See Test Framework for the new API. Similarly, ZTest's mocking framework is also deprecated (see Mocking via FFF).

### Quick start - Unit testing

Ztest can be used for unit testing. This means that rather than including the entire Zephyr OS for testing a single function, you can focus the testing efforts into the specific module in question. This will speed up testing since only the module will have to be compiled in, and the tested functions will be called directly.

Since you won’t be including basic kernel data structures that most code depends on, you have to provide function stubs in the test. Ztest provides some helpers for mocking functions, as demonstrated below.

In a unit test, mock objects can simulate the behavior of complex real objects and are used to decide whether a test failed or passed by verifying whether an interaction with an object occurred, and if required, to assert the order of that interaction.

**Best practices for declaring the test suite**  
*twister* and other validation tools need to obtain the list of subcases that a Zephyr ztest test image will expose.

### Rationale

This all is for the purpose of traceability. It's not enough to have only a semaphore test project. We also need to show that we have testpoints for all APIs and functionality, and we trace back to documentation of the API, and functional requirements.

The idea is that test reports show results for every sub-testcase as passed, failed, blocked, or skipped. Reporting on only the high-level test project level, particularly when tests do too many things, is too vague.
There exist two alternatives to writing tests. The first, and more verbose, approach is to directly declare and run the test suites. Here is a generic template for a test showing the expected use of \texttt{ztest_test_suite()}:

```
#include <zephyr/ztest.h>
extern void test_sometest1(void);
extern void test_sometest2(void);
 ifndef CONFIG_WHATEVER /* Conditionally skip test_sometest3 */
 void test_sometest3(void)
 { 
   ztest_test_skip();
 }
#else extern void test_sometest3(void);
#endif
extern void test_sometest4(void);
...

void test_main(void)
{
  ztest_test_suite(common,
   ztest_unit_test(test_sometest1),
   ztest_unit_test(test_sometest2),
   ztest_unit_test(test_sometest3),
   ztest_unit_test(test_sometest4)
 );
 ztest_run_test_suite(common);
}
```

Alternatively, it is possible to split tests across multiple files using \texttt{ztest_register_test_suite()} which bypasses the need for \texttt{extern}:

```
#include <zephyr/ztest.h>

void test_sometest1(void) {
  zassert_true(1, "true");
}

ztest_register_test_suite(common, NULL,
   ztest_unit_test(test_sometest1)) ;
```

The above sample simply registers the test suite and uses a NULL pragma function (more on that later). It is important to note that the test suite isn't directly run in this file. Instead two alternatives exist for running the suite. First, if to do nothing. A default \texttt{test_main} function is provided by ztest. This is the preferred approach if the test doesn’t involve a state and doesn’t require use of the pragma.

In cases of an integration test it is possible that some general state needs to be set between test suites. This can be thought of as a state diagram in which \texttt{test_main} simply goes through various actions that modify the board's state and different test suites need to run. This is achieved in the following:

```
#include <zephyr/ztest.h>

struct state {
   bool is_hibernating;
   bool is_usb_connected;
}

static bool pragma_always(const void *state)
```


```c
{
    return true;
}

static bool pragma_not_hibernating_not_connected(const void *s)
{
    struct state *state = s;
    return !(state->is_hibernating && !state->is_usb_connected);
}

static bool pragma_usb_connected(const void *s)
{
    return ((struct state *)s)->is_usb_connected;
}

ztest_register_test_suite(baseline, pragma_always,
                       ztest_unit_test(test_case0));
ztest_register_test_suite(before_usb, pragma_not_hibernating_not_connected,
                       ztest_unit_test(test_case1),
                       ztest_unit_test(test_case2));
ztest_register_test_suite(with_usb, pragma_usb_connected,
                       ztest_unit_test(test_case3),
                       ztest_unit_test(test_case4));

void test_main(void)
{
    struct state state;

    /* Should run 'baseline' test suite only. */
    ztest_run_registered_test_suites(&state);

    /* Simulate power on and update state. */
    emulate_power_on();
    /* Should run 'baseline' and 'before_usb' test suites. */
    ztest_run_registered_test_suites(&state);

    /* Simulate plugging in a USB device. */
    emulate_plugging_in_usb();
    /* Should run 'baseline' and 'with_usb' test suites. */
    ztest_run_registered_test_suites(&state);

    /* Verify that all the registered test suites actually ran. */
    ztest_verify_all_registered_test_suites_ran();
}
```

For `twister` to parse source files and create a list of subcases, the declarations of `ztest_test_suite()` and `ztest_register_test_suite()` must follow a few rules:

- one declaration per line
- conditional execution by using `ztest_test_skip()`

What to avoid:

- packing multiple testcases in one source file

```c
void test_main(void)
{
    #ifdef TEST_feature1
    ztest_test_suite(feature1,
                      ztest_unit_test(test_1a),
                      ztest_unit_test(test_1b),
```

(continues on next page)
• Do not use #if

```c
ztest_test_suite(common,
    ztest_unit_test(test_sometest1),
    ztest_unit_test(test_sometest2),
    #ifdef CONFIG_WHATEVER
    ztest_unit_test(test_sometest3),
    #endif
    ztest_unit_test(test_sometest4),
    ...
```

• Do not add comments on lines with a call to ztest_unit_test():

```c
ztest_test_suite(common,
    ztest_unit_test(test_sometest1),
    ztest_unit_test(test_sometest2) /* will fail */,
    /* will fail! */
    ztest_unit_test(test_sometest3),
    ztest_unit_test(test_sometest4),
    ...
```

• Do not define multiple definitions of unit / user unit test case per line

```c
ztest_test_suite(common,
    ztest_unit_test(test_sometest1),
    ztest_unit_test(test_sometest2),
    ztest_unit_test(test_sometest3),
    ztest_unit_test(test_sometest4),
    ...
```

Other questions:

• Why not pre-scan with CPP and then parse? or post scan the ELF file?
  If C pre-processing or building fails because of any issue, then we won't be able to tell the subcases.

• Why not declare them in the YAML testcase description?
  A separate testcase description file would be harder to maintain than just keeping the information in the test source files themselves – only one file to update when changes are made eliminates duplication.

**Mocking**

These functions allow abstracting callbacks and related functions and controlling them from specific tests. You can enable the mocking framework by setting CONFIG_ZTEST_MOCKING to “y” in the configuration file of the test. The amount of concurrent return values and expected parameters is limited by CONFIG_ZTEST_PARAMETER_COUNT.
Here is an example for configuring the function `expect_two_parameters` to expect the values `a=2` and `b=3`, and telling `returns_int` to return `5`:

```c
#include <zephyr/ztest.h>

static void expect_two_parameters(int a, int b)
{
    ztest_check_expected_value(a);
    ztest_check_expected_value(b);
}

static void parameter_tests(void)
{
    ztest_expect_value(expect_two_parameters, a, 2);
    ztest_expect_value(expect_two_parameters, b, 3);
    expect_two_parameters(2, 3);
}

static int returns_int(void)
{
    return ztest_get_return_value();
}

static void return_value_tests(void)
{
    ztest_returns_value(returns_int, 5);
    zassert_equal(returns_int(), 5, NULL);
}

void test_main(void)
{
    ztest_test_suite(mock_framework_tests, 
        ztest_unit_test(parameter_test), 
        ztest_unit_test(return_value_test)
    );
    ztest_run_test_suite(mock_framework_tests);
}
```

**group ztest_mock**

This module provides simple mocking functions for unit testing.
These need CONFIG_ZTEST_MOCKING=y.

**Defines**

*ztest_expect_value* (func, param, value)

Tell function `func` to expect the value `value` for `param`.
When using `ztest_check_expected_value()`, tell that the value of `param` should be `value`.
The value will internally be stored as an `uintptr_t`.

**Parameters**

- `func` – Function in question
- `param` – Parameter for which the value should be set
- `value` – Value for `param`

*ztest_check_expected_value* (param)

If `param` doesn’t match the value set by `ztest_expect_value()`, fail the test.
This will first check that does \texttt{param} have a value to be expected, and then checks whether the value of the parameter is equal to the expected value. If either of these checks fail, the current test will fail. This must be called from the called function.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{param} – Parameter to check
\end{itemize}

\textbf{ztest\_expect\_data(func, param, data)}

Tell function \texttt{func} to expect the data \texttt{data} for \texttt{param}.

When using \texttt{ztest\_check\_expected\_data()}, the data pointed to by \texttt{param} should be same \texttt{data} in this function. Only data pointer is stored by this function, so it must still be valid when \texttt{ztest\_check\_expected\_data} is called.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{func} – Function in question
  \item \texttt{param} – Parameter for which the data should be set
  \item \texttt{data} – pointer for the data for parameter \texttt{param}
\end{itemize}

\textbf{ztest\_check\_expected\_data(param, length)}

If data pointed by \texttt{param} don't match the data set by \texttt{ztest\_expect\_data()}, fail the test.

This will first check that \texttt{param} is expected to be null or non-null and then check whether the data pointed by parameter is equal to expected data. If either of these checks fail, the current test will fail. This must be called from the called function.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{param} – Parameter to check
  \item \texttt{length} – Length of the data to compare
\end{itemize}

\textbf{ztest\_return\_data(func, param, data)}

Tell function \texttt{func} to return the data \texttt{data} for \texttt{param}.

When using \texttt{ztest\_return\_data()}, the data pointed to by \texttt{param} should be same \texttt{data} in this function. Only data pointer is stored by this function, so it must still be valid when \texttt{ztest\_copy\_return\_data} is called.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{func} – Function in question
  \item \texttt{param} – Parameter for which the data should be set
  \item \texttt{data} – pointer for the data for parameter \texttt{param}
\end{itemize}

\textbf{ztest\_copy\_return\_data(param, length)}

Copy the data set by \texttt{ztest\_return\_data} to the memory pointed by \texttt{param}.

This will first check that \texttt{param} is not null and then copy the data. This must be called from the called function.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{param} – Parameter to return data for
  \item \texttt{length} – Length of the data to return
\end{itemize}

\textbf{ztest\_returns\_value(func, value)}

Tell \texttt{func} that it should return \texttt{value}.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{func} – Function that should return \texttt{value}
  \item \texttt{value} – Value to return from \texttt{func}
\end{itemize}
ztest_get_return_value()

Get the return value for current function.

The return value must have been set previously with ztest_returns_value(). If no return value exists, the current test will fail.

**Returns**
The value the current function should return

ztest_get_return_value_ptr()

Get the return value as a pointer for current function.

The return value must have been set previously with ztest_returns_value(). If no return value exists, the current test will fail.

**Returns**
The value the current function should return as a void *

## 2.13 Static Code Analysis (SCA)

Support for static code analysis tools in Zephyr is possible through CMake.

The build setting ZEPHYR_SCA_VARIANT can be used to specify the SCA tool to use. ZEPHYR_SCA_VARIANT is also supported as environment variable.

Use -DZEPHYR_SCA_VARIANT=<tool>, for example -DZEPHYR_SCA_VARIANT=sparse to enable the static analysis tool sparse.

### 2.13.1 SCA Tool infrastructure

Support for an SCA tool is implemented in a file: sca.cmake file. The file: sca.cmake must be placed under file: `<SCA_ROOT>/cmake/sca/<tool>/sca.cmake`. Zephyr itself is always added as an SCA_ROOT but the build system offers the possibility to add additional folders to the SCA_ROOT setting.

You can provide support for out of tree SCA tools by creating the following structure:

```
<scram_root>/
  cmake/
  
  sca/
  
  VARIANT <tool>/
  
  sca.cmake # CMake code that configures the tool to be used with Zephyr
```

To add foo under /path/to/my_tools/cmake/sca create the following structure:

```
/path/to/my_tools/
  cmake/
  
  sca/
  
  foo/
  
  sca.cmake
```

To use foo as SCA tool you must then specify -DZEPHYR_SCA_VARIANT=foo.

Remember to add /path/to/my_tools to SCA_ROOT.

SCA_TOOL can be set as a regular CMake setting using -DSCA_ROOT=<scram_root>, or added by a Zephyr module in its module.yml file, see Zephyr Modules - Build settings.
2.13.2 Native SCA Tool support

The following is a list of SCA tools natively supported by Zephyr build system.

CodeChecker support

CodeChecker is a static analysis infrastructure. It executes analysis tools available on the build system, such as Clang-Tidy, Clang Static Analyzer and Cppcheck. Refer to the analyzer’s websites for installation instructions.

Installing CodeChecker

CodeChecker itself is a python package available on pypi.

```
pip install codechecker
```

Running with CodeChecker

To run CodeChecker, `west build` should be called with a `-DZEPHYR_SCA_VARIANT=codechecker` parameter, e.g.

```
west build -b mimxrt1064_evk samples/basic/blinky --DZEPHYR_SCA_VARIANT=codechecker
```

Configuring CodeChecker

To configure CodeChecker or analyzers used, arguments can be passed using the CODECHECKER_ANALYZE_OPTS parameter, e.g.

```
west build -b mimxrt1064_evk samples/basic/blinky --DZEPHYR_SCA_VARIANT=codechecker
-DCODECHECKER_ANALYZE_OPTS="--config;$CODECHECKER_CONFIG_FILE;--timeout;60"
```

Storing CodeChecker results

If a CodeChecker server is active the results can be uploaded and stored for tracking purposes. Storing is done using the optional CODECHECKER_STORE=y or CODECHECKER_STORE_OPTS="arg;list" parameters, e.g.

```
west build -b mimxrt1064_evk samples/basic/blinky --DZEPHYR_SCA_VARIANT=codechecker
-DCODECHECKER_STORE_OPTS="--name;build;--url=localhost:8001/Default"
```

Note: If `--name` isn’t passed to either CODECHECKER_ANALYZE_OPTS or CODECHECKER_STORE_OPTS, the default zephyr is used.

Exporting CodeChecker reports

Optional reports can be generated using the CodeChecker results, when passing a `-DCODECHECKER_EXPORT=<type>` parameter. Allowed types are: html, json, codeclimate, gerrit, baseline. Multiple types can be passed as comma-separated arguments.

Optional parser configuration arguments can be passed using the CODECHECKERPARSE_OPTS parameter, e.g.

```
west build -b mimxrt1064_evk samples/basic/blinky --DZEPHYR_SCA_VARIANT=codechecker
-DCODECHECKER_EXPORT=html,json -DCODECHECKERPARSE_OPTS="--trim-path-prefix;$PWD"
```
Sparse support

Sparse is a static code analysis tool. Apart from performing common code analysis tasks it also supports an address_space attribute, which allows introduction of distinct address spaces in C code with subsequent verification that pointers to different address spaces do not get confused. Additionally it supports a force attribute which should be used to cast pointers between different address spaces. At the moment Zephyr introduces a single custom address space __cache used to identify pointers from the cached address range on the Xtensa architecture. This helps identify cases where cached and uncached addresses are confused.

Running with sparse  To run a sparse verification build west build should be called with a -DZEPHYR_SCA_VARIANT=sparse parameter, e.g.

```
west build -d hello -b intel_adsp_cavs25 zephyr/samples/hello_world -- -DZEPHYR_SCA_ 
-VARIANT=sparse
```

GCC static analysis support

Static analysis was introduced in GCC 10 and it is enabled with the option -fanalyzer. This option performs a much more expensive and thorough analysis of the code than traditional warnings.

Run GCC static analysis  To run GCC static analysis, west build should be called with a -DZEPHYR_SCA_VARIANT=gcc parameter, e.g.

```
wes t build -b qemu_x86 samples/userspace/hello_world_user -- -DZEPHYR_SCA_VARIANT=gcc
```

Parasoft C/C++test support

Parasoft C/C++test is a software testing and static analysis tool for C and C++. It is a commercial software and you must acquire a commercial license to use it.

Documentation of C/C++test can be found at https://docs.parasoft.com/. Please refer to the documentation for how to use it.

Generating Build Data Files  To use C/C++test, cpptestscan must be found in your PATH environment variable. And west build should be called with a -DZEPHYR_SCA_VARIANT=cpptest parameter, e.g.

```
wes t build -b qemu_cortex_m3 zephyr/samples/hello_world -- -DZEPHYR_SCA_VARIANT=cpptest
```

A .bdf file will be generated as build/sca/cpptest/cpptestscan.bdf.

Generating a report file  Please refer to Parasoft C/C++test documentation for more details. To import and generate a report file, something like the following should work.

```
cpptestcli -data out -localsettings local.conf -bdf build/sca/cpptest/cpptestscan.bdf -
-config "builtin://Recommended Rules" -report out/report
```

You might need to set bdf.import.c.compiler.exec, bdf.import.cpp.compiler.exec, and bdf. import.linker.exec to the toolchain west build used.
2.14 Toolchains

Guides on how to set up toolchains for Zephyr development.

2.14.1 Zephyr SDK

The Zephyr Software Development Kit (SDK) contains toolchains for each of Zephyr’s supported architectures. It also includes additional host tools, such as custom QEMU and OpenOCD.

Use of the Zephyr SDK is highly recommended and may even be required under certain conditions (for example, running tests in QEMU for some architectures).

Supported architectures

The Zephyr SDK supports the following target architectures:

- ARC (32-bit and 64-bit; ARCv1, ARCv2, ARCv3)
- ARM (32-bit and 64-bit; ARMv6, ARMv7, ARMv8; A/R/M Profiles)
- MIPS (32-bit and 64-bit)
- Nios II
- RISC-V (32-bit and 64-bit; RV32I, RV32E, RV64I)
- x86 (32-bit and 64-bit)
- Xtensa

Installation bundle and variables

The Zephyr SDK bundle supports all major operating systems (Linux, macOS and Windows) and is delivered as a compressed file. The installation consists of extracting the file and running the included setup script. Additional OS-specific instructions are described in the sections below.

If no toolchain is selected, the build system looks for Zephyr SDK and uses the toolchain from there. You can enforce this by setting the environment variable `ZEPHYR_TOOLCHAIN_VARIANT` to `zephyr`.

If you install the Zephyr SDK outside any of the default locations (listed in the operating system specific instructions below) and you want automatic discovery of the Zephyr SDK, then you must register the Zephyr SDK in the CMake package registry by running the setup script. If you decide not to register the Zephyr SDK in the CMake registry, then the `ZEPHYR_SDK_INSTALL_DIR` can be used to point to the Zephyr SDK installation directory.

You can also set `ZEPHYR_SDK_INSTALL_DIR` to point to a directory containing multiple Zephyr SDKs, allowing for automatic toolchain selection. For example, you can set `ZEPHYR_SDK_INSTALL_DIR` to `/company/tools`, where the `company/tools` folder contains the following subfolders:

- `/company/tools/zephyr-sdk-0.13.2`
- `/company/tools/zephyr-sdk-a.b.c`
- `/company/tools/zephyr-sdk-x.y.z`

This allows the Zephyr build system to choose the correct version of the SDK, while allowing multiple Zephyr SDKs to be grouped together at a specific path.
Zephyr SDK version compatibility

In general, the Zephyr SDK version referenced in this page should be considered the recommended version for the corresponding Zephyr version.

For the full list of compatible Zephyr and Zephyr SDK versions, refer to the Zephyr SDK Version Compatibility Matrix.

Zephyr SDK installation

**Note:** You can change 0.16.5 to another version in the instructions below if needed; the Zephyr SDK Releases page contains all available SDK releases.

**Note:** If you want to uninstall the SDK, you may simply remove the directory where you installed it.

**Ubuntu**

1. Download and verify the Zephyr SDK bundle:

   ```
   cd ~
   wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/
   zephyr-sdk-0.16.5_linux-x86_64.tar.xz
   wget -O - https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/sha256.sum | shasum --check --ignore-missing
   ```

   If your host architecture is 64-bit ARM (for example, Raspberry Pi), replace x86_64 with aarch64 in order to download the 64-bit ARM Linux SDK.

2. Extract the Zephyr SDK bundle archive:

   ```
   tar xvf zephyr-sdk-0.16.5_linux-x86_64.tar.xz
   ```

   **Note:** It is recommended to extract the Zephyr SDK bundle at one of the following locations:
   - `$HOME`
   - `$HOME/.local`
   - `$HOME/.local/opt`
   - `$HOME/bin`
   - `/opt`
   - `/usr/local`

   The Zephyr SDK bundle archive contains the zephyr-sdk-<version> directory and, when extracted under $HOME, the resulting installation path will be $HOME/zephyr-sdk-<version>.

3. Run the Zephyr SDK bundle setup script:

   ```
   cd zephyr-sdk-0.16.5
   ./setup.sh
   ```

   **Note:** You only need to run the setup script once after extracting the Zephyr SDK bundle.
You must rerun the setup script if you relocate the Zephyr SDK bundle directory after the initial setup.

4. **Install udev rules**, which allow you to flash most Zephyr boards as a regular user:
   
   ```
sudo cp ~/zephyr-sdk-0.16.5/sysroots/x86_64-pokysdk-linux/usr/share/openocd/
   → contrib/60-openocd.rules /etc/udev/rules.d
   sudo udevadm control --reload
   ```

**macOS**

1. **Download and verify the Zephyr SDK bundle:**
   
   ```
cd ~
curl -L -o https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/zephyr-sdk-0.16.5_macos-x86_64.tar.xz
   curl -L https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/sha256.sum | shasum --check --ignore-missing
   ```
   
   If your host architecture is 64-bit ARM (Apple Silicon, also known as M1), replace `x86_64` with `aarch64` in order to download the 64-bit ARM macOS SDK.

2. **Extract the Zephyr SDK bundle archive:**
   
   ```
tar xvf zephyr-sdk-0.16.5_macos-x86_64.tar.xz
   ```

   **Note:** It is recommended to extract the Zephyr SDK bundle at one of the following locations:
   
   ```
   • $HOME
   • $HOME/.local
   • $HOME/.local/opt
   • $HOME/bin
   • /opt
   • /usr/local
   ```
   
   The Zephyr SDK bundle archive contains the `zephyr-sdk-<version>` directory and, when extracted under `$HOME`, the resulting installation path will be `$HOME/zephyr-sdk-<version>`.

3. **Run the Zephyr SDK bundle setup script:**
   
   ```
cd /home/zephyr-sdk-0.16.5
./setup.sh
   ```

   **Note:** You only need to run the setup script once after extracting the Zephyr SDK bundle. You must rerun the setup script if you relocate the Zephyr SDK bundle directory after the initial setup.

**Windows**

1. **Open a cmd.exe terminal window as a regular user**

2. **Download the Zephyr SDK bundle:**
   
   ```
cd %HOMEPATH%
wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.16.5/
   → zephyr-sdk-0.16.5_windows-x86_64.7z
   ```

3. **Extract the Zephyr SDK bundle archive:**
Zephyr Project Documentation, Release 3.6.0-rc3

7z x zephyr-sdk-0.16.5_windows-x86_64.7z

**Note:** It is recommended to extract the Zephyr SDK bundle at one of the following locations:

- `%HOMEPATH%`
- `%PROGRAMFILES%`

The Zephyr SDK bundle archive contains the `zephyr-sdk-<version>` directory and, when extracted under `%HOMEPATH%`, the resulting installation path will be `%HOMEPATH%\zephyr-sdk-<version>`.

4. Run the Zephyr SDK bundle setup script:
   ```
cd zephyr-sdk-0.16.5
setup.cmd
   ```

**Note:** You only need to run the setup script once after extracting the Zephyr SDK bundle. You must rerun the setup script if you relocate the Zephyr SDK bundle directory after the initial setup.

### 2.14.2 Arm Compiler 6

1. Download and install a development suite containing the Arm Compiler 6 for your operating system.

2. **Set these environment variables**:
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `armclang`.
   - Set `ARMCLANG_TOOLCHAIN_PATH` to the toolchain installation directory.

3. The Arm Compiler 6 needs the `ARMLMD_LICENSE_FILE` environment variable to point to your license file or server.

For example:

```plaintext
# Linux, macOS, license file:
export ARMLMD_LICENSE_FILE=/<path>/license_armds.dat
# Linux, macOS, license server:
export ARMLMD_LICENSE_FILE=8224@myserver

# Windows, license file:
set ARMLMD_LICENSE_FILE=c:\<path>\license_armds.dat
# Windows, license server:
set ARMLMD_LICENSE_FILE=8224@myserver
```

1. If the Arm Compiler 6 was installed as part of an Arm Development Studio, then you must set the `ARM_PRODUCT_DEF` to point to the product definition file: See also: Product and toolkit configuration. For example if the Arm Development Studio is installed in: `/opt/armds-2020-1` with a Gold license, then set `ARM_PRODUCT_DEF` to point to `/opt/armds-2020-1/gold.elmap`.

**Note:** The Arm Compiler 6 uses `armlink` for linking. This is incompatible with Zephyr's linker script template, which works with GNU ld. Zephyr's Arm Compiler 6 support Zephyr's CMake linker script generator, which supports generating scatter files. Basic scatter file support is in place, but there are still areas covered in ld templates which are not fully supported by the CMake linker script generator.

### 2.14. Toolchains
Some Zephyr subsystems or modules may also contain C or assembly code that relies on GNU intrinsics and have not yet been updated to work fully with armclang.

### 2.14.3 Cadence Tensilica Xtensa C/C++ Compiler (XCC)

1. Obtain Tensilica Software Development Toolkit targeting the specific SoC on hand. This usually contains two parts:
   - The Xtensa Xplorer which contains the necessary executables and libraries.
   - A SoC-specific add-on to be installed on top of Xtensa Xplorer.
     - This add-on allows the compiler to generate code for the SoC on hand.

2. Install Xtensa Xplorer and then the SoC add-on.
   - Follow the instruction from Cadence on how to install the SDK.
   - Depending on the SDK, there are two set of compilers:
     - GCC-based compiler: xt-xcc and its friends.
     - Clang-based compiler: xt-clang and its friends.

3. Make sure you have obtained a license to use the SDK, or has access to a remote licensing server.

4. **Set these environment variables:**
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `xcc` or `xt-clang`.
   - Set `XTENSA_TOOLCHAIN_PATH` to the toolchain installation directory.
   - Set `XTENSA_CORE` to the SoC ID where application is being targeting.
   - Set `TOOLCHAIN_VER` to the Xtensa SDK version.

5. For example, assuming the SDK is installed in `/opt/xtensa`, and using the SDK for application development on `intel_adsp_cavs15`, setup the environment using:

   ```
   # Linux
   export ZEPHYR_TOOLCHAIN_VARIANT=xcc
   export XTENSA_TOOLCHAIN_PATH=/opt/xtensa/XtDevTools/install/tools/
   export XTENSA_CORE=X6H3SUE_RI_2018_0
   export TOOLCHAIN_VER=RI-2018.0-linux
   ```

6. To use Clang-based compiler:
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `xt-clang`.
   - Note that the Clang-based compiler may contain an old LLVM bug which results in the following error:

     ```
     /tmp/file.s: Assembler messages:
     /tmp/file.s:28: Error: file number 1 already allocated
     clang-3.9: error: Xtensa-as command failed with exit code 1
     ```

     If this happens, set `XCC_NO_G_FLAG` to 1.
     - For example:

     ```
     # Linux
     export XCC_NO_G_FLAG=1
     ```
2.14.4 DesignWare ARC MetaWare Development Toolkit (MWDT)

1. You need to have ARC MWDT installed on your host.
2. You need to have Zephyr SDK installed on your host.

**Note:** A Zephyr SDK is used as a source of tools like device tree compiler (DTC), QEMU, etc... Even though ARC MWDT toolchain is used for Zephyr RTOS build, still the GNU preprocessor & GNU objcopy might be used for some steps like device tree preprocessing and .bin file generation. We used Zephyr SDK as a source of these ARC GNU tools as well.

3. *Set these environment variables:*
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `arcmwdt`.
   - Set `ARCMWDT_TOOLCHAIN_PATH` to the toolchain installation directory. MWDT installation provides `METAWARE_ROOT` so simply set `ARCMWDT_TOOLCHAIN_PATH` to `$METAWARE_ROOT/..` / (Linux) or `%METAWARE_ROOT%\..` (Windows).

   **Tip:** If you have only one ARC MWDT toolchain version installed on your machine you may skip setting `ARCMWDT_TOOLCHAIN_PATH` - it would be detected automatically.

4. To check that you have set these variables correctly in your current environment, follow these example shell sessions (the `ARCMWDT_TOOLCHAIN_PATH` values may be different on your system):

   ```bash
   # Linux:
   $ echo $ZEPHYR_TOOLCHAIN_VARIANT
   arcwmdt
   $ echo $ARCMWDT_TOOLCHAIN_PATH
   /home/you/ARC/MWDT_2023.03/
   
   # Windows:
   > echo %ZEPHYR_TOOLCHAIN_VARIANT%
   arcwmdt
   > echo %ARCMWDT_TOOLCHAIN_PATH%
   C:\ARC\MWDT_2023.03\ 
   ```

2.14.5 GNU Arm Embedded

1. Download and install a GNU Arm Embedded build for your operating system and extract it on your file system.

   **Note:** On Windows, we’ll assume for this guide that you install into the directory `C:\gnu_arm_embedded`. You can also choose the default installation path used by the ARM GCC installer, in which case you will need to adjust the path accordingly in the guide below.

   **Warning:** On macOS Catalina or later you might need to change a security policy for the toolchain to be able to run from the terminal.

2. *Set these environment variables:*
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `gnuarmemb`.
   - Set `GNUARMEMB_TOOLCHAIN_PATH` to the toolchain installation directory.
3. To check that you have set these variables correctly in your current environment, follow these example shell sessions (the GNUARMEMB_TOOLCHAIN_PATH values may be different on your system):

```bash
# Linux, macOS:
$ echo "$ZEPHYR_TOOLCHAIN_VARIANT" gnuarmemb
$ echo "$GNUARMEMB_TOOLCHAIN_PATH" /home/you/Downloads/gnu_arm_embedded

# Windows:
> echo %ZEPHYR_TOOLCHAIN_VARIANT% gnuarmemb
> echo %GNUARMEMB_TOOLCHAIN_PATH% C:\gnu_arm_embedded
```

**Warning:** On macOS, if you are having trouble with the suggested procedure, there is an unofficial package on brew that might help you. Run `brew install gcc-arm-embedded` and configure the variables

- Set `ZEPHYR_TOOLCHAIN_VARIANT` to `gnuarmemb`.
- Set `GNUARMEMB_TOOLCHAIN_PATH` to the brew installation directory (something like `/usr/local`)

### 2.14.6 Intel oneAPI Toolkit

1. **Download** Intel oneAPI Base Toolkit

2. Assuming the toolkit is installed in `/opt/intel/oneApi`, set environment using:

```bash
# Linux, macOS:
export ONEAPI_TOOLCHAIN_PATH=/opt/intel/oneapi
source $ONEAPI_TOOLCHAIN_PATH/compiler/latest/env/vars.sh

# Windows:
> set ONEAPI_TOOLCHAIN_PATH=C:\Users\Intel\oneapi
```

To setup the complete oneApi environment, use:

```bash
source /opt/intel/oneapi/setvars.sh
```

The above will also change the python environment to the one used by the toolchain and might conflict with what Zephyr uses.

3. Set `ZEPHYR_TOOLCHAIN_VARIANT` to `oneApi`.

### 2.14.7 Crosstool-NG (Deprecated)

**Warning:** xtools toolchain variant is deprecated. The `cross-compile toolchain variant` should be used when using a custom toolchain built with Crosstool-NG.

You can build toolchains from source code using crosstool-NG.

1. Follow the steps on the crosstool-NG website to prepare your host.
2. Follow the Zephyr SDK with Crosstool NG instructions to build your toolchain. Repeat as necessary to build toolchains for multiple target architectures.

You will need to clone the sdk-ng repo and run the following command:

```bash
./go.sh <arch>
```

**Note:** Currently, only i586 and Arm toolchain builds are verified.

3. **Set these environment variables**:
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `xtools`.
   - Set `XT OOLS_TOOLCHAIN_PATH` to the toolchain build directory.

4. To check that you have set these variables correctly in your current environment, follow these example shell sessions (the `XT OOLS_TOOLCHAIN_PATH` values may be different on your system):

```bash
# Linux, macOS:
$ echo $ZEPHYR_TOOLCHAIN_VARIANT
xtools
$ echo $XT OOLS_TOOLCHAIN_PATH
/Volumes/CrossToolNGNew/build/output/
```

### 2.14.8 Host Toolchains

In some specific configurations, like when building for non-MCU x86 targets on a Linux host, you may be able to reuse the native development tools provided by your operating system.

To use your host gcc, set the `ZEPHYR_TOOLCHAIN_VARIANT` environment variable to `host`. To use clang, set `ZEPHYR_TOOLCHAIN_VARIANT` to `llvm`.

### 2.14.9 Other Cross Compilers

This toolchain variant is borrowed from the Linux kernel build system’s mechanism of using a `CROSS_COMPILE` environment variable to set up a GNU-based cross toolchain.

Examples of such “other cross compilers” are cross toolchains that your Linux distribution packaged, that you compiled on your own, or that you downloaded from the net. Unlike toolchains specifically listed in Toolchains, the Zephyr build system may not have been tested with them, and doesn’t officially support them. (Nonetheless, the toolchain set-up mechanism itself is supported.)

Follow these steps to use one of these toolchains.

1. Install a cross compiler suitable for your host and target systems.

   For example, you might install the `gcc-arm-none-eabi` package on Debian-based Linux systems, or `arm-none-eabi-newlib` on Fedora or Red Hat:

   ```bash
   # On Debian or Ubuntu
   sudo apt-get install gcc-arm-none-eabi
   # On Fedora or Red Hat
   sudo dnf install arm-none-eabi-newlib
   ```

2. **Set these environment variables**:
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `cross-compile`.  

**2.14. Toolchains**
• Set CROSS_COMPILE to the common path prefix which your toolchain's binaries have, e.g. the path to the directory containing the compiler binaries plus the target triplet and trailing dash.

3. To check that you have set these variables correctly in your current environment, follow these example shell sessions (the CROSS_COMPILE value may be different on your system):

```bash
# Linux, macOS:
$ echo "$ZEPHYR_TOOLCHAIN_VARIANT"
cross-compile
$ echo "$CROSS_COMPILE" /usr/bin/arm-none-eabi-
```

You can also set CROSS_COMPILE as a CMake variable.

When using this option, all of your toolchain binaries must reside in the same directory and have a common file name prefix. The CROSS_COMPILE variable is set to the directory concatenated with the file name prefix. In the Debian example above, the gcc-arm-none-eabi package installs binaries such as arm-none-eabi-gcc and arm-none-eabi-ld in directory /usr/bin/, so the common prefix is /usr/bin/arm-none-eabi- (including the trailing dash, -). If your toolchain is installed in /opt/mytoolchain/bin with binary names based on target triplet myarch-none-elf, CROSS_COMPILE would be set to /opt/mytoolchain/bin/myarch-none-elf-.

### 2.14.10 Custom CMake Toolchains

To use a custom toolchain defined in an external CMake file, **set these environment variables:**

- Set ZEPHYR_TOOLCHAIN_VARIANT to your toolchain's name
- Set TOOLCHAIN_ROOT to the path to the directory containing your toolchain's CMake configuration files.

Zephyr will then include the toolchain cmake files located in the TOOLCHAIN_ROOT directory:

- `cmake/toolchain/<toolchain name>/generic.cmake`: configures the toolchain for “generic” use, which mostly means running the C preprocessor on the generated Device-tree file.
- `cmake/toolchain/<toolchain name>/target.cmake`: configures the toolchain for “target” use, i.e. building Zephyr and your application's source code.

Here `<toolchain name>` is the same as the name provided in ZEPHYR_TOOLCHAIN_VARIANT. See the zephyr files `cmake/modules/FindHostTools.cmake` and `cmake/modules/FindTargetTools.cmake` for more details on what your generic.cmake and target.cmake files should contain.

You can also set ZEPHYR_TOOLCHAIN_VARIANT and TOOLCHAIN_ROOT as CMake variables when generating a build system for a Zephyr application, like so:

```bash
west build ... -- -DZEPHYR_TOOLCHAIN_VARIANT=... -DTOOLCHAIN_ROOT=...
```

```bash
cmake -DZEPHYR_TOOLCHAIN_VARIANT=... -DTOOLCHAIN_ROOT=...
```

If you do this, `-C <initial-cache> cmake option may useful. If you save your ZEPHYR_TOOLCHAIN_VARIANT, TOOLCHAIN_ROOT, and other settings in a file named my-toolchain.cmake, you can then invoke cmake as cmake -C my-toolchain.cmake ... to save typing.

Zephyr includes `include/toolchain.h` which again includes a toolchain specific header based on the compiler identifier, such as __llvm__ or __GNUC__. Some custom compilers identify themselves as the compiler on which they are based, for example llvm which then gets the toolchain/llvm.h included. This included file may though not be right for the custom toolchain. In order to solve this, and thus to get the include/other.h included instead, add the set(TOOLCHAIN_USE_CUSTOM 1) cmake line to the generic.cmake and/or target.cmake files located under <TOOLCHAIN_ROOT>/cmake/toolchain/<toolchain name>/.
When `TOOLCHAIN_USE_CUSTOM` is set, the `other.h` must be available out-of-tree and it must include the correct header for the custom toolchain. A good location for the `other.h` header file, would be a directory under the directory specified in `TOOLCHAIN_ROOT` as `include/toolchain`. To get the toolchain header included in zephyr's build, the `USERINCLUDE` can be set to point to the include directory, as shown here:

```
west build -- -DZEPHYR_TOOLCHAIN_VARIANT=... -DTOOLCHAIN_ROOT=... -DUSERINCLUDE=...
```

### 2.15 Tools and IDEs

#### 2.15.1 Coccinelle

Coccinelle is a tool for pattern matching and text transformation that has many uses in kernel development, including the application of complex, tree-wide patches and detection of problematic programming patterns.

**Note:** Linux and macOS development environments are supported, but not Windows.

#### Getting Coccinelle

The semantic patches included in the kernel use features and options which are provided by Coccinelle version 1.0.0-rc11 and above. Using earlier versions will fail as the option names used by the Coccinelle files and coccicheck have been updated.

Coccinelle is available through the package manager of many distributions, e.g. :

- Debian
- Fedora
- Ubuntu
- OpenSUSE
- Arch Linux
- NetBSD
- FreeBSD

Some distribution packages are obsolete and it is recommended to use the latest version released from the Coccinelle homepage at [http://coccinelle.lip6.fr/](http://coccinelle.lip6.fr/)

Or from Github at:

[https://github.com/coccinelle/coccinelle](https://github.com/coccinelle/coccinelle)

Once you have it, run the following commands:

```
./autogen
./configure
make
```

as a regular user, and install it with:

```
sudo make install
```

More detailed installation instructions to build from source can be found at:

Supplemental documentation

For Semantic Patch Language (SmPL) grammar documentation refer to:
https://coccinelle.gitlabpages.inria.fr/website/documentation.html

Using Coccinelle on Zephyr

coccicheck checker is the front-end to the Coccinelle infrastructure and has various modes:
Four basic modes are defined: patch, report, context, and org. The mode to use is specified by setting --mode=<mode> or -m=<mode>.

- patch proposes a fix, when possible.
- report generates a list in the following format: file:line:column-column: message
- context highlights lines of interest and their context in a diff-like style. Lines of interest are indicated with -. 
- org generates a report in the Org mode format of Emacs.

Note that not all semantic patches implement all modes. For easy use of Coccinelle, the default mode is report.

Two other modes provide some common combinations of these modes.

- chain tries the previous modes in the order above until one succeeds.
- rep+ctxt runs successively the report mode and the context mode. It should be used with the C option (described later) which checks the code on a file basis.

Examples

To make a report for every semantic patch, run the following command:

```
./scripts/coccicheck --mode=report
```

To produce patches, run:

```
./scripts/coccicheck --mode=patch
```

The coccicheck target applies every semantic patch available in the sub-directories of scripts/coccinelle to the entire source code tree.

For each semantic patch, a commit message is proposed. It gives a description of the problem being checked by the semantic patch, and includes a reference to Coccinelle.

As any static code analyzer, Coccinelle produces false positives. Thus, reports must be carefully checked, and patches reviewed.

To enable verbose messages set --verbose=1 option, for example:

```
./scripts/coccicheck --mode=report --verbose=1
```

Coccinelle parallelization

By default, coccicheck tries to run as parallel as possible. To change the parallelism, set the --jobs=<number> option. For example, to run across 4 CPUs:

```
./scripts/coccicheck --mode=report --jobs=4
```
As of Coccinelle 1.0.2 Coccinelle uses Ocaml parmap for parallelization, if support for this is detected you will benefit from parmap parallelization.

When parmap is enabled coccicheck will enable dynamic load balancing by using --chunksize 1 argument, this ensures we keep feeding threads with work one by one, so that we avoid the situation where most work gets done by only a few threads. With dynamic load balancing, if a thread finishes early we keep feeding it more work.

When parmap is enabled, if an error occurs in Coccinelle, this error value is propagated back, the return value of the coccicheck command captures this return value.

### Using Coccinelle with a single semantic patch

The option --cocci can be used to check a single semantic patch. In that case, the variable must be initialized with the name of the semantic patch to apply.

For instance:

```
./scripts/coccicheck --mode=report --cocci=<example.cocci>
```

or:

```
./scripts/coccicheck --mode=report --cocci=./path/to/<example.cocci>
```

### Controlling which files are processed by Coccinelle

By default the entire source tree is checked.

To apply Coccinelle to a specific directory, pass the path of specific directory as an argument.

For example, to check drivers/usb/ one may write:

```
./scripts/coccicheck --mode=patch drivers/usb/
```

The report mode is the default. You can select another one with the --mode=<mode> option explained above.

### Debugging Coccinelle SmPL patches

Using coccicheck is best as it provides in the spatch command line include options matching the options used when we compile the kernel. You can learn what these options are by using verbose option, you could then manually run Coccinelle with debug options added.

Alternatively you can debug running Coccinelle against SmPL patches by asking for stderr to be redirected to stderr; by default stderr is redirected to /dev/null, if you’d like to capture stderr you can specify the --debug=file.err option to coccicheck. For instance:

```
rm -f cocci.err
./scripts/coccicheck --mode=patch --debug=cocci.err
cat cocci.err
```

Debugging support is only supported when using Coccinelle >= 1.0.2.

### Additional Flags

Additional flags can be passed to spatch through the SPFLAGS variable. This works as Coccinelle respects the last flags given to it when options are in conflict.
Coccinelle supports idutils as well but requires coccinelle >= 1.0.6. When no ID file is specified, coccinelle assumes your ID database file is in the file .id-utils.index on the top level of the kernel, coccinelle carries a script scripts/idutils_index.sh which creates the database with:

```
mkid -i C --output .id-utils.index
```

If you have another database filename you can also just symlink with this name.

```
./scripts/coccicheck --sp-flag="--use-idutils"
```

Alternatively you can specify the database filename explicitly, for instance:

```
./scripts/coccicheck --sp-flag="--use-idutils /full-path/to/ID"
```

Sometimes coccinelle doesn’t recognize or parse complex macro variables due to insufficient definition. Therefore, to make it parsable we explicitly provide the prototype of the complex macro using the `---macro-file-builtins <headerfile.h>` flag.

The `<headerfile.h>` should contain the complete prototype of the complex macro from which spatch engine can extract the type information required during transformation.

For example:

```
Z_SYSCALL_HANDLER
```

is not recognized by coccinelle. Therefore, we put its prototype in a header file, say for example `mymacros.h`.

```
$ cat mymacros.h
#define Z_SYSCALL_HANDLER int xxx
```

Now we pass the header file `mymacros.h` during transformation:

```
./scripts/coccicheck --sp-flag="---macro-file-builtins mymacros.h"
```

See `spatch --help` to learn more about spatch options.

Note that the `--use-glimpse` and `--use-idutils` options require external tools for indexing the code. None of them is thus active by default. However, by indexing the code with one of these tools, and according to the cocci file used, spatch could proceed the entire code base more quickly.

**SmPL patch specific options**

SmPL patches can have their own requirements for options passed to Coccinelle. SmPL patch specific options can be provided by providing them at the top of the SmPL patch, for instance:

```
// Options: --no-includes --include-headers
```

**Proposing new semantic patches**

New semantic patches can be proposed and submitted by kernel developers. For sake of clarity, they should be organized in the sub-directories of `scripts/coccinelle/`.

The cocci script should have the following properties:

- The script **must** have report mode.
- The first few lines should state the purpose of the script using /// comments. Usually, this message would be used as the commit log when proposing a patch based on the script.
Example

```c
/// Use ARRAY_SIZE instead of dividing sizeof array with sizeof an element
```

- A more detailed information about the script with exceptional cases or false positives (if any) can be listed using `//#` comments.

Example

```c
//# This makes an effort to find cases where ARRAY_SIZE can be used such as
//# where there is a division of sizeof the array by the sizeof its first
//# element or by any indexed element or the element type. It replaces the
//# division of the two sizeofs by ARRAY_SIZE.
```

- Confidence: It is a property defined to specify the accuracy level of the script. It can be either High, Moderate or Low depending upon the number of false positives observed.

Example

```c
// Confidence: High
```

- Virtual rules: These are required to support the various modes framed in the script. The virtual rule specified in the script should have the corresponding mode handling rule.

Example

```c
virtual context

@depends on context@

T T[] E;
@@

( *
* (sizeof(E)/sizeof(*E))
| *
* (sizeof(E)/sizeof(E[...]))
| *
* (sizeof(E)/sizeof(T))
)`
```

Detailed description of the report mode

Report generates a list in the following format:

```
file:line:column-column: message
```

Example  Running:

```
./scripts/coccicheck --mode=report --cocci=scripts/coccinelle/array_size.cocci
```

will execute the following part of the SmPL script:

```
<smpl>
@r depends on (org || report)@

T[] T E;
```

(continues on next page)
position p;
@@
( (sizeof(E)*p /sizeof(*E))
 | (sizeof(E)*p /sizeof(E[...]))
 | (sizeof(E)*p /sizeof(T))
 )

@script:python depends on report@
p << r.p;
@@
msg="WARNING: Use ARRAY_SIZE"
coccilib.report.print_report(p[0], msg)
</smpl>

This SmPL excerpt generates entries on the standard output, as illustrated below:

```
ext/hal/nxp/mcux/drivers/lpc/fsl_wwdt.c:66:49-50: WARNING: Use ARRAY_SIZE
ext/hal/nxp/mcux/drivers/lpc/fsl_ctimer.c:74:53-54: WARNING: Use ARRAY_SIZE
ext/hal/nxp/mcux/drivers/imx/fsl_dcp.c:944:45-46: WARNING: Use ARRAY_SIZE
```

**Detailed description of the patch mode**

When the patch mode is available, it proposes a fix for each problem identified.

**Example**  Running:

```
./scripts/coccicheck --mode=patch --cocci=scripts/coccinelle/misc/array_size.cocci
```

will execute the following part of the SmPL script:

```
<smpl>
@depends on patch@
type T;
T[] E;
@@
( - (sizeof(E)/sizeof(*E))
 + ARRAY_SIZE(E)
 | - (sizeof(E)/sizeof(E[...]))
 + ARRAY_SIZE(E)
 | - (sizeof(E)/sizeof(T))
 + ARRAY_SIZE(E)
 )
</smpl>
```

This SmPL excerpt generates patch hunks on the standard output, as illustrated below:

```
diff -u -p a/ext/lib/encoding/tinycbor/src/cborvalidation.c b/ext/lib/encoding/tinycbor/src/.../cborvalidation.c
```

(continues on next page)
--- a/ext/lib/encoding/tinycbor/src/cborvalidation.c
+++ b/ext/lib/encoding/tinycbor/src/cborvalidation.c
@@ -325,7 +325,7 @@ static inline CborError validate_number(
 static inline CborError validate_tag(CborValue *it, CborTag tag, int flags, int_
               recursionLeft)
 {
-    const size_t knownTagCount = sizeof(knownTagData) / sizeof(knownTagData[0]);
+    const size_t knownTagCount = ARRAY_SIZE(knownTagData);
        const struct KnownTagData *tagData = knownTagData;
        const struct KnownTagData * const knownTagDataEnd = knownTagData + knownTagCount;

Detailed description of the context mode

context highlights lines of interest and their context in a diff-like style.

Note: The diff-like output generated is NOT an applicable patch. The intent of the context mode is to highlight the important lines (annotated with minus, -) and gives some surrounding context lines around. This output can be used with the diff mode of Emacs to review the code.

Example Running:

./scripts/coccicheck --mode=context --cocciscripts/coccinelle/array_size.cocci

will execute the following part of the SmPL script:

@depends on context@
type T;
T[] E;
@@
(* (sizeof(E)/sizeof(*E))
 | (* (sizeof(E)/sizeof(E[...]))
 | (* (sizeof(E)/sizeof(T))
 )
</smpl>

This SmPL excerpt generates diff hunks on the standard output, as illustrated below:

diff -u -p ext/lib/encoding/tinycbor/src/cborvalidation.c /tmp/anything/ext/lib/encoding/
   tinycbor/src/cborvalidation.c
--- ext/lib/encoding/tinycbor/src/cborvalidation.c
+++ /tmp/anything/ext/lib/encoding/tinycbor/src/cborvalidation.c
@@ -325,7 +325,6 @@ static inline CborError validate_number(
 static inline CborError validate_tag(CborValue *it, CborTag tag, int flags, int_
               recursionLeft)
 {
-    const size_t knownTagCount = sizeof(knownTagData) / sizeof(knownTagData[0]);
+    const size_t knownTagCount = sizeof(knownTagData[0]);
        const struct KnownTagData *tagData = knownTagData;
        const struct KnownTagData * const knownTagDataEnd = knownTagData + knownTagCount;

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Detailed description of the org mode

org generates a report in the Org mode format of Emacs.

Example  Running:

```
./scripts/coccicheck --mode=org --cocci=scripts/coccinelle/misc/array_size.cocci
```

will execute the following part of the SmPL script:

```smpl
@r depends on (org || report)@
type T;
T[] E;
position p;
@@
( (sizeof(E)p /sizeof(*E))
 | (sizeof(E)p /sizeof(E[...])))
 | (sizeof(E)p /sizeof(T))
)
@script:python depends on org@
p << r.p;
@@
coccilib.org.print_todo(p[0], "WARNING should use ARRAY_SIZE")
</smpl>
```

This SmPL excerpt generates Org entries on the standard output, as illustrated below:

```
* TODO [[view:ext/lib/encoding/tinycbor/src/cborvalidation.c::face=ovl-→face1::linb=328::colb=52::cole=53][WARNING should use ARRAY_SIZE]]
```

Coccinelle Mailing List

Subscribe to the coccinelle mailing list:

- https://systeme.lip6.fr/mailman/listinfo/cocci

Archives:

- https://lore.kernel.org/cocci/
- https://systeme.lip6.fr/pipermail/cocci/

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Chapter 3

Kernel

3.1 Kernel Services

The Zephyr kernel lies at the heart of every Zephyr application. It provides a low footprint, high performance, multi-threaded execution environment with a rich set of available features. The rest of the Zephyr ecosystem, including device drivers, networking stack, and application-specific code, uses the kernel's features to create a complete application.

The configurable nature of the kernel allows you to incorporate only those features needed by your application, making it ideal for systems with limited amounts of memory (as little as 2 KB!) or with simple multi-threading requirements (such as a set of interrupt handlers and a single background task). Examples of such systems include: embedded sensor hubs, environmental sensors, simple LED wearable, and store inventory tags.

Applications requiring more memory (50 to 900 KB), multiple communication devices (like Wi-Fi and Bluetooth Low Energy), and complex multi-threading, can also be developed using the Zephyr kernel. Examples of such systems include: fitness wearables, smart watches, and IoT wireless gateways.

3.1.1 Scheduling, Interrupts, and Synchronization

These pages cover basic kernel services related to thread scheduling and synchronization.

Threads

Note: There is also limited support for using Operation without Threads.
This section describes kernel services for creating, scheduling, and deleting independently executable threads of instructions.

A thread is a kernel object that is used for application processing that is too lengthy or too complex to be performed by an ISR.

Any number of threads can be defined by an application (limited only by available RAM). Each thread is referenced by a thread id that is assigned when the thread is spawned.

A thread has the following key properties:

- A stack area, which is a region of memory used for the thread's stack. The size of the stack area can be tailored to conform to the actual needs of the thread's processing. Special macros exist to create and work with stack memory regions.
- A thread control block for private kernel bookkeeping of the thread's metadata. This is an instance of type k_thread.
- An entry point function, which is invoked when the thread is started. Up to 3 argument values can be passed to this function.
- A scheduling priority, which instructs the kernel's scheduler how to allocate CPU time to the thread. (See Scheduling.)
- A set of thread options, which allow the thread to receive special treatment by the kernel under specific circumstances. (See Thread Options.)
- A start delay, which specifies how long the kernel should wait before starting the thread.
- An execution mode, which can either be supervisor or user mode. By default, threads run in supervisor mode and allow access to privileged CPU instructions, the entire memory address space, and peripherals. User mode threads have a reduced set of privileges. This depends on the CONFIG_USERSPACE option. See User Mode.

Lifecycle

Thread Creation  A thread must be created before it can be used. The kernel initializes the thread control block as well as one end of the stack portion. The remainder of the thread's stack is typically left uninitialized.
Specifying a start delay of `K_NO_WAIT` instructs the kernel to start thread execution immediately. Alternatively, the kernel can be instructed to delay execution of the thread by specifying a timeout value – for example, to allow device hardware used by the thread to become available.

The kernel allows a delayed start to be canceled before the thread begins executing. A cancellation request has no effect if the thread has already started. A thread whose delayed start was successfully canceled must be re-spawned before it can be used.

**Thread Termination**  Once a thread is started it typically executes forever. However, a thread may synchronously end its execution by returning from its entry point function. This is known as **termination**.

A thread that terminates is responsible for releasing any shared resources it may own (such as mutexes and dynamically allocated memory) prior to returning, since the kernel does not reclaim them automatically.

In some cases a thread may want to sleep until another thread terminates. This can be accomplished with the `k_thread_join()` API. This will block the calling thread until either the timeout expires, the target thread self-exits, or the target thread aborts (either due to a `k_thread_abort()` call or triggering a fatal error).

Once a thread has terminated, the kernel guarantees that no use will be made of the thread struct. The memory of such a struct can then be re-used for any purpose, including spawning a new thread. Note that the thread must be fully terminated, which presents race conditions where a thread's own logic signals completion which is seen by another thread before the kernel processing is complete. Under normal circumstances, application code should use `k_thread_join()` or `k_thread_abort()` to synchronize on thread termination state and not rely on signaling from within application logic.

**Thread Aborting**  A thread may asynchronously end its execution by **aborting**. The kernel automatically aborts a thread if the thread triggers a fatal error condition, such as dereferencing a null pointer.

A thread can also be aborted by another thread (or by itself) by calling `k_thread_abort()`. However, it is typically preferable to signal a thread to terminate itself gracefully, rather than aborting it.

As with thread termination, the kernel does not reclaim shared resources owned by an aborted thread.

---

**Note:** The kernel does not currently make any claims regarding an application’s ability to respawn a thread that aborts.

---

**Thread Suspension**  A thread can be prevented from executing for an indefinite period of time if it becomes **suspended**. The function `k_thread_suspend()` can be used to suspend any thread, including the calling thread. Suspending a thread that is already suspended has no additional effect.

Once suspended, a thread cannot be scheduled until another thread calls `k_thread_resume()` to remove the suspension.

---

**Note:** A thread can prevent itself from executing for a specified period of time using `k_sleep()`. However, this is different from suspending a thread since a sleeping thread becomes executable automatically when the time limit is reached.
**Thread States**  A thread that has no factors that prevent its execution is deemed to be **ready**, and is eligible to be selected as the current thread.

A thread that has one or more factors that prevent its execution is deemed to be **unready**, and cannot be selected as the current thread.

The following factors make a thread unready:

- The thread has not been started.
- The thread is waiting for a kernel object to complete an operation. (For example, the thread is taking a semaphore that is unavailable.)
- The thread is waiting for a timeout to occur.
- The thread has been suspended.
- The thread has terminated or aborted.

**Thread Stack objects**  Every thread requires its own stack buffer for the CPU to push context. Depending on configuration, there are several constraints that must be met:

- There may need to be additional memory reserved for memory management structures
- If guard-based stack overflow detection is enabled, a small write-protected memory management region must immediately precede the stack buffer to catch overflows.
- If userspace is enabled, a separate fixed-size privilege elevation stack must be reserved to serve as a private kernel stack for handling system calls.
- If userspace is enabled, the thread's stack buffer must be appropriately sized and aligned such that a memory protection region may be programmed to exactly fit.

---

**Note:** Although the diagram above may appear to suggest that both **Ready** and **Running** are distinct thread states, that is not the correct interpretation. **Ready** is a thread state, and **Running** is a schedule state that only applies to **Ready** threads.
The alignment constraints can be quite restrictive, for example some MPUs require their regions to be of some power of two in size, and aligned to its own size.

Because of this, portable code can't simply pass an arbitrary character buffer to `k_thread_create()`. Special macros exist to instantiate stacks, prefixed with `K_KERNEL_STACK` and `K_THREAD_STACK`.

**Kernel-only Stacks**  If it is known that a thread will never run in user mode, or the stack is being used for special contexts like handling interrupts, it is best to define stacks using the `K_KERNEL_STACK` macros.

These stacks save memory because an MPU region will never need to be programmed to cover the stack buffer itself, and the kernel will not need to reserve additional room for the privilege elevation stack, or memory management data structures which only pertain to user mode threads.

Attempts from user mode to use stacks declared in this way will result in a fatal error for the caller.

If `CONFIG_USERSPACE` is not enabled, the set of `K_THREAD_STACK` macros have an identical effect to the `K_KERNEL_STACK` macros.

**Thread stacks**  If it is known that a stack will need to host user threads, or if this cannot be determined, define the stack with `K_THREAD_STACK` macros. This may use more memory but the stack object is suitable for hosting user threads.

If `CONFIG_USERSPACE` is not enabled, the set of `K_THREAD_STACK` macros have an identical effect to the `K_KERNEL_STACK` macros.

**Thread Priorities**  A thread's priority is an integer value, and can be either negative or non-negative. Numerically lower priorities takes precedence over numerically higher values. For example, the scheduler gives thread A of priority 4 higher priority over thread B of priority 7; likewise thread C of priority -2 has higher priority than both thread A and thread B.

The scheduler distinguishes between two classes of threads, based on each thread's priority.

- A *cooperative thread* has a negative priority value. Once it becomes the current thread, a cooperative thread remains the current thread until it performs an action that makes it unready.
- A *preemptible thread* has a non-negative priority value. Once it becomes the current thread, a preemptible thread may be supplanted at any time if a cooperative thread, or a preemptible thread of higher or equal priority, becomes ready.

A thread's initial priority value can be altered up or down after the thread has been started. Thus it is possible for a preemptible thread to become a cooperative thread, and vice versa, by changing its priority.

**Note:** The scheduler does not make heuristic decisions to re-prioritize threads. Thread priorities are set and changed only at the application's request.

The kernel supports a virtually unlimited number of thread priority levels. The configuration options `CONFIG_NUM_COOP_PRIORITIES` and `CONFIG_NUM_PREEMPT_PRIORITIES` specify the number of priority levels for each class of thread, resulting in the following usable priority ranges:

- cooperative threads: `-CONFIG_NUM_COOP_PRIORITIES` to `-1`
- preemptive threads: `0` to `(CONFIG_NUM_PREEMPT_PRIORITIES - 1)`
For example, configuring 5 cooperative priorities and 10 preemptive priorities results in the ranges -5 to -1 and 0 to 9, respectively.

**Meta-IRQ Priorities**  When enabled (see CONFIG_NUM_METAIRQ_PRIORITIES), there is a special subclass of cooperative priorities at the highest (numerically lowest) end of the priority space: meta-IRQ threads. These are scheduled according to their normal priority, but also have the special ability to preempt all other threads (and other meta-IRQ threads) at lower priorities, even if those threads are cooperative and/or have taken a scheduler lock. Meta-IRQ threads are still threads, however, and can still be interrupted by any hardware interrupt.

This behavior makes the act of unblocking a meta-IRQ thread (by any means, e.g. creating it, calling k_sem_give(), etc.) into the equivalent of a synchronous system call when done by a lower priority thread, or an ARM-like “pended IRQ” when done from true interrupt context. The intent is that this feature will be used to implement interrupt “bottom half” processing and/or “tasklet” features in driver subsystems. The thread, once woken, will be guaranteed to run before the current CPU returns into application code.

Unlike similar features in other OSes, meta-IRQ threads are true threads and run on their own stack (which must be allocated normally), not the per-CPU interrupt stack. Design work to enable the use of the IRQ stack on supported architectures is pending.

Note that because this breaks the promise made to cooperative threads by the Zephyr API (namely that the OS won’t schedule other thread until the current thread deliberately blocks), it should be used only with great care from application code. These are not simply very high priority threads and should not be used as such.

**Thread Options**  The kernel supports a small set of thread options that allow a thread to receive special treatment under specific circumstances. The set of options associated with a thread are specified when the thread is spawned.

A thread that does not require any thread option has an option value of zero. A thread that requires a thread option specifies it by name, using the | character as a separator if multiple options are needed (i.e. combine options using the bitwise OR operator).

The following thread options are supported.

**K_ESSENTIAL**
This option tags the thread as an essential thread. This instructs the kernel to treat the termination or aborting of the thread as a fatal system error.

By default, the thread is not considered to be an essential thread.

**K_SSE_REGS**
This x86-specific option indicate that the thread uses the CPU’s SSE registers. Also see K_FP_REGS.
By default, the kernel does not attempt to save and restore the contents of these registers when scheduling the thread.

**K_FP_REGS**
This option indicate that the thread uses the CPU's floating point registers. This instructs the kernel to take additional steps to save and restore the contents of these registers when scheduling the thread. (For more information see *Floating Point Services.*

By default, the kernel does not attempt to save and restore the contents of this register when scheduling the thread.

**K_USER**
If `CONFIG_USERSPACE` is enabled, this thread will be created in user mode and will have reduced privileges. See *User Mode.* Otherwise this flag does nothing.

**K_INHERIT_PERMS**
If `CONFIG_USERSPACE` is enabled, this thread will inherit all kernel object permissions that the parent thread had, except the parent thread object. See *User Mode.*

**Thread Custom Data**  Every thread has a 32-bit *custom data* area, accessible only by the thread itself, and may be used by the application for any purpose it chooses. The default custom data value for a thread is zero.

**Note:** Custom data support is not available to ISRs because they operate within a single shared kernel interrupt handling context.

By default, thread custom data support is disabled. The configuration option `CONFIG_THREAD_CUSTOM_DATA` can be used to enable support.

The `k_thread_custom_data_set()` and `k_thread_custom_data_get()` functions are used to write and read a thread's custom data, respectively. A thread can only access its own custom data, and not that of another thread.

The following code uses the custom data feature to record the number of times each thread calls a specific routine.

**Note:** Obviously, only a single routine can use this technique, since it monopolizes the use of the custom data feature.

```c
int call_tracking_routine(void)
{
    uint32_t call_count;

    if (k_is_in_isr()) {
        /* ignore any call made by an ISR */
    } else {
        call_count = (uint32_t)k_thread_custom_data_get();
        call_count++;
        k_thread_custom_data_set((void *)&call_count);
    }

    /* do rest of routine's processing */
    ...
}
```

Use thread custom data to allow a routine to access thread-specific information, by using the custom data as a pointer to a data structure owned by the thread.

3.1. Kernel Services
Implementation

Spawning a Thread  A thread is spawned by defining its stack area and its thread control block, and then calling `k_thread_create()`.

The stack area must be defined using `K_THREAD_STACK_DEFINE` or `K_KERNEL_STACK_DEFINE` to ensure it is properly set up in memory.

The size parameter for the stack must be one of three values:

- The original requested stack size passed to `K_THREAD_STACK` or `K_KERNEL_STACK` family of stack instantiation macros.
- For a stack object defined with the `K_THREAD_STACK` family of macros, the return value of `K_THREAD_STACK_SIZEOF()` for that object.
- For a stack object defined with the `K_KERNEL_STACK` family of macros, the return value of `K_KERNEL_STACK_SIZEOF()` for that object.

The thread spawning function returns its thread id, which can be used to reference the thread.

The following code spawns a thread that starts immediately.

```c
#define MY_STACK_SIZE 500
#define MY_PRIORITY 5

extern void my_entry_point(void *, void *, void *);

K_THREAD_STACK_DEFINE(my_stack_area, MY_STACK_SIZE);
struct k_thread my_thread_data;

k_tid_t my_tid = k_thread_create(&my_thread_data, my_stack_area,
    K_THREAD_STACK_SIZEOF(my_stack_area),
    my_entry_point,
    NULL, NULL, NULL,
    MY_PRIORITY, 0, K_NO_WAIT);
```

Alternatively, a thread can be declared at compile time by calling `K_THREAD_DEFINE`. Observe that the macro defines the stack area, control block, and thread id variables automatically.

The following code has the same effect as the code segment above.

```c
#define MY_STACK_SIZE 500
#define MY_PRIORITY 5

extern void my_entry_point(void *, void *, void *);

K_THREAD_DEFINE(my_tid, MY_STACK_SIZE,
    my_entry_point,
    NULL, NULL, NULL,
    MY_PRIORITY, 0, 0);
```

Note: The delay parameter to `k_thread_create()` is a `k_timeout_t` value, so `K_NO_WAIT` means to start the thread immediately. The corresponding parameter to `K_THREAD_DEFINE` is a duration in integral milliseconds, so the equivalent argument is 0.

User Mode Constraints  This section only applies if `CONFIG_USERSPACE` is enabled, and a user thread tries to create a new thread. The `k_thread_create()` API is still used, but there are additional constraints which must be met or the calling thread will be terminated:

- The calling thread must have permissions granted on both the child thread and stack parameters; both are tracked by the kernel as kernel objects.
• The child thread and stack objects must be in an uninitialized state, i.e. it is not currently running and the stack memory is unused.
• The stack size parameter passed in must be equal to or less than the bounds of the stack object when it was declared.
• The \texttt{K\_USER} option must be used, as user threads can only create other user threads.
• The \texttt{K\_ESSENTIAL} option must not be used, user threads may not be considered essential threads.
• The priority of the child thread must be a valid priority value, and equal to or lower than the parent thread.

\noindent \textbf{Dropping Permissions} \hspace{0.5em} If \texttt{CONFIG\_USERSPACE} is enabled, a thread running in supervisor mode may perform a one-way transition to user mode using the \texttt{k\_thread\_user\_mode\_enter()} API. This is a one-way operation which will reset and zero the thread's stack memory. The thread will be marked as non-essential.

\noindent \textbf{Terminating a Thread} \hspace{0.5em} A thread terminates itself by returning from its entry point function. The following code illustrates the ways a thread can terminate.

\begin{verbatim}
void my_entry_point(int unused1, int unused2, int unused3)
{
    while (1) {
        ...  // <some condition>
        if (<some condition>) {
            return; /* thread terminates from mid-entry point function */
        }
        ...
    }
    /* thread terminates at end of entry point function */
}
\end{verbatim}

If \texttt{CONFIG\_USERSPACE} is enabled, aborting a thread will additionally mark the thread and stack objects as uninitialized so that they may be re-used.

\noindent \textbf{Runtime Statistics} \hspace{0.5em} Thread runtime statistics can be gathered and retrieved if \texttt{CONFIG\_THREAD\_RUNTIME\_STATS} is enabled, for example, total number of execution cycles of a thread. By default, the runtime statistics are gathered using the default kernel timer. For some architectures, SoCs or boards, there are timers with higher resolution available via timing functions. Using of these timers can be enabled via \texttt{CONFIG\_THREAD\_RUNTIME\_STATS\_USE\_TIMING\_FUNCTIONS}.

\noindent Here is an example:

\begin{verbatim}
k_thread_runtime_stats_t rt_stats_thread;
k_thread_runtime_stats_get(k_current_get(), &rt_stats_thread);
printk("Cycles: %llu\n", rt_stats_thread.execution_cycles);
\end{verbatim}

\noindent \textbf{Suggested Uses} \hspace{0.5em} Use threads to handle processing that cannot be handled in an ISR.

Use separate threads to handle logically distinct processing operations that can execute in parallel.
Configuration Options  Related configuration options:

- CONFIG_MAIN_THREAD_PRIORITY
- CONFIG_MAIN_STACK_SIZE
- CONFIG_IDLE_STACK_SIZE
- CONFIG_THREAD_CUSTOM_DATA
- CONFIG_NUM_COOP_PRIORITIES
- CONFIG_NUM_PREEMPT_PRIORITIES
- CONFIG_TIMESLICING
- CONFIG_TIMESLICE_SIZE
- CONFIG_TIMESLICE_PRIORITY
- CONFIG_USERSPACE

API Reference

Related code samples

Basic Synchronization
Manipulate basic kernel synchronization primitives.

Basic thread manipulation
Spawn multiple threads that blink LEDs and print information to the console.

Dumb HTTP server (multi-threaded)
Implement a simple HTTP server supporting simultaneous connections using BSD sockets.

group thread_apis

Defines

K_ESSENTIAL
system thread that must not abort

K_FP_IDX
FPU registers are managed by context switch.
This option indicates that the thread uses the CPU's floating point registers. This instructs the kernel to take additional steps to save and restore the contents of these registers when scheduling the thread. No effect if CONFIG_FPU_SHARING is not enabled.

K_FP_REGS

K_USER
user mode thread
This thread has dropped from supervisor mode to user mode and consequently has additional restrictions
K_INHERIT_PERMS
Inherit Permissions.
Indicates that the thread being created should inherit all kernel object permissions
from the thread that created it. No effect if CONFIG_USERSPACE is not enabled.

K_CALLBACK_STATE
Callback item state.
This is a single bit of state reserved for “callback manager” utilities (p4wq initially)
who need to track operations invoked from within a user-provided callback they have
been invoked. Effectively it serves as a tiny bit of zero-overhead TLS data.

K_DSP_IDX
DSP registers are managed by context switch.
This option indicates that the thread uses the CPU’s DSP registers. This instructs the
kernel to take additional steps to save and restore the contents of these registers when
scheduling the thread. No effect if CONFIG_DSP_SHARING is not enabled.

K_DSP_REGS
K_AGU_IDX
AGU registers are managed by context switch.
This option indicates that the thread uses the ARC processor's XY memory and DSP fea-
ture. Often used with CONFIG_ARC_AGU_SHARING. No effect if CONFIG_ARC_AGU_SHARING
is not enabled.

K_AGU_REGS
K_SSE_REGS
FP and SSE registers are managed by context switch on x86.
This option indicates that the thread uses the x86 CPU’s floating point and SSE registers.
This instructs the kernel to take additional steps to save and restore the contents of
these registers when scheduling the thread. No effect if CONFIG_X86_SSE is not enabled.

k_thread_access_grant(thread, ...)
Grant a thread access to a set of kernel objects.
This is a convenience function. For the provided thread, grant access to the remaining
arguments, which must be pointers to kernel objects.
The thread object must be initialized (i.e. running). The objects don’t need to be. Note
that NULL shouldn’t be passed as an argument.

Parameters
• thread – Thread to grant access to objects
• ... – list of kernel object pointers

K_THREAD_DEFINE(name, stack_size, entry, p1, p2, p3, prio, options, delay)
Statically define and initialize a thread.
The thread may be scheduled for immediate execution or a delayed start.
Thread options are architecture-specific, and can include K_ESSENTIAL, K_FP_REGS,
and K_SSE_REGS. Multiple options may be specified by separating them using “|” (the
logical OR operator).

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The ID of the thread can be accessed using:

```c
extern const k_tid_t <name>;
```

**Note:** Static threads with zero delay should not normally have MetaIRQ priority levels. This can preempt the system initialization handling (depending on the priority of the main thread) and cause surprising ordering side effects. It will not affect anything in the OS per se, but consider it bad practice. Use a SYS_INIT() callback if you need to run code before entrance to the application main().

### Parameters

- **name** – Name of the thread.
- **stack_size** – Stack size in bytes.
- **entry** – Thread entry function.
- **p1** – 1st entry point parameter.
- **p2** – 2nd entry point parameter.
- **p3** – 3rd entry point parameter.
- **prio** – Thread priority.
- **options** – Thread options.
- **delay** – Scheduling delay (in milliseconds), zero for no delay.

**K_KERNEL_THREAD_DEFINE**(name, stack_size, entry, p1, p2, p3, prio, options, delay)

Statically define and initialize a thread intended to run only in kernel mode. The thread may be scheduled for immediate execution or a delayed start.

Thread options are architecture-specific, and can include K_ESSENTIAL, K_FP_REGS, and K_SSE_REGS. Multiple options may be specified by separating them using “|” (the logical OR operator).

The ID of the thread can be accessed using:

```c
extern const k_tid_t <name>;
```

**Note:** Threads defined by this can only run in kernel mode, and cannot be transformed into user thread via `k_thread_user_mode_enter()`.

**Warning:** Depending on the architecture, the stack size (stack_size) may need to be multiples of CONFIG_MMU_PAGE_SIZE (if MMU) or in power-of-two size (if MPU).

### Parameters

- **name** – Name of the thread.
- **stack_size** – Stack size in bytes.
- **entry** – Thread entry function.
- **p1** – 1st entry point parameter.
- **p2** – 2nd entry point parameter.
• **p3** – 3rd entry point parameter.
• **prio** – Thread priority.
• **options** – Thread options.
• **delay** – Scheduling delay (in milliseconds), zero for no delay.

**Typedefs**

typedef void (*k_thread_user_cb_t)(const struct k_thread *thread, void *user_data)

**Functions**

void k_thread_foreach(k_thread_user_cb_t user_cb, void *user_data)

Iterate over all the threads in the system.

This routine iterates over all the threads in the system and calls the user_cb function for each thread.

**Note:** CONFIG_THREAD_MONITOR must be set for this function to be effective.

**Note:** This API uses **k_spin_lock** to protect the _kernel.threads list which means creation of new threads and terminations of existing threads are blocked until this API returns.

**Parameters**

• **user_cb** – Pointer to the user callback function.
• **user_data** – Pointer to user data.

void k_thread_foreach_unlocked(k_thread_user_cb_t user_cb, void *user_data)

Iterate over all the threads in the system without locking.

This routine works exactly the same like **k_thread_foreach** but unlocks interrupts when user_cb is executed.

**Note:** CONFIGTHREAD_MONITOR must be set for this function to be effective.

**Note:** This API uses **k_spin_lock** only when accessing the _kernel.threads queue elements. It unlocks it during user callback function processing. If a new task is created when this foreach function is in progress, the added new task would not be included in the enumeration. If a task is aborted during this enumeration, there would be a race here and there is a possibility that this aborted task would be included in the enumeration.

**Note:** If the task is aborted and the memory occupied by its **k_thread** structure is reused when this k_thread_foreach_unlocked is in progress it might even lead to the system behave unstable. This function may never return, as it would follow some next task pointers treating given pointer as a pointer to the **k_thread** structure while
it is something different right now. Do not reuse the memory that was occupied by
*k_thread* structure of aborted task if it was aborted after this function was called in
any context.

**Parameters**
- *user_cb* – Pointer to the user callback function.
- *user_data* – Pointer to user data.

```c
k_thread_stack_t *k_thread_stack_alloc(size_t size, int flags)
```

Dynamically allocate a thread stack.

Relevant stack creation flags include:
- *K_USER* allocate a userspace thread (requires CONFIG_USERSPACE=y)

**See also:**
CONFIG_DYNAMIC_THREAD

**Parameters**
- *size* – Stack size in bytes.
- *flags* – Stack creation flags, or 0.

**Return values**
- *the* – allocated thread stack on success.
- *NULL* – on failure.

```c
int k_thread_stack_free(k_thread_stack_t *stack)
```

Free a dynamically allocated thread stack.

**See also:**
CONFIG_DYNAMIC_THREAD

**Parameters**
- *stack* – Pointer to the thread stack.

**Return values**
- 0 – on success.
- -EBUSY – if the thread stack is in use.
- -EINVAL – if stack is invalid.
- -ENOSYS – if dynamic thread stack allocation is disabled

```c
k_tid_t k_thread_create(struct k_thread *new_thread, k_thread_stack_t *stack, size_t
stack_size, k_thread_entry_t entry, void *p1, void *p2, void *p3,
int prio, uint32_t options, k_timeout_t delay)
```

Create a thread.

This routine initializes a thread, then schedules it for execution.

The new thread may be scheduled for immediate execution or a delayed start. If the
newly spawned thread does not have a delayed start the kernel scheduler may preempt
the current thread to allow the new thread to execute.
Thread options are architecture-specific, and can include K_ESSENTIAL, K_FP_REGS, and K_SSE_REGS. Multiple options may be specified by separating them using “|” (the logical OR operator).

Stack objects passed to this function must be originally defined with either of these macros in order to be portable:

- `K_THREAD_STACK_DEFINE()` - For stacks that may support either user or supervisor threads.
- `K_KERNEL_STACK_DEFINE()` - For stacks that may support supervisor threads only. These stacks use less memory if CONFIG_USERSPACE is enabled.

The stack_size parameter has constraints. It must either be:

- The original size value passed to `K_THREAD_STACK_DEFINE()` or `K_KERNEL_STACK_DEFINE()`
- The return value of `K_THREAD_STACK_SIZEOF(stack)` if the stack was defined with `K_THREAD_STACK_DEFINE()`
- The return value of `K_KERNEL_STACK_SIZEOF(stack)` if the stack was defined with `K_KERNEL_STACK_DEFINE()`.

Using other values, or sizeof(stack) may produce undefined behavior.

**Parameters**

- `new_thread` – Pointer to uninitialized struct `k_thread`
- `stack` – Pointer to the stack space.
- `stack_size` – Stack size in bytes.
- `entry` – Thread entry function.
- `p1` – 1st entry point parameter.
- `p2` – 2nd entry point parameter.
- `p3` – 3rd entry point parameter.
- `prio` – Thread priority.
- `options` – Thread options.
- `delay` – Scheduling delay, or K_NO_WAIT (for no delay).

**Returns**

ID of new thread.

FUNC_NORETURN void `k_thread_user_mode_enter` (k_thread_entry_t entry, void *p1, void *p2, void *p3)

Drop a thread's privileges permanently to user mode.

This allows a supervisor thread to be re-used as a user thread. This function does not return, but control will transfer to the provided entry point as if this was a new user thread.

The implementation ensures that the stack buffer contents are erased. Any thread-local storage will be reverted to a pristine state.

Memory domain membership, resource pool assignment, kernel object permissions, priority, and thread options are preserved.

A common use of this function is to re-use the main thread as a user thread once all supervisor mode-only tasks have been completed.
Parameters

- `entry` - Function to start executing from
- `p1` – 1st entry point parameter
- `p2` – 2nd entry point parameter
- `p3` – 3rd entry point parameter

static inline void k_thread_heap_assign(struct k_thread *thread, struct k_heap *heap)
Assign a resource memory pool to a thread.

By default, threads have no resource pool assigned unless their parent thread has a resource pool, in which case it is inherited. Multiple threads may be assigned to the same memory pool.

Changing a thread's resource pool will not migrate allocations from the previous pool.

Parameters

- `thread` – Target thread to assign a memory pool for resource requests.
- `heap` – Heap object to use for resources, or NULL if the thread should no longer have a memory pool.

int k_thread_join(struct k_thread *thread, k_timeout_t timeout)
Sleep until a thread exits.

The caller will be put to sleep until the target thread exits, either due to being aborted, self-exiting, or taking a fatal error. This API returns immediately if the thread isn’t running.

This API may only be called from ISRs with a K_NO_WAIT timeout, where it can be useful as a predicate to detect when a thread has aborted.

Parameters

- `thread` – Thread to wait to exit
- `timeout` – upper bound time to wait for the thread to exit.

Return values

- 0 – success, target thread has exited or wasn’t running
- -EBUSY – returned without waiting
- -EAGAIN – waiting period timed out
- -EDEADLK – target thread is joining on the caller, or target thread is the caller

int32_t k_sleep(k_timeout_t timeout)
Put the current thread to sleep.

This routine puts the current thread to sleep for duration, specified as a `k_timeout_t` object.

Note: if `timeout` is set to K_FOREVER then the thread is suspended.

Parameters

- `timeout` – Desired duration of sleep.

Returns

Zero if the requested time has elapsed or if the thread was woken up by the `k_wakeup` call, the time left to sleep rounded up to the nearest millisecond.
static inline int32_t k_msleep(int32_t ms)
  Put the current thread to sleep.

  This routine puts the current thread to sleep for \textit{duration} milliseconds.

  \textbf{Parameters}
  \begin{itemize}
  \item \texttt{ms} – Number of milliseconds to sleep.
  \end{itemize}

  \textbf{Returns}
  Zero if the requested time has elapsed or if the thread was woken up by the \texttt{k_wakeup} call, the time left to sleep rounded up to the nearest millisecond.

int32_t k_usleep(int32_t us)
  Put the current thread to sleep with microsecond resolution.

  This function is unlikely to work as expected without kernel tuning. In particular, because the lower bound on the duration of a sleep is the duration of a tick, \texttt{CONFIG_SYS_CLOCK_TICKS_PER_SEC} must be adjusted to achieve the resolution desired. The implications of doing this must be understood before attempting to use \texttt{k_usleep()}. Use with caution.

  \textbf{Parameters}
  \begin{itemize}
  \item \texttt{us} – Number of microseconds to sleep.
  \end{itemize}

  \textbf{Returns}
  Zero if the requested time has elapsed or if the thread was woken up by the \texttt{k_wakeup} call, the time left to sleep rounded up to the nearest microsecond.

void k_busy_wait(uint32_t usec_to_wait)
  Cause the current thread to busy wait.

  This routine causes the current thread to execute a “do nothing” loop for \texttt{usec_to_wait} microseconds.

\textbf{Note:} The clock used for the microsecond-resolution delay here may be skewed relative to the clock used for system timeouts like \texttt{k_sleep()}. For example \texttt{k_busy_wait(1000)} may take slightly more or less time than \texttt{k_sleep(K_MSEC(1))}, with the offset dependent on clock tolerances.

\textbf{Note:} In case when \texttt{CONFIG_SYSTEM_CLOCK_SLOPPY_IDLE} and \texttt{CONFIG_PM} options are enabled, this function may not work. The timer/clock used for delay processing may be disabled/inactive.

bool k_can_yield(void)
  Check whether it is possible to yield in the current context.

  This routine checks whether the kernel is in a state where it is possible to yield or call blocking API's. It should be used by code that needs to yield to perform correctly, but can feasibly be called from contexts where that is not possible. For example in the \texttt{PRE_KERNEL} initialization step, or when being run from the idle thread.

  \textbf{Returns}
  True if it is possible to yield in the current context, false otherwise.

void k_yield(void)
  Yield the current thread.

  This routine causes the current thread to yield execution to another thread of the same or higher priority. If there are no other ready threads of the same or higher priority, the routine returns immediately.
void k_wakeup(k_tid_t thread)
    Wake up a sleeping thread.
    This routine prematurely wakes up *thread* from sleeping.
    If *thread* is not currently sleeping, the routine has no effect.

    **Parameters**
    • thread – ID of thread to wake.

__attribute_const__ k_tid_t k_sched_current_thread_query(void)
    Query thread ID of the current thread.
    This unconditionally queries the kernel via a system call.

    **Note:** Use *k_current_get()* unless absolutely sure this is necessary. This should only be used directly where the thread local variable cannot be used or may contain invalid values if thread local storage (TLS) is enabled. If TLS is not enabled, this is the same as *k_current_get()*.

__attribute_const__ static inline k_tid_t k_current_get(void)
    Get thread ID of the current thread.

    **Returns**
    ID of current thread.

void k_thread_abort(k_tid_t thread)
    Abort a thread.
    This routine permanently stops execution of *thread*. The thread is taken off all kernel queues it is part of (i.e. the ready queue, the timeout queue, or a kernel object wait queue). However, any kernel resources the thread might currently own (such as mutexes or memory blocks) are not released. It is the responsibility of the caller of this routine to ensure all necessary cleanup is performed.

    After *k_thread_abort()* returns, the thread is guaranteed not to be running or to become runnable anywhere on the system. Normally this is done via blocking the caller (in the same manner as *k_thread_join()*), but in interrupt context on SMP systems the implementation is required to spin for threads that are running on other CPUs.

    **Parameters**
    • thread – ID of thread to abort.

void k_thread_start(k_tid_t thread)
    Start an inactive thread.
    If a thread was created with K_FOREVER in the delay parameter, it will not be added to the scheduling queue until this function is called on it.

    **Parameters**
    • thread – thread to start

k_ticks_t k_thread_timeoutExpires_ticks(const struct k_thread *t)
    Get time when a thread wakes up, in system ticks.
    This routine computes the system uptime when a waiting thread next executes, in units of system ticks. If the thread is not waiting, it returns current system time.
**k_ticks_t k_thread_timeout_remaining_ticks(const struct k_thread *t)**

Get time remaining before a thread wakes up, in system ticks.

This routine computes the time remaining before a waiting thread next executes, in units of system ticks. If the thread is not waiting, it returns zero.

**int k_thread_priority_get(k_tid_t thread)**

Get a thread's priority.

This routine gets the priority of `thread`.

**Parameters**

- `thread` – ID of thread whose priority is needed.

**Returns**

Priority of `thread`.

**void k_thread_priority_set(k_tid_t thread, int prio)**

Set a thread's priority.

This routine immediately changes the priority of `thread`.

Rescheduling can occur immediately depending on the priority `thread` is set to:

- If its priority is raised above the priority of the caller of this function, and the caller is preemptible, `thread` will be scheduled in.
- If the caller operates on itself, it lowers its priority below that of other threads in the system, and the caller is preemptible, the thread of highest priority will be scheduled in.

Priority can be assigned in the range of `-CONFIG_NUM_COOP_PRIORITIES` to `CONFIG_NUM_PREEMPT_PRIORITIES-1`, where `-CONFIG_NUM_COOP_PRIORITIES` is the highest priority.

**Warning:** Changing the priority of a thread currently involved in mutex priority inheritance may result in undefined behavior.

**Parameters**

- `thread` – ID of thread whose priority is to be set.
- `prio` – New priority.

**void k_thread_deadline_set(k_tid_t thread, int deadline)**

Set deadline expiration time for scheduler.

This sets the “deadline” expiration as a time delta from the current time, in the same units used by `k_cycle_get_32()`. The scheduler (when deadline scheduling is enabled) will choose the next expiring thread when selecting between threads at the same static priority. Threads at different priorities will be scheduled according to their static priority.

**Note:** Deadlines are stored internally using 32 bit unsigned integers. The number of cycles between the “first” deadline in the scheduler queue and the “last” deadline must be less than $2^{31}$ (i.e a signed non-negative quantity). Failure to adhere to this rule may result in scheduled threads running in an incorrect deadline order.
Note: Despite the API naming, the scheduler makes no guarantees the thread WILL be scheduled within that deadline, nor does it take extra metadata (like e.g. the “runtime” and “period” parameters in Linux sched_setattr()) that allows the kernel to validate the scheduling for achievability. Such features could be implemented above this call, which is simply input to the priority selection logic.

Note: You should enable CONFIG_SCHED_DEADLINE in your project configuration.

Parameters
- thread – A thread on which to set the deadline
- deadline – A time delta, in cycle units

int k_thread_cpu_mask_clear(k_tid_t thread)
Sets all CPU enable masks to zero.
After this returns, the thread will no longer be schedulable on any CPUs. The thread must not be currently runnable.

Note: You should enable CONFIG_SCHED_CPU_MASK in your project configuration.

Parameters
- thread – Thread to operate upon

Returns
Zero on success, otherwise error code

int k_thread_cpu_mask_enable_all(k_tid_t thread)
Sets all CPU enable masks to one.
After this returns, the thread will be schedulable on any CPU. The thread must not be currently runnable.

Note: You should enable CONFIG_SCHED_CPU_MASK in your project configuration.

Parameters
- thread – Thread to operate upon

Returns
Zero on success, otherwise error code

int k_thread_cpu_mask_enable(k_tid_t thread, int cpu)
Enable thread to run on specified CPU.
The thread must not be currently runnable.

Note: You should enable CONFIG_SCHED_CPU_MASK in your project configuration.

Parameters
- thread – Thread to operate upon
• cpu – CPU index

Returns
Zero on success, otherwise error code

int k_thread_cpu_mask_disable(k_tid_t thread, int cpu)
Prevent thread to run on specified CPU.
The thread must not be currently runnable.

Note: You should enable CONFIG_SCHED_CPU_MASK in your project configuration.

Parameters
• thread – Thread to operate upon
• cpu – CPU index

Returns
Zero on success, otherwise error code

int k_thread_cpu_pin(k_tid_t thread, int cpu)
Pin a thread to a CPU.
Pin a thread to a CPU by first clearing the cpu mask and then enabling the thread on the selected CPU.

Parameters
• thread – Thread to operate upon
• cpu – CPU index

Returns
Zero on success, otherwise error code

void k_thread_suspend(k_tid_t thread)
Suspend a thread.
This routine prevents the kernel scheduler from making thread the current thread. All other internal operations on thread are still performed; for example, kernel objects it is waiting on are still handed to it. Note that any existing timeouts (e.g. k_sleep(), or a timeout argument to k.sem.take() et. al.) will be canceled. On resume, the thread will begin running immediately and return from the blocked call.
When the target thread is active on another CPU, the caller will block until the target thread is halted (suspended or aborted). But if the caller is in an interrupt context, it will spin waiting for that target thread active on another CPU to halt.

If thread is already suspended, the routine has no effect.

Parameters
• thread – ID of thread to suspend.

void k_thread_resume(k_tid_t thread)
Resume a suspended thread.
This routine allows the kernel scheduler to make thread the current thread, when it is next eligible for that role.

If thread is not currently suspended, the routine has no effect.

Parameters
• thread – ID of thread to resume.
void k_sched_time_slice_set(int32_t slice, int prio)

Set time-slicing period and scope.

This routine specifies how the scheduler will perform time slicing of preemptible threads.

To enable time slicing, `slice` must be non-zero. The scheduler ensures that no thread runs for more than the specified time limit before other threads of that priority are given a chance to execute. Any thread whose priority is higher than `prio` is exempted, and may execute as long as desired without being preempted due to time slicing.

Time slicing only limits the maximum amount of time a thread may continuously execute. Once the scheduler selects a thread for execution, there is no minimum guaranteed time the thread will execute before threads of greater or equal priority are scheduled.

When the current thread is the only one of that priority eligible for execution, this routine has no effect; the thread is immediately rescheduled after the slice period expires.

To disable timeslicing, set both `slice` and `prio` to zero.

**Parameters**

- `slice` – Maximum time slice length (in milliseconds).
- `prio` – Highest thread priority level eligible for time slicing.

void k_thread_time_slice_set(struct k_thread *th, int32_t slice_ticks, k_thread_timeslice_fn_t expired, void *data)

Set thread time slice.

As for `k_sched_time_slice_set`, but (when CONFIG_TIMESLICE_PER_THREAD=y) sets the timeslice for a specific thread. When non-zero, this timeslice will take precedence over the global value.

When such a thread's timeslice expires, the configured callback will be called before the thread is removed/re-added to the run queue. This callback will occur in interrupt context, and the specified thread is guaranteed to have been preempted by the currently-executing ISR. Such a callback is free to, for example, modify the thread priority or slice time for future execution, suspend the thread, etc...

**Note:** Unlike the older API, the time slice parameter here is specified in ticks, not milliseconds. Ticks have always been the internal unit, and not all platforms have integer conversions between the two.

**Note:** Threads with a non-zero slice time set will be timesliced always, even if they are higher priority than the maximum timeslice priority set via `k_sched_time_slice_set()`.

**Note:** The callback notification for slice expiration happens, as it must, while the thread is still "current", and thus it happens before any registered timeouts at this tick. This has the somewhat confusing side effect that the tick time (c.f. `k_uptime_get()`) does not yet reflect the expired ticks. Applications wishing to make fine-grained timing decisions within this callback should use the cycle API, or derived facilities like `k_thread_runtime_stats_get()`.

**Parameters**

- `th` – A valid, initialized thread
- `slice_ticks` – Maximum timeslice, in ticks
• **expired** – Callback function called on slice expiration
• **data** – Parameter for the expiration handler

```c
void k_sched_lock(void)
Lock the scheduler.

This routine prevents the current thread from being preempted by another thread by instructing the scheduler to treat it as a cooperative thread. If the thread subsequently performs an operation that makes it unready, it will be context switched out in the normal manner. When the thread again becomes the current thread, its non-preemptible status is maintained.

This routine can be called recursively.

Owing to clever implementation details, scheduler locks are extremely fast for non-userspace threads (just one byte inc/decrement in the thread struct).
```

**Note:** This works by elevating the thread priority temporarily to a cooperative priority, allowing cheap synchronization vs. other preemptible or cooperative threads running on the current CPU. It does not prevent preemption or asynchrony of other types. It does not prevent threads from running on other CPUs when CONFIG_SMP=y. It does not prevent interrupts from happening, nor does it prevent threads with MetaIRQ priorities from preempting the current thread. In general this is a historical API not well-suited to modern applications, use with care.

```c
void k_sched_unlock(void)
Unlock the scheduler.

This routine reverses the effect of a previous call to `k_sched_lock()`. A thread must call the routine once for each time it called `k_sched_lock()` before the thread becomes preemptible.

void k_thread_custom_data_set(void *value)
Set current thread’s custom data.

This routine sets the custom data for the current thread to @ value.

Custom data is not used by the kernel itself, and is freely available for a thread to use as it sees fit. It can be used as a framework upon which to build thread-local storage.

**Parameters**

• **value** – New custom data value.

void *k_thread_custom_data_get(void)
Get current thread’s custom data.

This routine returns the custom data for the current thread.

**Returns**

Current custom data value.

int k_thread_name_set(k_tid_t thread, const char *str)
Set current thread name.

Set the name of the thread to be used when CONFIG_THREAD_MONITOR is enabled for tracing and debugging.

**Parameters**

• **thread** – Thread to set name, or NULL to set the current thread
• **str** – Name string
Return values

- 0 – on success
- -EFAULT – Memory access error with supplied string
- -ENOSYS – Thread name configuration option not enabled
- -EINVAL – Thread name too long

const char *k_thread_name_get(k_tid_t thread)
Get thread name.
Get the name of a thread

Parameters

- thread – Thread ID

Return values

Thread – name, or NULL if configuration not enabled

int k_thread_name_copy(k_tid_t thread, char *buf, size_t size)
Copy the thread name into a supplied buffer.

Parameters

- thread – Thread to obtain name information
- buf – Destination buffer
- size – Destination buffer size

Return values

- -ENOSPC – Destination buffer too small
- -EFAULT – Memory access error
- -ENOSYS – Thread name feature not enabled
- 0 – Success

const char *k_thread_state_str(k_tid_t thread_id, char *buf, size_t buf_size)
Get thread state string.
This routine generates a human friendly string containing the thread’s state, and copies as much of it as possible into buf.

Parameters

- thread_id – Thread ID
- buf – Buffer into which to copy state strings
- buf_size – Size of the buffer

Return values

Pointer – to buf’ if data was copied, else a pointer to “”.

struct k_thread

#include <thread.h> Thread Structure.

Public Members

struct _callee_saved callee_saved

defined by the architecture, but all archs need these
void *init_data
    static thread init data

_wait_q_t join_queue
    threads waiting in k_thread_join()

struct _thread_entry entry
    thread entry and parameters description

struct k_thread *next_thread
    next item in list of all threads

void *custom_data
    crude thread-local storage

struct _thread_stack_info stack_info
    Stack Info.

struct _mem_domain_info mem_domain_info
    memory domain info of the thread

k_thread_stack_t *stack_obj
    Base address of thread stack.

void *syscall_frame
    current syscall frame pointer

int swap_retval
    z_swap() return value

void *switch_handle
    Context handle returned via arch_switch()

struct k_heap *resource_pool
    resource pool

_wait_q_t halt_queue
    threads waiting in k_thread_suspend()

struct _thread_arch arch
    arch-specifics: must always be at the end

group thread_stack_api
    Thread Stack APIs.

Defines
K_KERNEL_STACK_DECLARE(sym, size)
  Declare a reference to a thread stack.

  This macro declares the symbol of a thread stack defined elsewhere in the current scope.

  Parameters
  • `sym` – Thread stack symbol name
  • `size` – Size of the stack memory region

K_KERNEL_STACK_ARRAY_DECLARE(sym, nmemb, size)
Declare a reference to a thread stack array.

This macro declares the symbol of a thread stack array defined elsewhere in the current scope.

  Parameters
  • `sym` – Thread stack symbol name
  • `nmemb` – Number of stacks defined
  • `size` – Size of the stack memory region

K_KERNEL_PINNED_STACK_ARRAY_DECLARE(sym, nmemb, size)
Declare a reference to a pinned thread stack array.

This macro declares the symbol of a pinned thread stack array defined elsewhere in the current scope.

  Parameters
  • `sym` – Thread stack symbol name
  • `nmemb` – Number of stacks defined
  • `size` – Size of the stack memory region

K_KERNEL_STACK_DEFINE(sym, size)
Define a toplevel kernel stack memory region.

This defines a region of memory for use as a thread stack, for threads that exclusively run in supervisor mode. This is also suitable for declaring special stacks for interrupt or exception handling.

Stacks defined with this macro may not host user mode threads.

It is legal to precede this definition with the ‘static’ keyword.

It is NOT legal to take the `sizeof(sym)` and pass that to the stackSize parameter of `k_thread_create()`, it may not be the same as the ‘size’ parameter. Use `K_KERNEL_STACK_SIZEOF()` instead.

The total amount of memory allocated may be increased to accommodate fixed-size stack overflow guards.

  Parameters
  • `sym` – Thread stack symbol name
  • `size` – Size of the stack memory region

K_KERNEL_PINNED_STACK_DEFINE(sym, size)
Define a toplevel kernel stack memory region in pinned section.

See `K_KERNEL_STACK_DEFINE()` for more information and constraints.
This puts the stack into the pinned noinit linker section if CONFIG_LINKER_USE_PINNED_SECTION is enabled, or else it would put the stack into the same section as `K_KERNELSTACK_DEFINE()`.

### Parameters
- **sym** – Thread stack symbol name
- **size** – Size of the stack memory region

`K_KERNEL_STACK_ARRAY_DEFINE( sym, nmemb, size )`

Defines a toplevel array of kernel stack memory regions.

Stacks defined with this macro may not host user mode threads.

### Parameters
- **sym** – Kernel stack array symbol name
- **nmemb** – Number of stacks to define
- **size** – Size of the stack memory region

`K_KERNEL_PINNED_STACK_ARRAY_DEFINE( sym, nmemb, size )`

Defines a toplevel array of kernel stack memory regions in pinned section.

See `K_KERNEL_STACK_ARRAY_DEFINE()` for more information and constraints.

This puts the stack into the pinned noinit linker section if CONFIG_LINKER_USE_PINNED_SECTION is enabled, or else it would put the stack into the same section as `K_KERNEL_STACK_ARRAY_DEFINE()`.

### Parameters
- **sym** – Kernel stack array symbol name
- **nmemb** – Number of stacks to define
- **size** – Size of the stack memory region

`K_KERNEL_STACK_MEMBER( sym, size )`

Defines an embedded stack memory region.

Used for kernel stacks embedded within other data structures.

Stacks defined with this macro may not host user mode threads.

### Parameters
- **sym** – Thread stack symbol name
- **size** – Size of the stack memory region

`K_KERNEL_STACK_SIZEOF( sym )`

`K_THREAD_STACK_DECLARE( sym, size )`

Declares a reference to a thread stack.

This macro declares the symbol of a thread stack defined elsewhere in the current scope.

### Parameters
- **sym** – Thread stack symbol name
- **size** – Size of the stack memory region

`K_THREAD_STACK_ARRAY_DECLARE( sym, nmemb, size )`

Declares a reference to a thread stack array.

This macro declares the symbol of a thread stack array defined elsewhere in the current scope.

### Parameters
- **sym** – Thread stack symbol name
- **size** – Size of the stack memory region
Parameters

- **sym** – Thread stack symbol name
- **nmemb** – Number of stacks defined
- **size** – Size of the stack memory region

**K_THREAD_STACK_SIZEOF(sym)**

Return the size in bytes of a stack memory region.

Convenience macro for passing the desired stack size to `k_thread_create()` since the underlying implementation may actually create something larger (for instance a guard area).

The value returned here is not guaranteed to match the ‘size’ parameter passed to `K_THREAD_STACK_DEFINE` and may be larger, but is always safe to pass to `k_thread_create()` for the associated stack object.

Parameters

- **sym** – Stack memory symbol

Returns

Size of the stack buffer

**K_THREAD_STACK_DEFINE(sym, size)**

Define a toplevel thread stack memory region.

This defines a region of memory suitable for use as a thread's stack.

This is the generic, historical definition. Align to Z_THREAD_STACK_OBJ_ALIGN and put in ‘noinit’ section so that it isn’t zeroed at boot.

The defined symbol will always be a k_thread_stack_t which can be passed to `k_thread_create()`, but should otherwise not be manipulated. If the buffer inside needs to be examined, examine thread->stack_info for the associated thread object to obtain the boundaries.

It is legal to precede this definition with the ‘static’ keyword.

It is NOT legal to take the sizeof(sym) and pass that to the stackSize parameter of `k_thread_create()`, it may not be the same as the ‘size’ parameter. Use `K_THREAD_STACK_SIZEOF()` instead.

Some arches may round the size of the usable stack region up to satisfy alignment constraints. `K_THREAD_STACK_SIZEOF()` will return the aligned size.

Parameters

- **sym** – Thread stack symbol name
- **size** – Size of the stack memory region

**K_THREAD_PINNED_STACK_DEFINE(sym, size)**

Define a toplevel thread stack memory region in pinned section.

This defines a region of memory suitable for use as a thread’s stack.

This is the generic, historical definition. Align to Z_THREAD_STACK_OBJ_ALIGN and put in ‘noinit’ section so that it isn’t zeroed at boot.

The defined symbol will always be a k_thread_stack_t which can be passed to `k_thread_create()`, but should otherwise not be manipulated. If the buffer inside needs to be examined, examine thread->stack_info for the associated thread object to obtain the boundaries.

It is legal to precede this definition with the ‘static’ keyword.
It is NOT legal to take the `sizeof(sym)` and pass that to the `stackSize` parameter of `k_thread_create()`, it may not be the same as the `size` parameter. Use `K_THREAD_STACK_SIZEOF()` instead.

Some arches may round the size of the usable stack region up to satisfy alignment constraints. `K_THREAD_STACK_SIZEOF()` will return the aligned size.

This puts the stack into the pinned noinit linker section if `CONFIG_LINKER_USE_PINNED_SECTION` is enabled, or else it would put the stack into the same section as `K_THREAD_STACK_DEFINE()`.

**Parameters**
- `sym` – Thread stack symbol name
- `size` – Size of the stack memory region

**K_THREAD_STACK_LEN(size)**
Calculate size of stacks to be allocated in a stack array.

This macro calculates the size to be allocated for the stacks inside a stack array. It accepts the indicated “size” as a parameter and if required, pads some extra bytes (e.g. for MPU scenarios). Refer `K_THREAD_STACK_ARRAY_DEFINE` definition to see how this is used. The returned size ensures each array member will be aligned to the required stack base alignment.

**Parameters**
- `size` – Size of the stack memory region

**Returns**
Appropriate size for an array member

**K_THREAD_STACK_ARRAY_DEFINE(sym, nmemb, size)**
Define a toplevel array of thread stack memory regions.

Create an array of equally sized stacks. See `K_THREAD_STACK_DEFINE` definition for additional details and constraints.

This is the generic, historical definition. Align to `Z_THREAD_STACK_OBJ_ALIGN` and put in ‘noinit’ section so that it isn’t zeroed at boot.

**Parameters**
- `sym` – Thread stack symbol name
- `nmemb` – Number of stacks to define
- `size` – Size of the stack memory region

**K_THREAD_PINNED_STACK_ARRAY_DEFINE(sym, nmemb, size)**
Define a toplevel array of thread stack memory regions in pinned section.

Create an array of equally sized stacks. See `K_THREAD_STACK_DEFINE` definition for additional details and constraints.

This is the generic, historical definition. Align to `Z_THREAD_STACK_OBJ_ALIGN` and put in ‘noinit’ section so that it isn’t zeroed at boot.

This puts the stack into the pinned noinit linker section if `CONFIG_LINKER_USE_PINNED_SECTION` is enabled, or else it would put the stack into the same section as `K_THREAD_STACK_DEFINE()`.

**Parameters**
- `sym` – Thread stack symbol name
- `nmemb` – Number of stacks to define
- `size` – Size of the stack memory region
K_THREAD_STACK_MEMBER(sym, size)

Define an embedded stack memory region.

Used for stacks embedded within other data structures. Use is highly discouraged but in some cases necessary. For memory protection scenarios, it is very important that any RAM preceding this member not be writable by threads else a stack overflow will lead to silent corruption. In other words, the containing data structure should live in RAM owned by the kernel.

A user thread can only be started with a stack defined in this way if the thread starting it is in supervisor mode.

Deprecated:

This is now deprecated, as stacks defined in this way are not usable from user mode. Use K_KERNEL_STACK_MEMBER.

Parameters

- `sym` – Thread stack symbol name
- `size` – Size of the stack memory region

Scheduling

The kernel's priority-based scheduler allows an application's threads to share the CPU.

Concepts  The scheduler determines which thread is allowed to execute at any point in time; this thread is known as the current thread.

There are various points in time when the scheduler is given an opportunity to change the identity of the current thread. These points are called reschedule points. Some potential reschedule points are:

- transition of a thread from running state to a suspended or waiting state, for example by `k_sem_take()` or `k_sleep()`.
- transition of a thread to the ready state, for example by `k_sem_give()` or `k_thread_start()`
- return to thread context after processing an interrupt
- when a running thread invokes `k_yield()`

A thread sleeps when it voluntarily initiates an operation that transitions itself to a suspended or waiting state.

Whenever the scheduler changes the identity of the current thread, or when execution of the current thread is replaced by an ISR, the kernel first saves the current thread's CPU register values. These register values get restored when the thread later resumes execution.

Scheduling Algorithm  The kernel's scheduler selects the highest priority ready thread to be the current thread. When multiple ready threads of the same priority exist, the scheduler chooses the one that has been waiting longest.

A thread's relative priority is primarily determined by its static priority. However, when both earliest-deadline-first scheduling is enabled (CONFIG_SCHED_DEADLINE) and a choice of threads have equal static priority, then the thread with the earlier deadline is considered to have the higher priority. Thus, when earliest-deadline-first scheduling is enabled, two threads are only considered to have the same priority when both their static priorities and deadlines are equal. The routine `k_thread_deadline_set()` is used to set a thread's deadline.
Note: Execution of ISRs takes precedence over thread execution, so the execution of the current thread may be replaced by an ISR at any time unless interrupts have been masked. This applies to both cooperative threads and preemptive threads.

The kernel can be built with one of several choices for the ready queue implementation, offering different choices between code size, constant factor runtime overhead and performance scaling when many threads are added.

- **Simple linked-list ready queue (CONFIG_SCHED_DUMB)**

  The scheduler ready queue will be implemented as a simple unordered list, with very fast constant time performance for single threads and very low code size. This implementation should be selected on systems with constrained code size that will never see more than a small number (3, maybe) of runnable threads in the queue at any given time. On most platforms (that are not otherwise using the red/black tree) this results in a savings of ~2k of code size.

- **Red/black tree ready queue (CONFIG_SCHED_SCALABLE)**

  The scheduler ready queue will be implemented as a red/black tree. This has rather slower constant-time insertion and removal overhead, and on most platforms (that are not otherwise using the red/black tree somewhere) requires an extra ~2kb of code. The resulting behavior will scale cleanly and quickly into the many thousands of threads.

  Use this for applications needing many concurrent runnable threads (> 20 or so). Most applications won't need this ready queue implementation.

- **Traditional multi-queue ready queue (CONFIG_SCHED_MULTIQ)**

  When selected, the scheduler ready queue will be implemented as the classic/textbook array of lists, one per priority (max 32 priorities).

  This corresponds to the scheduler algorithm used in Zephyr versions prior to 1.12.

  It incurs only a tiny code size overhead vs. the “dumb” scheduler and runs in O(1) time in almost all circumstances with very low constant factor. But it requires a fairly large RAM budget to store those list heads, and the limited features make it incompatible with features like deadline scheduling that need to sort threads more finely, and SMP affinity which need to traverse the list of threads.

  Typical applications with small numbers of runnable threads probably want the DUMB scheduler.

The wait_q abstraction used in IPC primitives to pend threads for later wakeup shares the same backend data structure choices as the scheduler, and can use the same options.

- **Scalable wait_q implementation (CONFIG_WAITQ_SCALABLE)**

  When selected, the wait_q will be implemented with a balanced tree. Choose this if you expect to have many threads waiting on individual primitives. There is a ~2kb code size increase over CONFIG_WAITQ_DUMB (which may be shared with CONFIG_SCHED_SCALABLE) if the red/black tree is not used elsewhere in the application, and pend/unpend operations on “small” queues will be somewhat slower (though this is not generally a performance path).

- **Simple linked-list wait_q (CONFIG_WAITQ_DUMB)**

  When selected, the wait_q will be implemented with a doubly-linked list. Choose this if you expect to have only a few threads blocked on any single IPC primitive.

**Cooperative Time Slicing** Once a cooperative thread becomes the current thread, it remains the current thread until it performs an action that makes it unready. Consequently, if a cooperative thread performs lengthy computations, it may cause an unacceptable delay in the scheduling of other threads, including those of higher priority and equal priority.
To overcome such problems, a cooperative thread can voluntarily relinquish the CPU from time to time to permit other threads to execute. A thread can relinquish the CPU in two ways:

- Calling `k_yield()` puts the thread at the back of the scheduler's prioritized list of ready threads, and then invokes the scheduler. All ready threads whose priority is higher or equal to that of the yielding thread are then allowed to execute before the yielding thread is rescheduled. If no such ready threads exist, the scheduler immediately reschedules the yielding thread without context switching.

- Calling `k_sleep()` makes the thread unready for a specified time period. Ready threads of all priorities are then allowed to execute; however, there is no guarantee that threads whose priority is lower than that of the sleeping thread will actually be scheduled before the sleeping thread becomes ready once again.

**Preemptive Time Slicing** Once a preemptive thread becomes the current thread, it remains the current thread until a higher priority thread becomes ready, or until the thread performs an action that makes it unready. Consequently, if a preemptive thread performs lengthy computations, it may cause an unacceptable delay in the scheduling of other threads, including those of equal priority.
To overcome such problems, a preemptive thread can perform cooperative time slicing (as described above), or the scheduler's time slicing capability can be used to allow other threads of the same priority to execute.

The scheduler divides time into a series of **time slices**, where slices are measured in system clock ticks. The time slice size is configurable, but this size can be changed while the application is running.

At the end of every time slice, the scheduler checks to see if the current thread is preemptible and, if so, implicitly invokes `k_yield()` on behalf of the thread. This gives other ready threads of the same priority the opportunity to execute before the current thread is scheduled again. If no threads of equal priority are ready, the current thread remains the current thread.

Threads with a priority higher than specified limit are exempt from preemptive time slicing, and are never preempted by a thread of equal priority. This allows an application to use preemptive time slicing only when dealing with lower priority threads that are less time-sensitive.

**Note:** The kernel's time slicing algorithm does **not** ensure that a set of equal-priority threads receive an equitable amount of CPU time, since it does not measure the amount of time a thread actually gets to execute. However, the algorithm **does** ensure that a thread never executes for longer than a single time slice without being required to yield.

**Scheduler Locking** A preemptible thread that does not wish to be preempted while performing a critical operation can instruct the scheduler to temporarily treat it as a cooperative thread by calling `k_sched_lock()`. This prevents other threads from interfering while the critical operation is being performed.

Once the critical operation is complete the preemptible thread must call `k_sched_unlock()` to restore its normal, preemptible status.

If a thread calls `k_sched_lock()` and subsequently performs an action that makes it unready, the scheduler will switch the locking thread out and allow other threads to execute. When the locking thread again becomes the current thread, its non-preemptible status is maintained.

**Note:** Locking out the scheduler is a more efficient way for a preemptible thread to prevent
Thread Sleeping  A thread can call \texttt{k_sleep()} to delay its processing for a specified time period. During the time the thread is sleeping the CPU is relinquished to allow other ready threads to execute. Once the specified delay has elapsed the thread becomes ready and is eligible to be scheduled once again.

A sleeping thread can be woken up prematurely by another thread using \texttt{k_wakeup().} This technique can sometimes be used to permit the secondary thread to signal the sleeping thread that something has occurred without requiring the threads to define a kernel synchronization object, such as a semaphore. Waking up a thread that is not sleeping is allowed, but has no effect.

Busy Waiting  A thread can call \texttt{k_busy_wait()} to perform a busy wait that delays its processing for a specified time period without relinquishing the CPU to another ready thread.

A busy wait is typically used instead of thread sleeping when the required delay is too short to warrant having the scheduler context switch from the current thread to another thread and then back again.

Suggested Uses  Use cooperative threads for device drivers and other performance-critical work.

Use cooperative threads to implement mutually exclusion without the need for a kernel object, such as a mutex.

Use preemptive threads to give priority to time-sensitive processing over less time-sensitive processing.

CPU Idling

Although normally reserved for the idle thread, in certain special applications, a thread might want to make the CPU idle.

- Concepts
- Implementation
  - Making the CPU idle
  - Making the CPU idle in an atomic fashion
- Suggested Uses
- API Reference

Concepts  Making the CPU idle causes the kernel to pause all operations until an event, normally an interrupt, wakes up the CPU. In a regular system, the idle thread is responsible for this. However, in some constrained systems, it is possible that another thread takes this duty.

Implementation
Making the CPU idle  Making the CPU idle is simple: call the `k_cpu_idle()` API. The CPU will stop executing instructions until an event occurs. Most likely, the function will be called within a loop. Note that in certain architectures, upon return, `k_cpu_idle()` unconditionally unmasks interrupts.

```c
static k_sem my_sem;

void my_isr(void *unused)
{
    k_sem_give(&my_sem);
}

int main(void)
{
    k_sem_init(&my_sem, 0, 1);

    /* wait for semaphore from ISR, then do related work */
    for (;;)
    {
        /* wait for ISR to trigger work to perform */
        if (k_sem_take(&my_sem, K_NO_WAIT) == 0)
        {
            /* ... do processing */
        }

        /* put CPU to sleep to save power */
        k_cpu_idle();
    }
}
```

Making the CPU idle in an atomic fashion  It is possible that there is a need to do some work atomically before making the CPU idle. In such a case, `k_cpu_atomic_idle()` should be used instead.

In fact, there is a race condition in the previous example: the interrupt could occur between the time the semaphore is taken, finding out it is not available and making the CPU idle again. In some systems, this can cause the CPU to idle until another interrupt occurs, which might be never, thus hanging the system completely. To prevent this, `k_cpu_atomic_idle()` should have been used, like in this example.

```c
static k_sem my_sem;

void my_isr(void *unused)
{
    k_sem_give(&my_sem);
}

int main(void)
{
    k_sem_init(&my_sem, 0, 1);

    for (;;)
    {
        unsigned int key = irq_lock();

        /*
         * Wait for semaphore from ISR; if acquired, do related work, then
         * go to next loop iteration (the semaphore might have been given
         * again); else, make the CPU idle.
         */
    }
}
```
if (k_sem_take(&my_sem, K_NO_WAIT) == 0) {
    irq_unlock(key);
    /* ... do processing */
}
else {
    /* put CPU to sleep to save power */
    k_cpu_atomic_idle(key);
}

**Suggested Uses**  Use `k_cpu_atomic_idle()` when a thread has to do some real work in addition to idling the CPU to wait for an event. See example above.

Use `k_cpu_idle()` only when a thread is only responsible for idling the CPU, i.e. not doing any real work, like in this example below.

```c
int main(void)
{
    /* ... do some system/application initialization */

    /* thread is only used for CPU idling from this point on */
    for (;;) {
        k_cpu_idle();
    }
}
```

**Note:** Do not use these APIs unless absolutely necessary. In a normal system, the idle thread takes care of power management, including CPU idling.

**API Reference**

*group* cpu_idle_apis

**Functions**

static inline void k_cpu_idle(void)

Make the CPU idle.

This function makes the CPU idle until an event wakes it up.

In a regular system, the idle thread should be the only thread responsible for making the CPU idle and triggering any type of power management. However, in some more constrained systems, such as a single-threaded system, the only thread would be responsible for this if needed.

**Note:** In some architectures, before returning, the function unmarks interrupts unconditionally.
static inline void k_cpu_atomic_idle(unsigned int key)
    Make the CPU idle in an atomic fashion.
    Similar to k_cpu_idle(), but must be called with interrupts locked.
    Enabling interrupts and entering a low-power mode will be atomic, i.e. there will be no
    period of time where interrupts are enabled before the processor enters a low-power
    mode.
    After waking up from the low-power mode, the interrupt lockout state will be restored
    as if by irq_unlock(key).

Parameters
- key – Interrupt locking key obtained from irq_lock().

System Threads

- Implementation
  - Writing a main() function
- Suggested Uses

A system thread is a thread that the kernel spawns automatically during system initialization.

The kernel spawns the following system threads:

Main thread
- This thread performs kernel initialization, then calls the application's main() function (if
  one is defined).
  - By default, the main thread uses the highest configured preemptible thread priority (i.e.
    0). If the kernel is not configured to support preemptible threads, the main thread uses the
    lowest configured cooperative thread priority (i.e. -1).
  - The main thread is an essential thread while it is performing kernel initialization or execut-
    ing the application's main() function; this means a fatal system error is raised if the thread
    aborts. If main() is not defined, or if it executes and then does a normal return, the main
    thread terminates normally and no error is raised.

Idle thread
- This thread executes when there is no other work for the system to do. If possible, the idle
  thread activates the board's power management support to save power; otherwise, the idle
  thread simply performs a “do nothing” loop. The idle thread remains in existence as long
  as the system is running and never terminates.
  - The idle thread always uses the lowest configured thread priority. If this makes it a coop-
    erative thread, the idle thread repeatedly yields the CPU to allow the application's other
    threads to run when they need to.
  - The idle thread is an essential thread, which means a fatal system error is raised if the
    thread aborts.

Additional system threads may also be spawned, depending on the kernel and board configura-

Implementation

3.1. Kernel Services
Writing a main() function  An application-supplied main() function begins executing once kernel initialization is complete. The kernel does not pass any arguments to the function.

The following code outlines a trivial main() function. The function used by a real application can be as complex as needed.

```c
int main(void)
{
    /* initialize a semaphore */
    ...

    /* register an ISR that gives the semaphore */
    ...

    /* monitor the semaphore forever */
    while (1) {
        /* wait for the semaphore to be given by the ISR */
        ...
        /* do whatever processing is now needed */
        ...
    }
}
```

Suggested Uses  Use the main thread to perform thread-based processing in an application that only requires a single thread, rather than defining an additional application-specific thread.

Workqueue Threads

- Work Item Lifecycle
- Delayable Work
- Triggered Work
- System Workqueue
- How to Use Workqueues
- Workqueue Best Practices
- Suggested Uses
- Configuration Options
- API Reference

A workqueue is a kernel object that uses a dedicated thread to process work items in a first in, first out manner. Each work item is processed by calling the function specified by the work item. A workqueue is typically used by an ISR or a high-priority thread to offload non-urgent processing to a lower-priority thread so it does not impact time-sensitive processing.

Any number of workqueues can be defined (limited only by available RAM). Each workqueue is referenced by its memory address.

A workqueue has the following key properties:

- A queue of work items that have been added, but not yet processed.
- A thread that processes the work items in the queue. The priority of the thread is configurable, allowing it to be either cooperative or preemptive as required.

Regardless of workqueue thread priority the workqueue thread will yield between each submitted work item, to prevent a cooperative workqueue from starving other threads.
A workqueue must be initialized before it can be used. This sets its queue to empty and spawns the workqueue's thread. The thread runs forever, but sleeps when no work items are available.

**Note:** The behavior described here is changed from the Zephyr workqueue implementation used prior to release 2.6. Among the changes are:

- Precise tracking of the status of cancelled work items, so that the caller need not be concerned that an item may be processing when the cancellation returns. Checking of return values on cancellation is still required.
- Direct submission of delayable work items to the queue with `K_NO_WAIT` rather than always going through the timeout API, which could introduce delays.
- The ability to wait until a work item has completed or a queue has been drained.
- Finer control of behavior when scheduling a delayable work item, specifically allowing a previous deadline to remain unchanged when a work item is scheduled again.
- Safe handling of work item resubmission when the item is being processed on another workqueue.

Using the return values of `k_work_busy_get()` or `k_work_is_pending()`, or measurements of remaining time until delayable work is scheduled, should be avoided to prevent race conditions of the type observed with the previous implementation. See also *Workqueue Best Practices*.

**Work Item Lifecycle** Any number of *work items* can be defined. Each work item is referenced by its memory address.

A work item is assigned a **handler function**, which is the function executed by the workqueue's thread when the work item is processed. This function accepts a single argument, which is the address of the work item itself. The work item also maintains information about its status.

A work item must be initialized before it can be used. This records the work item's handler function and marks it as not pending.

A work item may be **queued** (`K_WORK_QUEUED`) by submitting it to a workqueue by an ISR or a thread. Submitting a work item appends the work item to the workqueue's queue. Once the workqueue's thread has processed all of the preceding work items in its queue the thread will remove the next work item from the queue and invoke the work item's handler function. Depending on the scheduling priority of the workqueue's thread, and the work required by other items in the queue, a queued work item may be processed quickly or it may remain in the queue for an extended period of time.

A delayable work item may be **scheduled** (`K_WORK_DELAYED`) to a workqueue; see *Delayable Work*.

A work item will be **running** (`K_WORK_RUNNING`) when it is running on a work queue, and may also be **canceling** (`K_WORK_CANCELING`) if it started running before a thread has requested that it be cancelled.

A work item can be in multiple states; for example it can be:

- running on a queue;
- marked canceling (because a thread used `k_work_cancel_sync()` to wait until the work item completed);
- queued to run again on the same queue;
- scheduled to be submitted to a (possibly different) queue

all simultaneously. A work item that is in any of these states is **pending** (`k_work_is_pending()`) or **busy** (`k_work_busy_get()`).
A handler function can use any kernel API available to threads. However, operations that are potentially blocking (e.g., taking a semaphore) must be used with care, since the workqueue cannot process subsequent work items in its queue until the handler function finishes executing.

The single argument that is passed to a handler function can be ignored if it is not required. If the handler function requires additional information about the work it is to perform, the work item can be embedded in a larger data structure. The handler function can then use the argument value to compute the address of the enclosing data structure with `CONTAINER_OF`, and thereby obtain access to the additional information it needs.

A work item is typically initialized once and then submitted to a specific workqueue whenever work needs to be performed. If an ISR or a thread attempts to submit a work item that is already queued the work item is not affected; the work item remains in its current place in the workqueue’s queue, and the work is only performed once.

A handler function is permitted to re-submit its work item argument to the workqueue, since the work item is no longer queued at that time. This allows the handler to execute work in stages, without unduly delaying the processing of other work items in the workqueue's queue.

**Important:** A pending work item must not be altered until the item has been processed by the workqueue thread. This means a work item must not be re-initialized while it is busy. Furthermore, any additional information the work item's handler function needs to perform its work must not be altered until the handler function has finished executing.

### Delayable Work

An ISR or a thread may need to schedule a work item that is to be processed only after a specified period of time, rather than immediately. This can be done by scheduling a **delayable work item** to be submitted to a workqueue at a future time.

A delayable work item contains a standard work item but adds fields that record when and where the item should be submitted.

A delayable work item is initialized and scheduled to a workqueue in a similar manner to a standard work item, although different kernel APIs are used. When the schedule request is made the kernel initiates a timeout mechanism that is triggered after the specified delay has elapsed. Once the timeout occurs the kernel submits the work item to the specified workqueue, where it remains queued until it is processed in the standard manner.

Note that work handler used for delayable still receives a pointer to the underlying non-delayable work structure, which is not publicly accessible from `k_work_delayable`. To get access to an object that contains the delayable work object use this idiom:

```c
static void work_handler(struct k_work *work) {
    struct k_work_delayable *dwork = k_work_delayable_from_work(work);
    struct work_context *ctx = CONTAINER_OF(dwork, struct work_context, timed_work);
    ...
}
```

### Triggered Work

The `k_work_poll_submit()` interface schedules a triggered work item in response to a **poll event** (see Polling API), that will call a user-defined function when a monitored resource becomes available or poll signal is raised, or a timeout occurs. In contrast to `k_poll()`, the triggered work does not require a dedicated thread waiting or actively polling for a poll event.

A triggered work item is a standard work item that has the following added properties:

- A pointer to an array of poll events that will trigger work item submissions to the workqueue
- A size of the array containing poll events.
A triggered work item is initialized and submitted to a workqueue in a similar manner to a standard work item, although dedicated kernel APIs are used. When a submit request is made, the kernel begins observing kernel objects specified by the poll events. Once at least one of the observed kernel object’s changes state, the work item is submitted to the specified workqueue, where it remains queued until it is processed in the standard manner.

**Important:** The triggered work item as well as the referenced array of poll events have to be valid and cannot be modified for a complete triggered work item lifecycle, from submission to work item execution or cancellation.

An ISR or a thread may cancel a triggered work item it has submitted as long as it is still waiting for a poll event. In such case, the kernel stops waiting for attached poll events and the specified work is not executed. Otherwise the cancellation cannot be performed.

**System Workqueue** The kernel defines a workqueue known as the *system workqueue*, which is available to any application or kernel code that requires workqueue support. The system workqueue is optional, and only exists if the application makes use of it.

**Important:** Additional workqueues should only be defined when it is not possible to submit new work items to the system workqueue, since each new workqueue incurs a significant cost in memory footprint. A new workqueue can be justified if it is not possible for its work items to co-exist with existing system workqueue work items without an unacceptable impact; for example, if the new work items perform blocking operations that would delay other system workqueue processing to an unacceptable degree.

### How to Use Workqueues

**Defining and Controlling a Workqueue** A workqueue is defined using a variable of type `k_work_q`. The workqueue is initialized by defining the stack area used by its thread, initializing the `k_work_q`, either zeroing its memory or calling `k_work_queue_init()`, and then calling `k_work_queue_start()`. The stack area must be defined using `K_THREAD_STACK_DEFINE` to ensure it is properly set up in memory.

The following code defines and initializes a workqueue:

```c
#define MY_STACK_SIZE 512
#define MY_PRIORITY 5
K_THREAD_STACK_DEFINE(my_stack_area, MY_STACK_SIZE);

struct k_work_q my_work_q;

k_work_queue_init(&my_work_q);

k_work_queue_start(&my_work_q, my_stack_area, K_THREAD_STACK_SIZEOF(my_stack_area), MY_PRIORITY, NULL);
```

In addition the queue identity and certain behavior related to thread rescheduling can be controlled by the optional final parameter; see `k_work_queue_start()` for details.

The following API can be used to interact with a workqueue:

- `k_work_queue_drain()` can be used to block the caller until the work queue has no items left. Work items resubmitted from the workqueue thread are accepted while a queue is draining, but work items from any other thread or ISR are rejected. The restriction on
submitting more work can be extended past the completion of the drain operation in order to allow the blocking thread to perform additional work while the queue is “plugged”. Note that draining a queue has no effect on scheduling or processing delayable items, but if the queue is plugged and the deadline expires the item will silently fail to be submitted.

- \texttt{k\_work\_queue\_unplug()} removes any previous block on submission to the queue due to a previous drain operation.

### Submitting a Work Item

A work item is defined using a variable of type \texttt{k\_work}. It must be initialized by calling \texttt{k\_work\_init()}, unless it is defined using \texttt{K\_WORK\_DEFINE} in which case initialization is performed at compile-time.

An initialized work item can be submitted to the system workqueue by calling \texttt{k\_work\_submit()}, or to a specified workqueue by calling \texttt{k\_work\_submit\_to\_queue()}.

The following code demonstrates how an ISR can offload the printing of error messages to the system workqueue. Note that if the ISR attempts to resubmit the work item while it is still queued, the work item is left unchanged and the associated error message will not be printed.

```c
struct device_info {
    struct k_work work;
    char name[16]
} my_device;

void my_isr(void *arg) {
    ...
    if (error detected) {
        k_work_submit(&my_device.work);
    }
    ...
}

void print_error(struct k_work *item) {
    struct device_info *the_device = CONTAINER_OF(item, struct device_info, work);
    printk("Got error on device \%s\n", the_device->name);
}

/* initialize name info for a device */
strcpy(my_device.name, "FOO_dev");
/* initialize work item for printing device's error messages */
k_work_init(&my_device.work, print_error);
/* install my_isr() as interrupt handler for the device (not shown) */
...
```

The following API can be used to check the status of or synchronize with the work item:

- \texttt{k\_work\_busy\_get()} returns a snapshot of flags indicating work item state. A zero value indicates the work is not scheduled, submitted, being executed, or otherwise still being referenced by the workqueue infrastructure.

- \texttt{k\_work\_is\_pending()} is a helper that indicates true if and only if the work is scheduled, queued, or running.

- \texttt{k\_work\_flush()} may be invoked from threads to block until the work item has completed. It returns immediately if the work is not pending.

- \texttt{k\_work\_cancel()} attempts to prevent the work item from being executed. This may or may not be successful. This is safe to invoke from ISRs.
- `k_work_cancel_sync()` may be invoked from threads to block until the work completes; it will return immediately if the cancellation was successful or not necessary (the work wasn’t submitted or running). This can be used after `k_work_cancel()` is invoked (from an ISR) to confirm completion of an ISR-initiated cancellation.

### Scheduling a Delayable Work Item

A delayable work item is defined using a variable of type `k_work_delayable`. It must be initialized by calling `k_work_init_delayable()`.

For delayed work there are two common use cases, depending on whether a deadline should be extended if a new event occurs. An example is collecting data that comes in asynchronously, e.g. characters from a UART associated with a keyboard. There are two APIs that submit work after a delay:

- `k_work_schedule()` (or `k_work_schedule_for_queue()`) schedules work to be executed at a specific time or after a delay. Further attempts to schedule the same item with this API before the delay completes will not change the time at which the item will be submitted to its queue. Use this if the policy is to keep collecting data until a specified delay since the first unprocessed data was received;

- `k_work_reschedule()` (or `k_work_reschedule_for_queue()`) unconditionally sets the deadline for the work, replacing any previous incomplete delay and changing the destination queue if necessary. Use this if the policy is to keep collecting data until a specified delay since the last unprocessed data was received.

If the work item is not scheduled both APIs behave the same. If `K_NO_WAIT` is specified as the delay the behavior is as if the item was immediately submitted directly to the target queue, without waiting for a minimal timeout (unless `k_work_schedule()` is used and a previous delay has not completed).

Both also have variants that allow control of the queue used for submission.

The helper function `k_work_delayable_from_work()` can be used to get a pointer to the containing `k_work_delayable` from a pointer to `k_work` that is passed to a work handler function.

The following additional API can be used to check the status of or synchronize with the work item:

- `k_work_delayable_busy_get()` is the analog to `k_work_busy_get()` for delayable work.
- `k_work_delayable_is_pending()` is the analog to `k_work_is_pending()` for delayable work.
- `k_work_flush_delayable()` is the analog to `k_work_flush()` for delayable work.
- `k_work_cancel_delayable()` is the analog to `k_work_cancel()` for delayable work; similarly with `k_work_cancel_delayable_sync()`.

### Synchronizing with Work Items

While the state of both regular and delayable work items can be determined from any context using `k_work_busy_get()` and `k_work_delayable_busy_get()` some use cases require synchronizing with work items after they’ve been submitted. `k_work_flush()`, `k_work_cancel_sync()`, and `k_work_cancel_delayable_sync()` can be invoked from thread context to wait until the requested state has been reached.

These APIs must be provided with a `k_work_sync` object that has no application-inspectable components but is needed to provide the synchronization objects. These objects should not be allocated on a stack if the code is expected to work on architectures with `CONFIG_KERNEL_COHERENCE`.

### Workqueue Best Practices
Avoid Race Conditions  Sometimes the data a work item must process is naturally thread-safe, for example when it's put into a `k_queue` by some thread and processed in the work thread. More often external synchronization is required to avoid data races: cases where the work thread might inspect or manipulate shared state that's being accessed by another thread or interrupt. Such state might be a flag indicating that work needs to be done, or a shared object that is filled by an ISR or thread and read by the work handler.

For simple flags **Atomic Services** may be sufficient. In other cases spin locks (`k_spinlock_t`) or thread-aware locks (`k_sem`, `k_mutex`, ...) may be used to ensure data races don't occur.

If the selected lock mechanism can **sleep** then allowing the work thread to sleep will starve other work queue items, which may need to make progress in order to get the lock released. Work handlers should try to take the lock with its no-wait path. For example:

```c
static void work_handler(struct work *work)
{
    struct work_context *parent = CONTAINER_OF(work, struct work_context, work_item);
    
    if (k_mutex_lock(&parent->lock, K_NO_WAIT) != 0) {
        /* NB: Submit will fail if the work item is being cancelled. */
        (void)k_work_submit(work);
        return;
    }
    /* do stuff under lock */
    k_mutex_unlock(&parent->lock);
    /* do stuff without lock */
}
```

Be aware that if the lock is held by a thread with a lower priority than the work queue the resubmission may starve the thread that would release the lock, causing the application to fail. Where the idiom above is required a delayable work item is preferred, and the work should be (re-)scheduled with a non-zero delay to allow the thread holding the lock to make progress.

Note that submitting from the work handler can fail if the work item had been cancelled. Generally this is acceptable, since the cancellation will complete once the handler finishes. If it is not, the code above must take other steps to notify the application that the work could not be performed.

Work items in isolation are self-locking, so you don't need to hold an external lock just to submit or schedule them. Even if you use external state protected by such a lock to prevent further resubmission, it's safe to do the resubmit as long as you're sure that eventually the item will take its lock and check that state to determine whether it should do anything. Where a delayable work item is being rescheduled in its handler due to inability to take the lock some other self-locking state, such as an atomic flag set by the application/driver when the cancel is initiated, would be required to detect the cancellation and avoid the cancelled work item being submitted again after the deadline.

Check Return Values  All work API functions return status of the underlying operation, and in many cases it is important to verify that the intended result was obtained.

- Submitting a work item (`k_work_submit_to_queue()`) can fail if the work is being cancelled or the queue is not accepting new items. If this happens the work will not be executed, which could cause a subsystem that is animated by work handler activity to become non-responsive.

- Asynchronous cancellation (`k_work_cancel()` or `k_work_cancel_delayable()`) can complete while the work item is still being run by a handler. Proceeding to manipulate state shared with the work handler will result in data races that can cause failures.
Many race conditions have been present in Zephyr code because the results of an operation were not checked. There may be good reason to believe that a return value indicating that the operation did not complete as expected is not a problem. In those cases the code should clearly document this, by (1) casting the return value to `void` to indicate that the result is intentionally ignored, and (2) documenting what happens in the unexpected case. For example:

```c
/* If this fails, the work handler will check pub->active and exit without transmitting.
 */
(void)k_work_cancel_delayable(&pub->timer);
```

However in such a case the following code must still avoid data races, as it cannot guarantee that the work thread is not accessing work-related state.

### Don't Optimize Prematurely

The workqueue API is designed to be safe when invoked from multiple threads and interrupts. Attempts to externally inspect a work item’s state and make decisions based on the result are likely to create new problems.

So when new work comes in, just submit it. Don’t attempt to “optimize” by checking whether the work item is already submitted by inspecting snapshot state with `k_work_is_pending()` or `k_work_busy_get()`, or checking for a non-zero delay from `k_work_delayable_remaining_get()`. Those checks are fragile: a “busy” indication can be obsolete by the time the test is returned, and a “not-busy” indication can also be wrong if work is submitted from multiple contexts, or (for delayable work) if the deadline has completed but the work is still in queued or running state.

A general best practice is to always maintain in shared state some condition that can be checked by the handler to confirm whether there is work to be done. This way you can use the work handler as the standard cleanup path: rather than having to deal with cancellation and cleanup at points where items are submitted, you may be able to have everything done in the work handler itself.

A rare case where you could safely use `k_work_is_pending()` is as a check to avoid invoking `k_work_flush()` or `k_work_cancel_sync()`, if you are certain that nothing else might submit the work while you’re checking (generally because you’re holding a lock that prevents access to state used for submission).

### Suggested Uses

Use the system workqueue to defer complex interrupt-related processing from an ISR to a shared thread. This allows the interrupt-related processing to be done promptly without compromising the system's ability to respond to subsequent interrupts, and does not require the application to define and manage an additional thread to do the processing.

### Configuration Options

Related configuration options:

- `CONFIG_SYSTEM_WORKQUEUE_STACK_SIZE`
- `CONFIG_SYSTEM_WORKQUEUE_PRIORITY`
- `CONFIG_SYSTEM_WORKQUEUE_NO_YIELD`

### API Reference

`group workqueue_apis`
Defines

**K_WORK_DELAYABLE_DEFINE**(work, work_handler)

Initialize a statically-defined delayable work item.

This macro can be used to initialize a statically-defined delayable work item, prior to its first use. For example,

```c
static K_WORK_DELAYABLE_DEFINE(<dwork>, <work_handler>);
```

Note that if the runtime dependencies support initialization with `k_work_init_delayable()` using that will eliminate the initialized object in ROM that is produced by this macro and copied in at system startup.

**Parameters**

- **work** – Symbol name for delayable work item object
- **work_handler** – Function to invoke each time work item is processed.

**K_WORK_USER_DEFINE**(work, work_handler)

Initialize a statically-defined user work item.

This macro can be used to initialize a statically-defined user work item, prior to its first use. For example,

```c
static K_WORK_USER_DEFINE(<work>, <work_handler>);
```

**Parameters**

- **work** – Symbol name for work item object
- **work_handler** – Function to invoke each time work item is processed.

**K_WORK_DEFINE**(work, work_handler)

Initialize a statically-defined work item.

This macro can be used to initialize a statically-defined workqueue work item, prior to its first use. For example,

```c
static K_WORK_DEFINE(<work>, <work_handler>);
```

**Parameters**

- **work** – Symbol name for work item object
- **work_handler** – Function to invoke each time work item is processed.

Typedefs

typedef void (*k_work_handler_t)(struct k_work *work)

The signature for a work item handler function.

The function will be invoked by the thread animating a work queue.

**Param work**

the work item that provided the handler.
typedef void (*k_work_user_handler_t)(struct k_work_user *work)

Work item handler function type for user work queues.

A work item's handler function is executed by a user workqueue's thread when the
work item is processed by the workqueue.

**Param work**
Address of the work item.

**Enums**

**Values:**

enumerator K_WORK_RUNNING = BIT(K_WORK_RUNNING_BIT)
Flag indicating a work item that is running under a work queue thread.
Accessed via k_work_busy_get(). May co-occur with other flags.

enumerator K_WORK_CANCELLING = BIT(K_WORK_CANCELLING_BIT)
Flag indicating a work item that is being canceled.
Accessed via k_work_busy_get(). May co-occur with other flags.

enumerator K_WORK_QUEUED = BIT(K_WORK_QUEUED_BIT)
Flag indicating a work item that has been submitted to a queue but has not started
running.
Accessed via k_work_busy_get(). May co-occur with other flags.

enumerator K_WORK_DELAYED = BIT(K_WORK_DELAYED_BIT)
Flag indicating a delayed work item that is scheduled for submission to a queue.
Accessed via k_work_busy_get(). May co-occur with other flags.

enumerator K_WORK_FLUSHING = BIT(K_WORK_FLUSHING_BIT)
Flag indicating a synced work item that is being flushed.
Accessed via k_work_busy_get(). May co-occur with other flags.

**Functions**

void k_work_init(struct k_work *work, k_work_handler_t handler)
Initialize a (non-delayable) work structure.
This must be invoked before submitting a work structure for the first time. It need
not be invoked again on the same work structure. It can be re-invoked to change the
associated handler, but this must be done when the work item is idle.

**Function properties (list may not be complete)**

* isr-ok

**Parameters**
• **work** – the work structure to be initialized.
• **handler** – the handler to be invoked by the work item.

```c
int k_work_busy_get(const struct k_work *work)
```

Busy state flags from the work item.
A zero return value indicates the work item appears to be idle.

**Function properties (list may not be complete)**

* **isr-ok**

**Note:** This is a live snapshot of state, which may change before the result is checked.
Use locks where appropriate.

**Parameters**

• **work** – pointer to the work item.

**Returns**

A mask of flags K_WORK_DELAYED, K_WORK_QUEUED, K_WORK_RUNNING, K_WORK_CANCELING, and K_WORK_FLUSHING.

```c
static inline bool k_work_is_pending(const struct k_work *work)
```

Test whether a work item is currently pending.
Wrapper to determine whether a work item is in a non-idle dstate.

**Function properties (list may not be complete)**

* **isr-ok**

**Note:** This is a live snapshot of state, which may change before the result is checked.
Use locks where appropriate.

**Parameters**

• **work** – pointer to the work item.

**Returns**

true if and only if `k_work_busy_get()` returns a non-zero value.

```c
int k_work_submit_to_queue(struct k_work_q *queue, struct k_work *work)
```

Submit a work item to a queue.

**Function properties (list may not be complete)**

* **isr-ok**

**Parameters**

• **queue** – pointer to the work queue on which the item should run. If NULL
  the queue from the most recent submission will be used.
• **work** – pointer to the work item.

**Return values**

• 0 – if work was already submitted to a queue
• 1 – if work was not submitted and has been queued to queue
• 2 – if work was running and has been queued to the queue that was running it
• -EBUSY –
  – if work submission was rejected because the work item is cancelling; or
  – queue is draining; or
  – queue is plugged.
• -EINVAL – if queue is null and the work item has never been run.
• -ENODEV – if queue has not been started.

```
int k_work_submit(struct k_work *work)
Submit a work item to the system queue.
```

**Function properties (list may not be complete)**

*isr-ok*

**Parameters**

• `work` – pointer to the work item.

**Returns**

as with `k_work_submit_to_queue()`.

```
bool k_work_flush(struct k_work *work, struct k_work_sync *sync)
Wait for last-submitted instance to complete.
```

Resubmissions may occur while waiting, including chained submissions (from within the handler).

**Note:** Be careful of caller and work queue thread relative priority. If this function sleeps it will not return until the work queue thread completes the tasks that allow this thread to resume.

**Note:** Behavior is undefined if this function is invoked on `work` from a work queue running work.

**Parameters**

• `work` – pointer to the work item.

• `sync` – pointer to an opaque item containing state related to the pending cancellation. The object must persist until the call returns, and be accessible from both the caller thread and the work queue thread. The object must not be used for any other flush or cancel operation until this one completes. On architectures with CONFIG_KERNEL_COHERENCE the object must be allocated in coherent memory.

**Return values**

• `true` – if call had to wait for completion
• `false` – if work was already idle
int k_work_cancel(struct k_work *work)
    Cancel a work item.

This attempts to prevent a pending (non-delayable) work item from being processed
by removing it from the work queue. If the item is being processed, the work item will
continue to be processed, but resubmissions are rejected until cancellation completes.
If this returns zero cancellation is complete, otherwise something (probably a work
queue thread) is still referencing the item.
See also k_work_cancel_sync().

Function properties (list may not be complete)
    isr-ok

Parameters
    • work – pointer to the work item.

Returns
    the k_work_busy_get() status indicating the state of the item after all can-
cellation steps performed by this call are completed.

bool k_work_cancel_sync(struct k_work *work, struct k_work_sync *sync)
    Cancel a work item and wait for it to complete.

Same as k_work_cancel() but does not return until cancellation is complete. This can be
invoked by a thread after k_work_cancel() to synchronize with a previous cancellation.
On return the work structure will be idle unless something submits it after the cancel-
lation was complete.

Note: Be careful of caller and work queue thread relative priority. If this function
sleeps it will not return until the work queue thread completes the tasks that allow
this thread to resume.

Note: Behavior is undefined if this function is invoked on work from a work queue
running work.

Parameters
    • work – pointer to the work item.
    • sync – pointer to an opaque item containing state related to the pending
cancellation. The object must persist until the call returns, and be accessible
from both the caller thread and the work queue thread. The object
must not be used for any other flush or cancel operation until this one
completes. On architectures with CONFIG_KERNEL_COHERENCE the ob-
ject must be allocated in coherent memory.

Return values
    • true – if work was pending (call had to wait for cancellation of a run-
ning handler to complete, or scheduled or submitted operations were
cancelled);
    • false – otherwise
void k_work_queue_init(struct k_work_q *queue)
Initialize a work queue structure.

This must be invoked before starting a work queue structure for the first time. It need
not be invoked again on the same work queue structure.

**Function properties (list may not be complete)**

* isr-ok *

**Parameters**

- `queue` – the queue structure to be initialized.

void k_work_queue_start(struct k_work_q *queue, k_thread_stack_t *stack, size_t
stack_size, int prio, const struct k_work_queue_config *cfg)

Initialize a work queue.

This configures the work queue thread and starts it running. The function should not
be re-invoked on a queue.

**Parameters**

- `queue` – pointer to the queue structure. It must be initialized in zeroed/bss
  memory or with `k_work_queue_init` before use.
- `stack` – pointer to the work thread stack area.
- `stack_size` – size of the the work thread stack area, in bytes.
- `prio` – initial thread priority
- `cfg` – optional additional configuration parameters. Pass NULL if not re-
  quired, to use the defaults documented in `k_work_queue_config`.

static inline k_tid_t k_work_queue_thread_get(struct k_work_q *queue)

Access the thread that animates a work queue.

This is necessary to grant a work queue thread access to things the work items it will
process are expected to use.

**Parameters**

- `queue` – pointer to the queue structure.

**Returns**

the thread associated with the work queue.

int k_work_queue_drain(struct k_work_q *queue, bool plug)

Wait until the work queue has drained, optionally plugging it.

This blocks submission to the work queue except when coming from queue thread,
and blocks the caller until no more work items are available in the queue.

If `plug` is true then submission will continue to be blocked after the drain operation
completes until `k_work_queue_unplug()` is invoked.

Note that work items that are delayed are not yet associated with their work queue.
They must be cancelled externally if a goal is to ensure the work queue remains empty.
The `plug` feature can be used to prevent delayed items from being submitted after the
drain completes.

**Parameters**

- `queue` – pointer to the queue structure.
- `plug` – if true the work queue will continue to block new submissions
  after all items have drained.
Return values

- 1 – if call had to wait for the drain to complete
- 0 – if call did not have to wait
- negative – if wait was interrupted or failed

```c
int k_work_queue_unplug(struct k_work_q *queue)
```

Release a work queue to accept new submissions.

This releases the block on new submissions placed when `k_work_queue_drain()` is invoked with the plug option enabled. If this is invoked before the drain completes new items may be submitted as soon as the drain completes.

Function properties (list may not be complete)

- isr-ok

Parameters

- `queue` – pointer to the queue structure.

Return values

- 0 – if successfully unplugged
- -EALREADY – if the work queue was not plugged.

```c
void k_work_init_delayable(struct k_work_delayable *dwork, k_work_handler_t handler)
```

Initialize a delayable work structure.

This must be invoked before scheduling a delayable work structure for the first time. It need not be invoked again on the same work structure. It can be re-invoked to change the associated handler, but this must be done when the work item is idle.

Function properties (list may not be complete)

- isr-ok

Parameters

- `dwork` – the delayable work structure to be initialized.
- `handler` – the handler to be invoked by the work item.

```c
static inline struct k_work_delayable *k_work_delayable_from_work(struct k_work *work)
```

Get the parent delayable work structure from a work pointer.

This function is necessary when a `k_work_handler_t` function is passed to `k_work_schedule_for_queue()` and the handler needs to access data from the container of the containing `k_work_delayable`.

Parameters

- `work` – Address passed to the work handler

Returns

Address of the containing `k_work_delayable` structure.
int k_work_delayable_busy_get(const struct k_work_delayable *dwork)
  Busy state flags from the delayable work item.

**Function properties (list may not be complete)**

*isr-ok*

**Note:** This is a live snapshot of state, which may change before the result can be inspected. Use locks where appropriate.

**Parameters**

- `dwork` – pointer to the delayable work item.

**Returns**

A mask of flags K_WORK_DELAYED, K_WORK_QUEUED, K_WORK_RUNNING, K_WORK_CANCELING, and K_WORK_FLUSHING. A zero return value indicates the work item appears to be idle.

static inline bool k_work_delayable_is_pending(const struct k_work_delayable *dwork)
  Test whether a delayed work item is currently pending.
  Wrapper to determine whether a delayed work item is in a non-idle state.

**Function properties (list may not be complete)**

*isr-ok*

**Note:** This is a live snapshot of state, which may change before the result can be inspected. Use locks where appropriate.

**Parameters**

- `dwork` – pointer to the delayable work item.

**Returns**

true if and only if `k_work_delayable_busy_get()` returns a non-zero value.

static inline k_ticks_t k_work_delayable.expires_get(const struct k_work_delayable *dwork)
  Get the absolute tick count at which a scheduled delayable work will be submitted.

**Function properties (list may not be complete)**

*isr-ok*

**Note:** This is a live snapshot of state, which may change before the result can be inspected. Use locks where appropriate.

**Parameters**

- `dwork` – pointer to the delayable work item.

**Returns**

the tick count when the timer that will schedule the work item will expire, or the current tick count if the work is not scheduled.
static inline k_ticks_t k_work_delayable_remaining_get(const struct k_work_delayable *dwork)

Get the number of ticks until a scheduled delayable work will be submitted.

Function properties (list may not be complete)

isr-ok

Note: This is a live snapshot of state, which may change before the result can be inspected. Use locks where appropriate.

Parameters

• dwork – pointer to the delayable work item.

Returns

the number of ticks until the timer that will schedule the work item will expire, or zero if the item is not scheduled.

int k_work_schedule_for_queue(struct k_work_q *queue, struct k_work_delayable *dwork, k_timeout_t delay)

Submit an idle work item to a queue after a delay.

Unlike k_work_reschedule_for_queue() this is a no-op if the work item is already scheduled or submitted, even if delay is K_NO_WAIT.

Function properties (list may not be complete)

isr-ok

Parameters

• queue – the queue on which the work item should be submitted after the delay.

• dwork – pointer to the delayable work item.

• delay – the time to wait before submitting the work item. If K_NO_WAIT and the work is not pending this is equivalent to k_work_submit_to_queue().

Return values

• 0 – if work was already scheduled or submitted.

• 1 – if work has been scheduled.

• -EBUSY – if delay is K_NO_WAIT and k_work_submit_to_queue() fails with this code.

• -EINVAL – if delay is K_NO_WAIT and k_work_submit_to_queue() fails with this code.

• -ENODEV – if delay is K_NO_WAIT and k_work_submit_to_queue() fails with this code.

int k_work_schedule(struct k_work_delayable *dwork, k_timeout_t delay)

Submit an idle work item to the system work queue after a delay.

This is a thin wrapper around k_work_schedule_for_queue(), with all the API characteristics of that function.

Parameters
• *dwork* – pointer to the delayable work item.
• *delay* – the time to wait before submitting the work item. If K_NO_WAIT this is equivalent to *k_work_submit_to_queue()*.

**Returns**
as with *k_work_schedule_for_queue()*.

```c
int k_work_reschedule_for_queue(struct k_work_q *queue, struct k_work_delayable *dwork, k_timeout_t delay)
```

Reschedule a work item to a queue after a delay.

Unlike *k_work_schedule_for_queue()* this function can change the deadline of a scheduled work item, and will schedule a work item that is in any state (e.g. idle, submitted, or running). This function does not affect (“unsubmit”) a work item that has been submitted to a queue.

**Function properties (list may not be complete)**

`isr-ok`

**Note:** If delay is K_NO_WAIT (“no delay”) the return values are as with *k_work_submit_to_queue()*.

**Parameters**

• *queue* – the queue on which the work item should be submitted after the delay.
• *dwork* – pointer to the delayable work item.
• *delay* – the time to wait before submitting the work item. If K_NO_WAIT this is equivalent to *k_work_submit_to_queue()* after canceling any previous scheduled submission.

**Return values**

• 0 – if delay is K_NO_WAIT and work was already on a queue
• 1 – if
  • delay is K_NO_WAIT and work was not submitted but has now been queued to queue; or
  • delay not K_NO_WAIT and work has been scheduled
• 2 – if delay is K_NO_WAIT and work was running and has been queued to the queue that was running it
• -EBUSY – if delay is K_NO_WAIT and *k_work_submit_to_queue()* fails with this code.
• -EINVAL – if delay is K_NO_WAIT and *k_work_submit_to_queue()* fails with this code.
• -ENODEV – if delay is K_NO_WAIT and *k_work_submit_to_queue()* fails with this code.

```c
int k_work_reschedule(struct k_work_delayable *dwork, k_timeout_t delay)
```

Reschedule a work item to the system work queue after a delay.

This is a thin wrapper around *k_work_reschedule_for_queue()* with all the API characteristics of that function.

**Parameters**
• *dwork* – pointer to the delayable work item.
• *delay* – the time to wait before submitting the work item.

**Returns**

as with \texttt{k_work_reschedule_for_queue()}.  

\begin{verbatim}
bool k_work_flush_delayable(struct k_work_delayable *dwork, struct k_work_sync *sync)
\end{verbatim}

Flush delayable work.  
If the work is scheduled, it is immediately submitted. Then the caller blocks until the work completes, as with \texttt{k_work_flush()}.  

**Note:** Be careful of caller and work queue thread relative priority. If this function sleeps it will not return until the work queue thread completes the tasks that allow this thread to resume.  

**Note:** Behavior is undefined if this function is invoked on \texttt{dwork} from a work queue running \texttt{dwork}.

**Parameters**

• *dwork* – pointer to the delayable work item.
• *sync* – pointer to an opaque item containing state related to the pending cancellation. The object must persist until the call returns, and be accessible from both the caller thread and the work queue thread. The object must not be used for any other flush or cancel operation until this one completes. On architectures with CONFIG_KERNEL_COHERENCE the object must be allocated in coherent memory.

**Return values**

• \texttt{true} – if call had to wait for completion  
• \texttt{false} – if work was already idle

\begin{verbatim}
int k_work_cancel_delayable(struct k_work_delayable *dwork)
\end{verbatim}

Cancel delayable work.  
Similar to \texttt{k_work_cancel()} but for delayable work. If the work is scheduled or submitted it is canceled. This function does not wait for the cancellation to complete.

**Function properties (list may not be complete)**

\begin{itemize}
\item \texttt{isr-ok}
\end{itemize}

**Note:** The work may still be running when this returns. Use \texttt{k_work_flush_delayable()} or \texttt{k_work_cancel_delayable_sync()} to ensure it is not running.

**Note:** Canceling delayable work does not prevent rescheduling it. It does prevent submitting it until the cancellation completes.

**Parameters**

• *dwork* – pointer to the delayable work item.
Returns
the \texttt{k_work_delayable_busy_get()} status indicating the state of the item after all cancellation steps performed by this call are completed.

\begin{verbatim}
bool k_work_cancel_delayable_sync\((\text{struct } k\text{\_work}\_delayable \ast\text{dwork}, \text{struct } k\text{\_work}\_sync \ast\text{sync})\)
\end{verbatim}

Cancel delayable work and wait.
Like \texttt{k_work_cancel_delayable()} but waits until the work becomes idle.

\textbf{Note:} Canceling delayable work does not prevent rescheduling it. It does prevent submitting it until the cancellation completes.

\textbf{Note:} Be careful of caller and work queue thread relative priority. If this function sleeps it will not return until the work queue thread completes the tasks that allow this thread to resume.

\textbf{Note:} Behavior is undefined if this function is invoked on \texttt{dwork} from a work queue running \texttt{dwork}.

\section*{Parameters}

- \texttt{dwork} – pointer to the delayable work item.
- \texttt{sync} – pointer to an opaque item containing state related to the pending cancellation. The object must persist until the call returns, and be accessible from both the caller thread and the work queue thread. The object must not be used for any other flush or cancel operation until this one completes. On architectures with CONFIG_KERNEL_COHERENCE the object must be allocated in coherent memory.

\section*{Return values}

- \texttt{true} – if work was not idle (call had to wait for cancellation of a running handler to complete, or scheduled or submitted operations were cancelled);
- \texttt{false} – otherwise

\section*{Function properties (list may not be complete)}

\begin{verbatim}
static inline void k_work_user_init\((\text{struct } k\text{\_work}\_user \ast\text{work}, k\text{\_work}\_user\_handler_t \text{handler})\)
\end{verbatim}

Initialize a userspace work item.
This routine initializes a user workqueue work item, prior to its first use.

\section*{Parameters}

- \texttt{work} – Address of work item.
- \texttt{handler} – Function to invoke each time work item is processed.

\begin{verbatim}
static inline bool k_work_user_is_pending\((\text{struct } k\text{\_work}\_user \ast\text{work})\)
\end{verbatim}

Check if a userspace work item is pending.
This routine indicates if user work item \texttt{work} is pending in a workqueue's queue.
Note: Checking if the work is pending gives no guarantee that the work will still be pending when this information is used. It is up to the caller to make sure that this information is used in a safe manner.

Parameters
• work – Address of work item.

Returns
true if work item is pending, or false if it is not pending.

static inline int k_work_user_submit_to_queue(struct k_work_user_q *work_q, struct k_work_user *work)
Submit a work item to a user mode workqueue.
Submits a work item to a workqueue that runs in user mode. A temporary memory allocation is made from the caller's resource pool which is freed once the worker thread consumes the k_work item. The workqueue thread must have memory access to the k_work item being submitted. The caller must have permission granted on the work_q parameter's queue object.

Function properties (list may not be complete)
  isr-ok

Parameters
• work_q – Address of workqueue.
• work – Address of work item.

Return values
• -EBUSY – if the work item was already in some workqueue
• -ENOMEM – if no memory for thread resource pool allocation
• 0 – Success

void k_work_user_queue_start(struct k_work_user_q *work_q, k_thread_stack_t *stack, size_t stack_size, int prio, const char *name)
Start a workqueue in user mode.
This works identically to k_work_queue_start() except it is callable from user mode, and the worker thread created will run in user mode. The caller must have permissions granted on both the work_q parameter's thread and queue objects, and the same restrictions on priority apply as k_thread_create().

Parameters
• work_q – Address of workqueue.
• stack – Pointer to work queue thread's stack space, as defined by K_THREAD_STACK_DEFINE()
• stack_size – Size of the work queue thread's stack (in bytes), which should either be the same constant passed to K_THREAD_STACK_DEFINE() or the value of K_THREAD_STACK_SIZEOF().
• prio – Priority of the work queue's thread.
• name – optional thread name. If not null a copy is made into the thread's name buffer.

static inline k_tid_t k_work_user_queue_thread_get(struct k_work_user_q *work_q)
Access the user mode thread that animates a work queue.
This is necessary to grant a user mode work queue thread access to things the work items it will process are expected to use.

Parameters
• work_q – pointer to the user mode queue structure.

Returns
the user mode thread associated with the work queue.

void k_work_poll_init(struct k_work_poll *work, k_work_handler_t handler)
Initialize a triggered work item.
This routine initializes a workqueue triggered work item, prior to its first use.

Parameters
• work – Address of triggered work item.
• handler – Function to invoke each time work item is processed.

int k_work_poll_submit_to_queue(struct k_work_q *work_q, struct k_work_poll *work, struct k_poll_event *events, int num_events, k_timeout_t timeout)
Submit a triggered work item.
This routine schedules work item work to be processed by workqueue work_q when one of the given events is signaled. The routine initiates internal poller for the work item and then returns to the caller. Only when one of the watched events happen the work item is actually submitted to the workqueue and becomes pending.
Submitting a previously submitted triggered work item that is still waiting for the event cancels the existing submission and reschedules it the using the new event list. Note that this behavior is inherently subject to race conditions with the pre-existing triggered work item and work queue, so care must be taken to synchronize such resubmissions externally.

Function properties (list may not be complete)

Warning: Provided array of events as well as a triggered work item must be placed in persistent memory (valid until work handler execution or work cancellation) and cannot be modified after submission.

Parameters
• work_q – Address of workqueue.
• work – Address of delayed work item.
• events – An array of events which trigger the work.
• num_events – The number of events in the array.
• timeout – Timeout after which the work will be scheduled for execution even if not triggered.

Return values
• 0 – Work item started watching for events.
• -EINVAL – Work item is being processed or has completed its work.
• -EADDRINUSE – Work item is pending on a different workqueue.

```c
int k_work_poll_submit(struct k_work_poll *work, struct k_poll_event *events, int num_events, k_timeout_t timeout)
```
Submit a triggered work item to the system workqueue.

This routine schedules work item `work` to be processed by system workqueue when one of the given `events` is signaled. The routine initiates internal poller for the work item and then returns to the caller. Only when one of the watched events happen the work item is actually submitted to the workqueue and becomes pending.

Submitting a previously submitted triggered work item that is still waiting for the event cancels the existing submission and reschedules it the using the new event list. Note that this behavior is inherently subject to race conditions with the pre-existing triggered work item and work queue, so care must be taken to synchronize such resubmissions externally.

**Function properties (list may not be complete)**

`isr-ok`

**Warning:** Provided array of events as well as a triggered work item must not be modified until the item has been processed by the workqueue.

**Parameters**

- `work` – Address of delayed work item.
- `events` – An array of events which trigger the work.
- `num_events` – The number of events in the array.
- `timeout` – Timeout after which the work will be scheduled for execution even if not triggered.

**Return values**

- 0 – Work item started watching for events.
- -EINVAL – Work item is being processed or has completed its work.
- -EADDRINUSE – Work item is pending on a different workqueue.

```c
int k_work_poll_cancel(struct k_work_poll *work)
```
Cancel a triggered work item.

This routine cancels the submission of triggered work item `work`. A triggered work item can only be canceled if no event triggered work submission.

**Function properties (list may not be complete)**

`isr-ok`

**Parameters**

- `work` – Address of delayed work item.

**Return values**

- 0 – Work item canceled.
- **EINVAL** – Work item is being processed or has completed its work.

```c
struct k_work
    #include <kernel.h> A structure used to submit work.
```

```c
struct k_work_delayable
    #include <kernel.h> A structure used to submit work after a delay.
```

```c
struct k_work_sync
    #include <kernel.h> A structure holding internal state for a pending synchronous operation on a work item or queue.

Instances of this type are provided by the caller for invocation of `k_work_flush()`, `k_work_cancel_sync()` and sibling flush and cancel APIs. A referenced object must persist until the call returns, and be accessible from both the caller thread and the work queue thread.

**Note:** If CONFIG_KERNEL_COHERENCE is enabled the object must be allocated in coherent memory; see `arch_mem_coherent()`. The stack on these architectures is generally not coherent, be stack-allocated. Violations are detected by runtime assertion.

```c
struct k_work_queue_config
    #include <kernel.h> A structure holding optional configuration items for a work queue.

This structure, and values it references, are not retained by `k_work_queue_start()`.

**Public Members**

```c
const char *name
    The name to be given to the work queue thread.
    If left null the thread will not have a name.

bool no_yield
    Control whether the work queue thread should yield between items.

Yielding between items helps guarantee the work queue thread does not starve other threads, including cooperative ones released by a work item. This is the default behavior.

Set this to `true` to prevent the work queue thread from yielding between items. This may be appropriate when a sequence of items should complete without yielding control.

```c
struct k_work_q
    #include <kernel.h> A structure used to hold work until it can be processed.
```

**Operation without Threads**

Thread support is not necessary in some applications:

- Bootloaders
Thread support can be disabled by setting \texttt{CONFIG_MULTITHREADING} to \texttt{n}. Since this configuration has a significant impact on Zephyr's functionality and testing of it has been limited, there are conditions on what can be expected to work in this configuration.

**What Can be Expected to Work** These core capabilities shall function correctly when \texttt{CONFIG_MULTITHREADING} is disabled:

- The \texttt{build system}
- The ability to boot the application to \texttt{main()}
- \texttt{Interrupt management}
- The system clock including \texttt{k_uptime_get()}
- Timers, i.e. \texttt{k_timer()}
- Non-sleeping delays e.g. \texttt{k_busy_wait()}
- Sleeping \texttt{k_cpu_idle()}
- Pre \texttt{main()} drivers and subsystems initialization e.g. \texttt{SYS_INIT}

**Memory Management**
- Specifically identified drivers in certain subsystems, listed below.

The expectations above affect selection of other features; for example \texttt{CONFIG_SYS_CLOCK_EXISTS} cannot be set to \texttt{n}.

**What Cannot be Expected to Work** Functionality that will not work with \texttt{CONFIG_MULTITHREADING} includes majority of the kernel API:

- \texttt{Threads}
- \texttt{Scheduling}
- \texttt{Workqueue Threads}
- \texttt{Polling API}
- \texttt{Semaphores}
- \texttt{Mutexes}
- \texttt{Condition Variables}
- \texttt{Data Passing}

**Subsystem Behavior Without Thread Support** The sections below list driver and functional subsystems that are expected to work to some degree when \texttt{CONFIG_MULTITHREADING} is disabled. Subsystems that are not listed here should not be expected to work.

Some existing drivers within the listed subsystems do not work when threading is disabled, but are within scope based on their subsystem, or may be sufficiently isolated that supporting them on a particular platform is low-impact. Enhancements to add support to existing capabilities that were not originally implemented to work with threads disabled will be considered.

**Flash** The \texttt{Flash} is expected to work for all SoC flash peripheral drivers. Bus-accessed devices like serial memories may not be supported.

*List/table of supported drivers to go here*
**GPIO**  The *General-Purpose Input/Output (GPIO)* is expected to work for all SoC GPIO peripheral drivers. Bus-accessed devices like GPIO extenders may not be supported.

*List/table of supported drivers to go here*

**UART**  A subset of the *Universal Asynchronous Receiver-Transmitter (UART)* is expected to work for all SoC UART peripheral drivers.

- Applications that select `CONFIG_UART_INTERRUPT_DRIVEN` may work, depending on driver implementation.
- Applications that select `CONFIG_UART_ASYNC_API` may work, depending on driver implementation.
- Applications that do not select either `CONFIG_UART_ASYNC_API` or `CONFIG_UART_INTERRUPT_DRIVEN` are expected to work.

*List/table of supported drivers to go here, including which API options are supported*

**Interrupts**

An *interrupt service routine* (ISR) is a function that executes asynchronously in response to a hardware or software interrupt. An ISR normally preempts the execution of the current thread, allowing the response to occur with very low overhead. Thread execution resumes only once all ISR work has been completed.

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**Concepts**  Any number of ISRs can be defined (limited only by available RAM), subject to the constraints imposed by underlying hardware.

An ISR has the following key properties:

- An *interrupt request (IRQ) signal* that triggers the ISR.
- A *priority level* associated with the IRQ.
- An *interrupt service routine* that is invoked to handle the interrupt.
An argument value that is passed to that function.

An IDT (Interrupt Descriptor Table) or a vector table is used to associate a given interrupt source with a given ISR. Only a single ISR can be associated with a specific IRQ at any given time.

Multiple ISRs can utilize the same function to process interrupts, allowing a single function to service a device that generates multiple types of interrupts or to service multiple devices (usually of the same type). The argument value passed to an ISR's function allows the function to determine which interrupt has been signaled.

The kernel provides a default ISR for all unused IDT entries. This ISR generates a fatal system error if an unexpected interrupt is signaled.

The kernel supports interrupt nesting. This allows an ISR to be preempted in mid-execution if a higher priority interrupt is signaled. The lower priority ISR resumes execution once the higher priority ISR has completed its processing.

An ISR executes in the kernel's interrupt context. This context has its own dedicated stack area (or, on some architectures, stack areas). The size of the interrupt context stack must be capable of handling the execution of multiple concurrent ISRs if interrupt nesting support is enabled.

Important: Many kernel APIs can be used only by threads, and not by ISRs. In cases where a routine may be invoked by both threads and ISRs the kernel provides the \texttt{k_is_in_isr()} API to allow the routine to alter its behavior depending on whether it is executing as part of a thread or as part of an ISR.

Multi-level Interrupt Handling A hardware platform can support more interrupt lines than natively-provided through the use of one or more nested interrupt controllers. Sources of hardware interrupts are combined into one line that is then routed to the parent controller.

If nested interrupt controllers are supported, \texttt{CONFIG_MULTI_LEVEL_INTERRUPTS} should be enabled, and \texttt{CONFIG_2ND_LEVEL_INTERRUPTS} and \texttt{CONFIG_3RD_LEVEL_INTERRUPTS} configured as well, based on the hardware architecture.

A unique 32-bit interrupt number is assigned with information embedded in it to select and invoke the correct Interrupt Service Routine (ISR). Each interrupt level is given a byte within this 32-bit number, providing support for up to four interrupt levels using this arch, as illustrated and explained below:

| 9 | 2 | 0 |   |
| --- | --- | --- | --- | (LEVEL 1) |
| 5 | A |   |   |
| C | B |   |   |
| D |   |   |   |

There are three interrupt levels shown here.

- ‘-’ means interrupt line and is numbered from 0 (right most).
- LEVEL 1 has 12 interrupt lines, with two lines (2 and 9) connected to nested controllers and one device ‘A’ on line 4.
- One of the LEVEL 2 controllers has interrupt line 5 connected to a LEVEL 3 nested controller and one device ‘C’ on line 3.
- The other LEVEL 2 controller has no nested controllers but has one device ‘B’ on line 2.
- The LEVEL 3 controller has one device ‘D’ on line 2.

Here’s how unique interrupt numbers are generated for each hardware interrupt. Let’s consider four interrupts shown above as A, B, C, and D:
**Note:** The bit positions for LEVEL 2 and onward are offset by 1, as 0 means that interrupt number is not present for that level. For our example, the LEVEL 3 controller has device D on line 2, connected to the LEVEL 2 controller's line 5, that is connected to the LEVEL 1 controller's line 9 (2 -> 5 -> 9). Because of the encoding offset for LEVEL 2 and onward, device D is given the number 0x00030609.

---

**Preventing Interruptions** In certain situations it may be necessary for the current thread to prevent ISRs from executing while it is performing time-sensitive or critical section operations. A thread may temporarily prevent all IRQ handling in the system using an **IRQ lock**. This lock can be applied even when it is already in effect, so routines can use it without having to know if it is already in effect. The thread must unlock its IRQ lock the same number of times it was locked before interrupts can be once again processed by the kernel while the thread is running.

**Important:** The IRQ lock is thread-specific. If thread A locks out interrupts then performs an operation that puts itself to sleep (e.g. sleeping for N milliseconds), the thread's IRQ lock no longer applies once thread A is swapped out and the next ready thread B starts to run.

This means that interrupts can be processed while thread B is running unless thread B has also locked out interrupts using its own IRQ lock. (Whether interrupts can be processed while the kernel is switching between two threads that are using the IRQ lock is architecture-specific.)

When thread A eventually becomes the current thread once again, the kernel re-establishes thread A's IRQ lock. This ensures thread A won't be interrupted until it has explicitly unlocked its IRQ lock.

If thread A does not sleep but does make a higher-priority thread B ready, the IRQ lock will inhibit any preemption that would otherwise occur. Thread B will not run until the next reschedule point reached after releasing the IRQ lock.

Alternatively, a thread may temporarily **disable** a specified IRQ so its associated ISR does not execute when the IRQ is signaled. The IRQ must be subsequently **enabled** to permit the ISR to execute.

**Important:** Disabling an IRQ prevents all threads in the system from being preempted by the associated ISR, not just the thread that disabled the IRQ.

---

**Zero Latency Interrupts** Preventing interruptions by applying an IRQ lock may increase the observed interrupt latency. A high interrupt latency, however, may not be acceptable for certain low-latency use-cases.

The kernel addresses such use-cases by allowing interrupts with critical latency constraints to execute at a priority level that cannot be blocked by interrupt locking. These interrupts are defined as **zero-latency interrupts**. The support for zero-latency interrupts requires CONFIG_ZERO_LATENCY_IRQS to be enabled. In addition to that, the flag IRQ_ZERO_LATENCY must be passed to IRQ_CONNECT or IRQ_DIRECT_CONNECT macros to configure the particular interrupt with zero latency.

Zero-latency interrupts are expected to be used to manage hardware events directly, and not to interoperate with the kernel code at all. They should treat all kernel APIs as undefined behavior.
Zero-latency interrupts may not modify any data inspected by kernel APIs invoked from normal Zephyr contexts and shall not generate exceptions that need to be handled synchronously (e.g., kernel panic).

**Important:** Zero-latency interrupts are supported on an architecture-specific basis. The feature is currently implemented in the ARM Cortex-M architecture variant.

### Offloading ISR Work

An ISR should execute quickly to ensure predictable system operation. If time-consuming processing is required, the ISR should offload some or all processing to a thread, thereby restoring the kernel's ability to respond to other interrupts.

The kernel supports several mechanisms for offloading interrupt-related processing to a thread:

- An ISR can signal a helper thread to do interrupt-related processing using a kernel object, such as a FIFO, LIFO, or semaphore.
- An ISR can instruct the system workqueue thread to execute a work item. (See [Workqueue Threads](#).)

When an ISR offloads work to a thread, there is typically a single context switch to that thread when the ISR completes, allowing interrupt-related processing to continue almost immediately. However, depending on the priority of the thread handling the offload, it is possible that the currently executing cooperative thread or other higher-priority threads may execute before the thread handling the offload is scheduled.

### Sharing interrupt lines

In the case of some hardware platforms, the same interrupt lines may be used by different IPs. For example, interrupt 17 may be used by a DMA controller to signal that a data transfer has been completed or by a DAI controller to signal that the transfer FIFO has reached its watermark. To make this work, one would have to either employ some special logic or find a workaround (for example, using the shared_irq interrupt controller), which doesn't scale very well.

To solve this problem, one may use shared interrupts, which can be enabled using `CONFIG_SHARED_INTERRUPTS`. Whenever an attempt to register a second ISR/argument pair on the same interrupt line is made (using `IRQ_CONNECT` or `irq_connect_dynamic()`), the interrupt line will become shared, meaning the two ISR/argument pairs (previous one and the one that has just been registered) will be invoked each time the interrupt is triggered. The entities that make use of an interrupt line in the shared interrupt context are known as clients. The maximum number of allowed clients for an interrupt is controlled by `CONFIG_SHARED_IRQ_MAX_NUM_CLIENTS`.

Interrupt sharing is transparent to the user. As such, the user may register interrupts using `IRQ_CONNECT` and `irq_connect_dynamic()` as they normally would. The interrupt sharing is taken care of behind the scenes.

Enabling the shared interrupt support and dynamic interrupt support will allow users to dynamically disconnect ISRs using `irq_disconnect_dynamic()`. After an ISR is disconnected, whenever the interrupt line for which it was registered gets triggered, the ISR will no longer get invoked.

Please note that enabling `CONFIG_SHARED_INTERRUPTS` will result in a non-negligible increase in the binary size. Use with caution.

### Implementation

#### Defining a regular ISR

An ISR is defined at runtime by calling `IRQ_CONNECT`. It must then be enabled by calling `irq_enable()`.
**Important:** IRQ_CONNECT() is not a C function and does some inline assembly magic behind the scenes. All its arguments must be known at build time. Drivers that have multiple instances may need to define per-instance config functions to configure each instance of the interrupt.

The following code defines and enables an ISR.

```c
#define MY_DEV_IRQ 24 /* device uses IRQ 24 */
#define MY_DEV_PRIO 2 /* device uses interrupt priority 2 */
/* argument passed to my_isr(), in this case a pointer to the device */
#define MY_ISR_ARG DEVICE_GET(my_device)
#define MY_IRQ_FLAGS 0 /* IRQ flags */

void my_isr(void *arg)
{
    ... /* ISR code */
}

void my_isr_installer(void)
{
    ...
    IRQ_CONNECT(MY_DEV_IRQ, MY_DEV_PRIO, my_isr, MY_ISR_ARG, MY_IRQ_FLAGS);
    irq_enable(MY_DEV_IRQ);
    ...
}
```

Since the `IRQ_CONNECT` macro requires that all its parameters be known at build time, in some cases this may not be acceptable. It is also possible to install interrupts at runtime with `irq_connect_dynamic()`. It is used in exactly the same way as `IRQ_CONNECT`:

```c
void my_isr_installer(void)
{
    ...  
    irq_connect_dynamic(MY_DEV_IRQ, MY_DEV_PRIO, my_isr, MY_ISR_ARG, MY_IRQ_FLAGS);
    irq_enable(MY_DEV_IRQ);
    ...
}
```

Dynamic interrupts require the `CONFIG_DYNAMIC_INTERRUPTS` option to be enabled. Removing or re-configuring a dynamic interrupt is currently unsupported.

**Defining a ‘direct’ ISR** Regular Zephyr interrupts introduce some overhead which may be unacceptable for some low-latency use-cases. Specifically:

- The argument to the ISR is retrieved and passed to the ISR
- If power management is enabled and the system was idle, all the hardware will be resumed from low-power state before the ISR is executed, which can be very time-consuming
- Although some architectures will do this in hardware, other architectures need to switch to the interrupt stack in code
- After the interrupt is serviced, the OS then performs some logic to potentially make a scheduling decision.

Zephyr supports so-called ‘direct’ interrupts, which are installed via `IRQ_DIRECT_CONNECT`. These direct interrupts have some special implementation requirements and a reduced feature set; see the definition of `IRQ_DIRECT_CONNECT` for details.

The following code demonstrates a direct ISR:
Installation of dynamic direct interrupts is supported on an architecture-specific basis. (The feature is currently implemented in ARM Cortex-M architecture variant. Dynamic direct interrupts feature is exposed to the user via an ARM-only API)

Sharing an interrupt line

The same restrictions regarding `IRQ_CONNECT` described in Defining a regular ISR are applicable here. If `CONFIG_SHARED_INTERRUPTS` is disabled, the above code will generate a build error. Otherwise, the above code will result in the two ISRs being invoked each time interrupt 24 is triggered.

If `CONFIG_SHARED_IRQ_MAX_NUM_CLIENTS` is set to a value lower than 2 (current number of clients), a build error will be generated.

If dynamic interrupts are enabled, `irq_connect_dynamic()` will allow sharing interrupts during
runtime. Exceeding the configured maximum number of allowed clients will result in a failed assertion.

**Dynamically disconnecting an ISR** The following code defines two ISRs using the same interrupt number. The second ISR is disconnected during runtime.

```c
#define MY_DEV_IRQ 24 /* device uses INTID 24 */
#define MY_DEV_IRQ_PRIO 2 /* device uses interrupt priority 2 */
/* this argument may be anything */
#define MY_FST_ISR_ARG INT_TO_POINTER(1)
/* this argument may be anything */
#define MY_SND_ISR_ARG INT_TO_POINTER(2)
#define MY_IRQ_FLAGS 0 /* IRQ flags */

void my_first_isr(void *arg)
{
    /* some magic happens here */
}

void my_second_isr(void *arg)
{
    /* even more magic happens here */
}

void my_isr_installer(void)
{
    ...
    IRQ_CONNECT(MY_DEV_IRQ, MY_DEV_IRQ_PRIO, my_first_isr, MY_FST_ISR_ARG, MY_IRQ_FLAGS);
    IRQ_CONNECT(MY_DEV_IRQ, MY_DEV_IRQ_PRIO, my_second_isr, MY_SND_ISR_ARG, MY_IRQ_FLAGS);
    ...
}

void my_isr_uninstaller(void)
{
    ...
    irq_disconnect_dynamic(MY_DEV_IRQ, MY_DEV_IRQ_PRIO, my_first_isr, MY_FST_ISR_ARG, MY_IRQ_FLAGS);
    ...
}
```

The `irq_disconnect_dynamic()` call will result in interrupt 24 becoming unshared, meaning the system will act as if the first `IRQ_CONNECT` call never happened. This behaviour is only allowed if CONFIG_DYNAMIC_INTERRUPTS is enabled, otherwise a linker error will be generated.

**Implementation Details** Interrupt tables are set up at build time using some special build tools. The details laid out here apply to all architectures except x86, which are covered in the `x86 Details` section below.

The invocation of `IRQ_CONNECT` will declare an instance of `struct isr_list` which is placed in a special `.intList` section. This section is placed in compiled code on precompilation stages only. It is meant to be used by Zephyr script to generate interrupt tables and is removed from the final build. The script implements different parsers to process the data from `.intList` section and produce the required output.

The default parser generates C arrays filled with arguments and interrupt handlers in a form of addresses directly taken from `.intList` section entries. It works with all the architectures and compilers (with the exception mentioned above). The limitation of this parser is the fact that after the arrays are generated it is expected for the code not to relocate. Any relocation on this stage may lead to the situation where the entry in the interrupt array is no longer pointing to the
function that was expected. It means that this parser, being more compatible is limiting us from using Link Time Optimization.

The local isr declaration parser uses different approach to construct the same arrays at binary level. All the entries to the arrays are declared and defined locally, directly in the file where `IRQ_CONNECT` is used. They are placed in a section with the unique, synthetized name. The name of the section is then placed in .intList section and it is used to create linker script to properly place the created entry in the right place in the memory. This parser is now limited to the supported architectures and toolchains but in reward it keeps the information about object relations for linker thus allowing the Link Time Optimization.

**Implementation using C arrays**  This is the default configuration available for all Zephyr supported architectures.

Any invocation of `IRQ_CONNECT` will declare an instance of struct `_isr_list` which is placed in a special .intList section:

```c
struct _isr_list {
    /**< IRQ line number */
    int32_t irq;
    /**< Flags for this IRQ, see ISR_FLAG_* definitions */
    int32_t flags;
    /**< ISR to call */
    void *func;
    /**< Parameter for non-direct IRQs */
    void *param;
};
```

Zephyr is built in two phases; the first phase of the build produces `${ZEPHYR_PREBUILT_EXECUTABLE}.elf` which contains all the entries in the .intList section preceded by a header:

```c
struct {
    void *spurious_irq_handler;
    void *sw_irq_handler;
    uint32_t num_isrs;
    uint32_t num_vectors;
    struct _isr_list isrs[]; <- of size num_isrs
};
```

This data consisting of the header and instances of struct `_isr_list` inside `${ZEPHYR_PREBUILT_EXECUTABLE}.elf` is then used by the gen_isr_tables.py script to generate a C file defining a vector table and software ISR table that are then compiled and linked into the final application.

The priority level of any interrupt is not encoded in these tables, instead `IRQ_CONNECT` also has a runtime component which programs the desired priority level of the interrupt to the interrupt controller. Some architectures do not support the notion of interrupt priority, in which case the priority argument is ignored.

**Vector Table**  A vector table is generated when `CONFIG_GEN_IRQ_VECTOR_TABLE` is enabled. This data structure is used natively by the CPU and is simply an array of function pointers, where each element n corresponds to the IRQ handler for IRQ line n, and the function pointers are:

1. For ‘direct’ interrupts declared with `IRQ_DIRECT_CONNECT`, the handler function will be placed here.
2. For regular interrupts declared with `IRQ_CONNECT`, the address of the common software IRQ handler is placed here. This code does common kernel interrupt bookkeeping and looks up the ISR and parameter from the software ISR table.
3. For interrupt lines that are not configured at all, the address of the spurious IRQ handler will be placed here. The spurious IRQ handler causes a system fatal error if encountered.

Some architectures (such as the Nios II internal interrupt controller) have a common entry point for all interrupts and do not support a vector table, in which case the CONFIG_GEN_IRQ_VECTOR_TABLE option should be disabled.

Some architectures may reserve some initial vectors for system exceptions and declare this in a table elsewhere, in which case CONFIG_GEN_IRQ_START_VECTOR needs to be set to properly offset the indices in the table.

**SW ISR Table**  This is an array of struct _isr_table_entry:

```c
struct _isr_table_entry {
  void *arg;
  void (*isr)(void *);
};
```

This is used by the common software IRQ handler to look up the ISR and its argument and execute it. The active IRQ line is looked up in an interrupt controller register and used to index this table.

**Shared SW ISR Table**  This is an array of struct z_shared_isr_table_entry:

```c
struct z_shared_isr_table_entry {
  struct _isr_table_entry clients[CONFIG_SHARED_IRQ_MAX_NUM_CLIENTS];
  size_t client_num;
};
```

This table keeps track of the registered clients for each of the interrupt lines. Whenever an interrupt line becomes shared, `z_shared_isr()` will replace the currently registered ISR in _sw_isr_table. This special ISR will iterate through the list of registered clients and invoke the ISRs.

**Implementation using linker script**  This way of prepare and parse .isrList section to implement interrupt vectors arrays is called local isr declaration. The name comes from the fact that all the entries to the arrays that would create interrupt vectors are created locally in place of invocation of IRQ_CONNECT macro. Then automatically generated linker scripts are used to place it in the right place in the memory.

This option requires enabling by the choice of ISR_TABLES_LOCAL_DECLARATION. If this configuration is supported by the used architecture and toolchain the ISR_TABLES_LOCAL_DECLARATION_SUPPORTED is set. See details of this option for the information about currently supported configurations.

Any invocation of IRQ_CONNECT or IRQ_DIRECT_CONNECT will declare an instance of struct _isr_list_sname which is placed in a special .intList section:

```c
struct _isr_list_sname {
  /** IRQ line number */
  int32_t irq;
  /** Flags for this IRQ, see ISR_FLAG_* definitions */
  int32_t flags;
  /** The section name */
  const char sname[];
};
```

Note that the section name is placed in flexible array member. It means that the size of the initialized structure will wary depending on the structure name length. The whole entry is used by the script during the build of the application and has all the information needed for proper interrupt placement.
Beside of the _isr_list_sname the **IRQ_CONNECT** macro generates an entry that would be the part of the interrupt array:

```c
struct _isr_table_entry {
    const void *arg;
    void (*isr)(const void *);
};
```

This array is placed in a section with the name saved in _isr_list_sname structure.

The values created by **IRQ_DIRECT_CONNECT** macro depends on the architecture. It can be changed to variable that points to a interrupt handler:

```c
static uintptr_t <unique name> = ((uintptr_t)func);
```

Or to actual naked function that implements a jump to the interrupt handler:

```c
static void <unique name>(void)
{
    __asm(ARCH_IRQ_VECTOR_JUMP_CODE(func));
}
```

Similar like for **IRQ_CONNECT**, the created variable or function is placed in a section, saved in _isr_list_sname section.

**Files generated by the script**  The interrupt tables generator script creates 3 files: isr_tables.c, isr_tables_swi.ld, and isr_tables_vt.ld.

The isr_tables.c will contain all the structures for interrupts, direct interrupts and shared interrupts (if enabled). This file implements only all the structures that are not implemented by the application, leaving a comment where the interrupt not implemented here can be found.

Then two linker files are used. The isr_tables_vt.ld file is included in place where the interrupt vectors are required to be placed in the selected architecture. The isr_tables_swi.ld file describes the placement of the software interrupt table elements. The separated file is required as it might be placed in writable on nonwritable section, depending on the current configuration.

**x86 Details**  The x86 architecture has a special type of vector table called the Interrupt Descriptor Table (IDT) which must be laid out in a certain way per the x86 processor documentation. It is still fundamentally a vector table, and the arch/x86/gen_idt.py tool uses the .intList section to create it. However, on APIC-based systems the indexes in the vector table do not correspond to the IRQ line. The first 32 vectors are reserved for CPU exceptions, and all remaining vectors (up to index 255) correspond to the priority level, in groups of 16. In this scheme, interrupts of priority level 0 will be placed in vectors 32-47, level 1 48-63, and so forth. When the arch/x86/gen_idt.py tool is constructing the IDT, when it configures an interrupt it will look for a free vector in the appropriate range for the requested priority level and set the handler there.

On x86 when an interrupt or exception vector is executed by the CPU, there is no foolproof way to determine which vector was fired, so a software ISR table indexed by IRQ line is not used. Instead, the **IRQ_CONNECT** call creates a small assembly language function which calls the common interrupt code in _interrupt_enter() with the ISR and parameter as arguments. It is the address of this assembly interrupt stub which gets placed in the IDT. For interrupts declared with **IRQ_DIRECT_CONNECT** the parameterless ISR is placed directly in the IDT.

On systems where the position in the vector table corresponds to the interrupt's priority level, the interrupt controller needs to know at runtime what vector is associated with an IRQ line. arch/x86/gen_idt.py additionally creates an _irq_to_interrupt_vector array which maps an IRQ line to its configured vector in the IDT. This is used at runtime by **IRQ_CONNECT** to program the IRQ-to-vector association in the interrupt controller.
For dynamic interrupts, the build must generate some 4-byte dynamic interrupt stubs, one stub per dynamic interrupt in use. The number of stubs is controlled by the CONFIG_X86_DYNAMIC_IRQ_STUBS option. Each stub pushes an unique identifier which is then used to fetch the appropriate handler function and parameter out of a table populated when the dynamic interrupt was connected.

**Going Beyond the Default Supported Number of Interrupts** When generating interrupts in the multi-level configuration, 8-bits per level is the default mask used when determining which level a given interrupt code belongs to. This can become a problem when dealing with CPUs that support more than 255 interrupts per single aggregator. In this case it may be desirable to override these defaults and use a custom number of bits per level. Regardless of how many bits used for each level, the sum of the total bits used between all levels must sum to be less than or equal to 32-bits, fitting into a single 32-bit integer. To modify the bit total per level, override the default 8 in Kconfig.multilevel by setting CONFIG_1ST_LEVEL_INTERRUPT_BITS for the first level, CONFIG_2ND_LEVEL_INTERRUPT_BITS for the second level and CONFIG_3RD_LEVEL_INTERRUPT_BITS for the third level. These masks control the length of the bit masks and shift to apply when generating interrupt values, when checking the interrupts level and converting interrupts to a different level. The logic controlling this can be found in irq_multilevel.h

**Suggested Uses** Use a regular or direct ISR to perform interrupt processing that requires a very rapid response, and can be done quickly without blocking.

**Note:** Interrupt processing that is time consuming, or involves blocking, should be handed off to a thread. See *Offloading ISR Work* for a description of various techniques that can be used in an application.

**Configuration Options** Related configuration options:
- CONFIG_ISR_STACK_SIZE

Additional architecture-specific and device-specific configuration options also exist.

**API Reference**

group isr_apis

**Defines**

IRQ_CONNECT(irq_p, priority_p, isr_p, isr_param_p, flags_p)

Initialize an interrupt handler.

This routine initializes an interrupt handler for an IRQ. The IRQ must be subsequently enabled before the interrupt handler begins servicing interrupts.

**Warning:** Although this routine is invoked at run-time, all of its arguments must be computable by the compiler at build time.

**Parameters**

- irq_p – IRQ line number.
- priority_p – Interrupt priority.
• isr_p – Address of interrupt service routine.
• isr_param_p – Parameter passed to interrupt service routine.
• flags_p – Architecture-specific IRQ configuration flags.

`IRQ_DIRECT_CONNECT(irq_p, priority_p, isr_p, flags_p)`

Initialize a 'direct' interrupt handler.

This routine initializes an interrupt handler for an IRQ. The IRQ must be subsequently enabled via `irq_enable()` before the interrupt handler begins servicing interrupts.

These ISRs are designed for performance-critical interrupt handling and do not go through common interrupt handling code. They must be implemented in such a way that it is safe to put them directly in the vector table. For ISRs written in C, the `ISR_DIRECT_DECLARE()` macro will do this automatically. For ISRs written in assembly it is entirely up to the developer to ensure that the right steps are taken.

This type of interrupt currently has a few limitations compared to normal Zephyr interrupts:

• No parameters are passed to the ISR.
• No stack switch is done, the ISR will run on the interrupted context's stack, unless the architecture automatically does the stack switch in HW.
• Interrupt locking state is unchanged from how the HW sets it when the ISR runs. On arches that enter ISRs with interrupts locked, they will remain locked.
• Scheduling decisions are now optional, controlled by the return value of ISRs implemented with the `ISR_DIRECT_DECLARE()` macro
• The call into the OS to exit power management idle state is now optional. Normal interrupts always do this before the ISR is run, but when it runs is now controlled by the placement of a `ISR_DIRECT_PM()` macro, or omitted entirely.

**Warning:** Although this routine is invoked at run-time, all of its arguments must be computable by the compiler at build time.

**Parameters**

• irq_p – IRQ line number.
• priority_p – Interrupt priority.
• isr_p – Address of interrupt service routine.
• flags_p – Architecture-specific IRQ configuration flags.

`ISR_DIRECT_HEADER()`

Common tasks before executing the body of an ISR.

This macro must be at the beginning of all direct interrupts and performs minimal architecture-specific tasks before the ISR itself can run. It takes no arguments and has no return value.

`ISR_DIRECT_FOOTER(check_reschedule)`

Common tasks before exiting the body of an ISR.

This macro must be at the end of all direct interrupts and performs minimal architecture-specific tasks like EOI. It has no return value.

In a normal interrupt, a check is done at end of interrupt to invoke `z_swap()` logic if the current thread is preemptible and there is another thread ready to run in the kernel's ready queue cache. This is now optional and controlled by the check_reschedule
argument. If unsure, set to nonzero. On systems that do stack switching and nested interrupt tracking in software, z_swap() should only be called if this was a non-nested interrupt.

**Parameters**

- **check_reschedule** – If nonzero, additionally invoke scheduling logic

**ISR_DIRECT_PM()**

Perform power management idle exit logic.

This macro may optionally be invoked somewhere in between IRQ_DIRECT_HEADER() and IRQ_DIRECT_FOOTER() invocations. It performs tasks necessary to exit power management idle state. It takes no parameters and returns no arguments. It may be omitted, but be careful!

**ISR_DIRECT_DECLARE**(name)

Helper macro to declare a direct interrupt service routine.

This will declare the function in a proper way and automatically include the ISR_DIRECT_FOOTER() and ISR_DIRECT_HEADER() macros. The function should return nonzero status if a scheduling decision should potentially be made. See ISR_DIRECT_FOOTER() for more details on the scheduling decision.

For architectures that support ‘regular’ and ‘fast’ interrupt types, where these interrupt types require different assembly language handling of registers by the ISR, this will always generate code for the ‘fast’ interrupt type.

Example usage:

```c
ISR_DIRECT_DECLARE(my_isr)
{
    bool done = do_stuff();
    ISR_DIRECT_PM(); // done after do_stuff() due to latency concerns
    if (!done) {
        return 0; // don't bother checking if we have to z_swap()
    }

    k_sem_give(some_sem);
    return 1;
}
```

**Parameters**

- **name** – symbol name of the ISR

**irq_lock()**

Lock interrupts.

This routine disables all interrupts on the CPU. It returns an unsigned integer “lock-out key”, which is an architecture-dependent indicator of whether interrupts were locked prior to the call. The lock-out key must be passed to irq_unlock() to re-enable interrupts.

This routine can be called recursively, as long as the caller keeps track of each lock-out key that is generated. Interrupts are re-enabled by passing each of the keys to irq_unlock() in the reverse order they were acquired. (That is, each call to irq_lock() must be balanced by a corresponding call to irq_unlock().)

This routine can only be invoked from supervisor mode. Some architectures (for example, ARM) will fail silently if invoked from user mode instead of generating an exception.
Note: This routine must also serve as a memory barrier to ensure the uniprocessor implementation of `k_spinlock_t` is correct.

Note: This routine can be called by ISRs or by threads. If it is called by a thread, the interrupt lock is thread-specific; this means that interrupts remain disabled only while the thread is running. If the thread performs an operation that allows another thread to run (for example, giving a semaphore or sleeping for N milliseconds), the interrupt lock no longer applies and interrupts may be re-enabled while other processing occurs. When the thread once again becomes the current thread, the kernel re-establishes its interrupt lock; this ensures the thread won’t be interrupted until it has explicitly released the interrupt lock it established.

Warning: The lock-out key should never be used to manually re-enable interrupts or to inspect or manipulate the contents of the CPU’s interrupt bits.

Returns

An architecture-dependent lock-out key representing the “interrupt disable state” prior to the call.

```c
irq_unlock(key)
```

Unlock interrupts.

This routine reverses the effect of a previous call to `irq_lock()` using the associated lock-out key. The caller must call the routine once for each time it called `irq_lock()`, supplying the keys in the reverse order they were acquired, before interrupts are enabled.

This routine can only be invoked from supervisor mode. Some architectures (for example, ARM) will fail silently if invoked from user mode instead of generating an exception.

Note: This routine must also serve as a memory barrier to ensure the uniprocessor implementation of `k_spinlock_t` is correct.

Note: Can be called by ISRs.

Parameters

- key – Lock-out key generated by `irq_lock()`.

```c
irq_enable(irq)
```

Enable an IRQ.

This routine enables interrupts from source `irq`.

Parameters

- irq – IRQ line.

```c
irq_disable(irq)
```

Disable an IRQ.

This routine disables interrupts from source `irq`.
Parameters

- irq – IRQ line.

`irq_is_enabled(irq)`

Get IRQ enable state.

This routine indicates if interrupts from source `irq` are enabled.

**Parameters**

- irq – IRQ line.

**Returns**

interrupt enable state, true or false

Functions

static inline int `irq_connect_dynamic(unsigned int irq, unsigned int priority, void (*routine)(const void *parameter), const void *parameter, uint32_t flags)`

Configure a dynamic interrupt.

Use this instead of `IRQ_CONNECT()` if arguments cannot be known at build time.

**Parameters**

- irq – IRQ line number
- priority – Interrupt priority
- routine – Interrupt service routine
- parameter – ISR parameter
- flags – Arch-specific IRQ configuration flags

**Returns**

The vector assigned to this interrupt

static inline int `irq_disconnect_dynamic(unsigned int irq, unsigned int priority, void (*routine)(const void *parameter), const void *parameter, uint32_t flags)`

Disconnect a dynamic interrupt.

Use this in conjunction with shared interrupts to remove a routine/parameter pair from the list of clients using the same interrupt line. If the interrupt is not being shared then the associated _sw_isr_table entry will be replaced by (NULL, z_irq_spurious) (default entry).

**Parameters**

- irq – IRQ line number
- priority – Interrupt priority
- routine – Interrupt service routine
- parameter – ISR parameter
- flags – Arch-specific IRQ configuration flags

**Returns**

0 in case of success, negative value otherwise
bool k_is_in_isr(void)
Determine if code is running at interrupt level.
This routine allows the caller to customize its actions, depending on whether it is a
thread or an ISR.

Function properties (list may not be complete)

isr-ok

Returns
false if invoked by a thread.

Returns
ture if invoked by an ISR.

int k_is_preempt_thread(void)
Determine if code is running in a preemptible thread.
This routine allows the caller to customize its actions, depending on whether it can be
preempted by another thread. The routine returns a ‘true’ value if all of the following
conditions are met:

- The code is running in a thread, not at ISR.
- The thread’s priority is in the preemptible range.
- The thread has not locked the scheduler.

Function properties (list may not be complete)

isr-ok

Returns
0 if invoked by an ISR or by a cooperative thread.

Returns
Non-zero if invoked by a preemptible thread.

static inline bool k_is_pre_kernel(void)
Test whether startup is in the before-main-task phase.
This routine allows the caller to customize its actions, depending on whether it being
invoked before the kernel is fully active.

Function properties (list may not be complete)

isr-ok

Returns
true if invoked before post-kernel initialization

Returns
false if invoked during/after post-kernel initialization

Polling API

The polling API is used to wait concurrently for any one of multiple conditions to be fulfilled.

Concepts  The polling API's main function is `k_poll()`, which is very similar in concept to the POSIX `poll()` function, except that it operates on kernel objects rather than on file descriptors.

The polling API allows a single thread to wait concurrently for one or more conditions to be fulfilled without actively looking at each one individually.

There is a limited set of such conditions:

- a semaphore becomes available
- a kernel FIFO contains data ready to be retrieved
- a kernel message queue contains data ready to be retrieved
- a kernel pipe contains data ready to be retrieved
- a poll signal is raised

A thread that wants to wait on multiple conditions must define an array of poll events, one for each condition.

All events in the array must be initialized before the array can be polled on.

Each event must specify which type of condition must be satisfied so that its state is changed to signal the requested condition has been met.

Each event must specify what kernel object it wants the condition to be satisfied.

Each event must specify which mode of operation is used when the condition is satisfied.

Each event can optionally specify a tag to group multiple events together, to the user's discretion.

Apart from the kernel objects, there is also a poll signal pseudo-object type that be directly signaled.

The `k_poll()` function returns as soon as one of the conditions it is waiting for is fulfilled. It is possible for more than one to be fulfilled when `k_poll()` returns, if they were fulfilled before `k_poll()` was called, or due to the preemptive multi-threading nature of the kernel. The caller must look at the state of all the poll events in the array to figure out which ones were fulfilled and what actions to take.

Currently, there is only one mode of operation available: the object is not acquired. As an example, this means that when `k_poll()` returns and the poll event states that the semaphore is available, the caller of `k_poll()` must then invoke `k_sem_take()` to take ownership of the semaphore. If the semaphore is contested, there is no guarantee that it will be still available when `k_sem_take()` is called.

Implementation
Using `k_poll()` The main API is `k_poll()`, which operates on an array of poll events of type `k_poll_event`. Each entry in the array represents one event a call to `k_poll()` will wait for its condition to be fulfilled.

Poll events can be initialized using either the runtime initializers `K_POLL_EVENT_INITIALIZER()` or `k_poll_event_init()`, or the static initializer `K_POLL_EVENT_STATIC_INITIALIZER()`. An object that matches the `type` specified must be passed to the initializers. The `mode` must be set to `K_POLL_MODE_NOTIFY_ONLY`. The state must be set to `K_POLL_STATE_NOT_READY` (the initializers take care of this). The user `tag` is optional and completely opaque to the API: it is there to help a user to group similar events together. Being optional, it is passed to the static initializer, but not the runtime ones for performance reasons. If using runtime initializers, the user must set it separately in the `k_poll_event` data structure. If an event in the array is to be ignored, most likely temporarily, its type can be set to `K_POLL_TYPE_IGNORE`.

```c
struct k_poll_event events[4] = {
    K_POLL_EVENT_STATIC_INITIALIZER(K_POLL_TYPE_SEM_AVAILABLE, K_POLL_MODE_NOTIFY_ONLY, &my_sem, 0),
    K_POLL_EVENT_STATIC_INITIALIZER(K_POLL_TYPE_FIFO_DATA_AVAILABLE, K_POLL_MODE_NOTIFY_ONLY, &my_fifo, 0),
    K_POLL_EVENT_STATIC_INITIALIZER(K_POLL_TYPE_MSGQ_DATA_AVAILABLE, K_POLL_MODE_NOTIFY_ONLY, &my_msgq, 0),
    K_POLL_EVENT_STATIC_INITIALIZER(K_POLL_TYPE_PIPE_DATA_AVAILABLE, K_POLL_MODE_NOTIFY_ONLY, &my_pipe, 0),
};
```

or at runtime

```c
struct k_poll_event events[4];
void some_init(void)
{
    k_poll_event_init(&events[0], K_POLL_TYPE_SEM_AVAILABLE, K_POLL_MODE_NOTIFY_ONLY, &my_sem);
    k_poll_event_init(&events[1], K_POLL_TYPE_FIFO_DATA_AVAILABLE, K_POLL_MODE_NOTIFY_ONLY, &my_fifo);
    k_poll_event_init(&events[2], K_POLL_TYPE_MSGQ_DATA_AVAILABLE, K_POLL_MODE_NOTIFY_ONLY, &my_msgq);
    k_poll_event_init(&events[3], K_POLL_TYPE_PIPE_DATA_AVAILABLE, K_POLL_MODE_NOTIFY_ONLY, &my_pipe);

    // tags are left uninitialized if unused
}
```

After the events are initialized, the array can be passed to `k_poll()`. A timeout can be specified to wait only for a specified amount of time, or the special values `K_NO_WAIT` and `K_FOREVER` to either not wait or wait until an event condition is satisfied and not sooner.

A list of pollers is offered on each semaphore or FIFO and as many events can wait in it as the app wants. Notice that the waiters will be served in first-come-first-serve order, not in priority order.
In case of success, \texttt{k\_poll()} returns 0. If it times out, it returns \texttt{-EAGAIN}. 

```c
void do_stuff(void)
{
    rc = k_poll(events, 2, 1000);
    if (rc == 0) {
        if (events[0].state == K_POLL_STATE_SEM_AVAILABLE) {
            k_sem_take(events[0].sem, 0);
        } else if (events[1].state == K_POLL_STATE_FIFO_DATA_AVAILABLE) {
            data = k_fifo_get(events[1].fifo, 0);
            // handle data
        } else if (events[2].state == K_POLL_STATE_MSGQ_DATA_AVAILABLE) {
            ret = k_msgq_get(events[2].msgq, buf, K_NO_WAIT);
            // handle data
        } else if (events[3].state == K_POLL_STATE_PIPE_DATA_AVAILABLE) {
            ret = k_pipe_get(events[3].pipe, buf, bytes_to_read, &bytes_read, min_xfer, K_NO_WAIT);
            // handle data
        }
    } else {  // handle timeout
    }
}
```

When \texttt{k\_poll()} is called in a loop, the events state must be reset to \texttt{K\_POLL\_STATE\_NOT\_READY} by the user:

```c
void do_stuff(void)
{
    for(;;) {
        rc = k_poll(events, 2, K_FOREVER);
        if (events[0].state == K_POLL_STATE_SEM_AVAILABLE) {
            k_sem_take(events[0].sem, 0);
        } else if (events[1].state == K_POLL_STATE_FIFO_DATA_AVAILABLE) {
            data = k_fifo_get(events[1].fifo, 0);
            // handle data
        } else if (events[2].state == K_POLL_STATE_MSGQ_DATA_AVAILABLE) {
            ret = k_msgq_get(events[2].msgq, buf, K_NO_WAIT);
            // handle data
        } else if (events[3].state == K_POLL_STATE_PIPE_DATA_AVAILABLE) {
            ret = k_pipe_get(events[3].pipe, buf, bytes_to_read, &bytes_read, min_xfer, K_NO_WAIT);
            // handle data
        }
        events[0].state = K_POLL_STATE_NOT_READY;
        events[1].state = K_POLL_STATE_NOT_READY;
        events[2].state = K_POLL_STATE_NOT_READY;
        events[3].state = K_POLL_STATE_NOT_READY;
    }
}
```

\textbf{Using \texttt{k\_poll\_signal\_raise()}} One of the types of events is \texttt{K\_POLL\_TYPE\_SIGNAL}: this is a “direct” signal to a poll event. This can be seen as a lightweight binary semaphore only one thread can wait for.

A poll signal is a separate object of type \texttt{k\_poll\_signal} that must be attached to a \texttt{k\_poll\_event}, similar to a semaphore or FIFO. It must first be initialized either via \texttt{K\_POLL\_SIGNAL\_INITIALIZER()} or \texttt{k\_poll\_signal\_init()}. 

3.1. Kernel Services
struct k_poll_signal signal;
void do_stuff(void)
{
    k_poll_signal_init(&signal);
}

It is signaled via the \texttt{k_poll_signal_raise()} function. This function takes a user \texttt{result} parameter that is opaque to the API and can be used to pass extra information to the thread waiting on the event.

struct k_poll_signal signal;

// thread A
void do_stuff(void)
{
    k_poll_signal_init(&signal);
    
    struct k_poll_event events[1] = {
        K_POLL_EVENT_INITIALIZER(K_POLL_TYPE_SIGNAL,
                                K_POLL_MODE_NOTIFY_ONLY,
                                &signal),
    };
    
    k_poll(events, 1, K_FOREVER);
    
    if (events.signal->result == 0x1337) {
        // A-OK!
    } else {
        // weird error
    }

// thread B
void signal_do_stuff(void)
{
    k_poll_signal_raise(&signal, 0x1337);
}

If the signal is to be polled in a loop, both its event state and its \texttt{signaled} field \textit{must} be reset on each iteration if it has been signaled.

struct k_poll_signal signal;
void do_stuff(void)
{
    k_poll_signal_init(&signal);
    
    struct k_poll_event events[1] = {
        K_POLL_EVENT_INITIALIZER(K_POLL_TYPE_SIGNAL,
                                K_POLL_MODE_NOTIFY_ONLY,
                                &signal),
    };

    for (;;) {
        k_poll(events, 1, K_FOREVER);
        
        if (events[0].signal->result == 0x1337) {
            // A-OK!
        } else {
            // weird error
        }

        events[0].signal->signaled = 0;
    }

(continues on next page)
events[0].state = K_POLL_STATE_NOT_READY;
}
}

Note that poll signals are not internally synchronized. A \texttt{k.poll()} call that is passed a signal will return after any code in the system calls \texttt{k.poll_signal_raise()}. But if the signal is being externally managed and reset via \texttt{k.poll_signal_init()}, it is possible that by the time the application checks, the event state may no longer be equal to \texttt{K_POLL_STATE_SIGNAL}, and a (naive) application will miss events. Best practice is always to reset the signal only from within the thread invoking the \texttt{k.poll()} loop, or else to use some other event type which tracks event counts: semaphores and FIFOs are more error-proof in this sense because they can’t “miss” events, architecturally.

**Suggested Uses**  Use \texttt{k.poll()} to consolidate multiple threads that would be pending on one object each, saving possibly large amounts of stack space.

Use a poll signal as a lightweight binary semaphore if only one thread pends on it.

**Note:** Because objects are only signaled if no other thread is waiting for them to become available and only one thread can poll on a specific object, polling is best used when objects are not subject of contention between multiple threads, basically when a single thread operates as a main “server” or “dispatcher” for multiple objects and is the only one trying to acquire these objects.

**Configuration Options**  Related configuration options:

- \texttt{CONFIG_POLL}

**API Reference**

\texttt{group poll_apis}

**Defines**

\texttt{K_POLL_TYPE_IGNORE}

\texttt{K_POLL_TYPE_SIGNAL}

\texttt{K_POLL_TYPE_SEM_AVAILABLE}

\texttt{K_POLL_TYPE_DATA_AVAILABLE}

\texttt{K_POLL_TYPE_FIFO_DATA_AVAILABLE}

\texttt{K_POLL_TYPE.MSGQ_DATA_AVAILABLE}

\texttt{K_POLL_TYPE.PIPE_DATA_AVAILABLE}
K_POLL_STATE_NOT_READY
K_POLL_STATE_SIGNAL
K_POLL_STATE_SEM_AVAILABLE
K_POLL_STATE_DATA_AVAILABLE
K_POLL_STATE_FIFO_DATA_AVAILABLE
K_POLL_STATE_MSGQ_DATAAVAILABLE
K_POLL_STATE_PIPE_DATA_AVAILABLE
K_POLL_STATE_CANCELLED
K_POLL_SIGNAL_INITIALIZER(obj)
K_POLL_EVENT_INITIALIZER(_event_type, _event_mode, _event_obj)
K_POLL_EVENT_STATIC_INITIALIZER(_event_type, _event_mode, _event_obj, event_tag)

Enums

enum k_poll_modes

   Values:

   enumerator K_POLL_MODE_NOTIFY_ONLY = 0

   enumerator K_POLL_NUM_MODES

Functions

void k_poll_event_init(struct k_poll_event *event, uint32_t type, int mode, void *obj)

Initialize one struct k_poll_event instance.

After this routine is called on a poll event, the event it ready to be placed in an event
array to be passed to k_poll().

Parameters

   • event – The event to initialize.
   • type – A bitfield of the types of event, from the K_POLL_TYPE_xxx val-
     ues. Only values that apply to the same object being polled can be used
together. Choosing K_POLL_TYPE_IGNORE disables the event.
   • mode – Future. Use K_POLL_MODE_NOTIFY_ONLY.
   • obj – Kernel object or poll signal.
int k_poll(struct k_poll_event *events, int num_events, k_timeout_t timeout)

Wait for one or many of multiple poll events to occur.

This routine allows a thread to wait concurrently for one or many of multiple poll events to have occurred. Such events can be a kernel object being available, like a semaphore, or a poll signal event.

When an event notifies that a kernel object is available, the kernel object is not “given” to the thread calling `k_poll()`: it merely signals the fact that the object was available when the `k_poll()` call was in effect. Also, all threads trying to acquire an object the regular way, i.e. by pending on the object, have precedence over the thread polling on the object. This means that the polling thread will never get the poll event on an object until the object becomes available and its pend queue is empty. For this reason, the `k_poll()` call is more effective when the objects being polled only have one thread, the polling thread, trying to acquire them.

When `k_poll()` returns 0, the caller should loop on all the events that were passed to `k_poll()` and check the state field for the values that were expected and take the associated actions.

Before being reused for another call to `k_poll()`, the user has to reset the state field to K_POLL_STATE_NOT_READY.

When called from user mode, a temporary memory allocation is required from the caller’s resource pool.

**Parameters**

- **events** – An array of events to be polled for.
- **num_events** – The number of events in the array.
- **timeout** – Waiting period for an event to be ready, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**

- 0 – One or more events are ready.
- -EAGAIN – Waiting period timed out.
- -EINTR – Polling has been interrupted, e.g. with `k_queue_cancel_wait()`. All output events are still set and valid, cancelled event(s) will be set to K_POLL_STATE_CANCELLED. In other words, -EINTR status means that at least one of output events is K_POLL_STATE_CANCELLED.
- -ENOMEM – Thread resource pool insufficient memory (user mode only)
- -EINVAL – Bad parameters (user mode only)

```c
void k_poll_signal_init(struct k_poll_signal *sig)

Initialize a poll signal object.

Ready a poll signal object to be signaled via `k_poll_signal_raise()`.

**Parameters**

- **sig** – A poll signal.

```c
void k_poll_signal_reset(struct k_poll_signal *sig)

```c
void k_poll_signal_check(struct k_poll_signal *sig, unsigned int *signaled, int *result)

Fetch the signaled state and result value of a poll signal.

**Parameters**

- **sig** – A poll signal object
• **signaled** – An integer buffer which will be written nonzero if the object was signaled
• **result** – An integer destination buffer which will be written with the result value if the object was signaled, or an undefined value if it was not.

```c
int k_poll_signal_raise(struct k_poll_signal *sig, int result)
```

Signal a poll signal object.

This routine makes ready a poll signal, which is basically a poll event of type K_POLL_TYPE_SIGNAL. If a thread was polling on that event, it will be made ready to run. A `result` value can be specified.

The poll signal contains a ‘signaled’ field that, when set by `k_poll_signal_raise()`, stays set until the user sets it back to 0 with `k_poll_signal_reset()`. It thus has to be reset by the user before being passed again to `k_poll()` or `k_poll()` will consider it being signaled, and will return immediately.

**Note:** The result is stored and the ‘signaled’ field is set even if this function returns an error indicating that an expiring poll was not notified. The next `k_poll()` will detect the missed raise.

**Parameters**
- **sig** – A poll signal.
- **result** – The value to store in the result field of the signal.

**Return values**
- **0** – The signal was delivered successfully.
- **-EAGAIN** – The polling thread’s timeout is in the process of expiring.

```c
struct k_poll_signal
#include <kernel.h>
```

**Public Members**

```c
sys_dlist_t poll_events
PRIVATE - DO NOT TOUCH.
```

```c
unsigned int signaled
1 if the event has been signaled, 0 otherwise.
Stays set to 1 until user resets it to 0.
```

```c
int result
custom result value passed to k_poll_signal_raise() if needed
```

```c
struct k_poll_event
#include <kernel.h> Poll Event.
```
Public Members

```c
struct z_poller *poller
    PRIVATE - DO NOT TOUCH.
```

```c
uint32_t tag
    optional user-specified tag, opaque, untouched by the API
```

```c
uint32_t type
    bitfield of event types (bitwise-ORed K_POLL_TYPE_xxx values)
```

```c
uint32_t state
    bitfield of event states (bitwise-ORed K_POLL_STATE_xxx values)
```

```c
uint32_t mode
    mode of operation, from enum k_poll_modes
```

```c
uint32_t unused
    unused bits in 32-bit word
```

```c
union k_poll_event
    per-type data
```

Semaphores

A `semaphore` is a kernel object that implements a traditional counting semaphore.

- **Concepts**
- **Implementation**
  - Defining a Semaphore
  - Giving a Semaphore
  - Taking a Semaphore
- **Suggested Uses**
- **Configuration Options**
- **API Reference**
- **User Mode Semaphore API Reference**

**Concepts** Any number of semaphores can be defined (limited only by available RAM). Each semaphore is referenced by its memory address.

A semaphore has the following key properties:

- A **count** that indicates the number of times the semaphore can be taken. A count of zero indicates that the semaphore is unavailable.
- A **limit** that indicates the maximum value the semaphore's count can reach.
A semaphore must be initialized before it can be used. Its count must be set to a non-negative value that is less than or equal to its limit.

A semaphore may be **given** by a thread or an ISR. Giving the semaphore increments its count, unless the count is already equal to the limit.

A semaphore may be **taken** by a thread. Taking the semaphore decrements its count, unless the semaphore is unavailable (i.e. at zero). When a semaphore is unavailable a thread may choose to wait for it to be given. Any number of threads may wait on an unavailable semaphore simultaneously. When the semaphore is given, it is taken by the highest priority thread that has waited longest.

**Note:** You may initialize a “full” semaphore (count equal to limit) to limit the number of threads able to execute the critical section at the same time. You may also initialize an empty semaphore (count equal to 0, with a limit greater than 0) to create a gate through which no waiting thread may pass until the semaphore is incremented. All standard use cases of the common semaphore are supported.

**Note:** The kernel does allow an ISR to take a semaphore, however the ISR must not attempt to wait if the semaphore is unavailable.

### Implementation

**Defining a Semaphore**  A semaphore is defined using a variable of type `k_sem`. It must then be initialized by calling `k_sem_init()`.

The following code defines a semaphore, then configures it as a binary semaphore by setting its count to 0 and its limit to 1.

```c
struct k_sem my_sem;
k_sem_init(&my_sem, 0, 1);
```

Alternatively, a semaphore can be defined and initialized at compile time by calling `K_SEM_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_SEM_DEFINE(my_sem, 0, 1);
```

**Giving a Semaphore**  A semaphore is given by calling `k_sem_give()`.

The following code builds on the example above, and gives the semaphore to indicate that a unit of data is available for processing by a consumer thread.

```c
void input_data_interrupt_handler(void *arg)
{
    /* notify thread that data is available */
    k_sem_give(&my_sem);
    ...
}
```
Taking a Semaphore  A semaphore is taken by calling `k_sem_take()`.

The following code builds on the example above, and waits up to 50 milliseconds for the semaphore to be given. A warning is issued if the semaphore is not obtained in time.

```c
void consumer_thread(void)
{
    ...
    if (k_sem_take(&my_sem, K_MSEC(50)) ! = 0) {
        printk("Input data not available!");
    } else {
        /* fetch available data */
    }
    ...
}
```

Suggested Uses  Use a semaphore to control access to a set of resources by multiple threads.

Use a semaphore to synchronize processing between a producing and consuming threads or ISRs.

Configuration Options  Related configuration options:

• None.

API Reference  Related code samples  Basic Synchronization  Manipulate basic kernel synchronization primitives.

```c
group semaphore_apis

Defines

K_SEM_MAX_LIMIT
Maximum limit value allowed for a semaphore.
This is intended for use when a semaphore does not have an explicit maximum limit, and instead is just used for counting purposes.

K_SEM_DEFINE(name, initial_count, count_limit)
Statically define and initialize a semaphore.
The semaphore can be accessed outside the module where it is defined using:

```c
extern struct k_sem <name>;
```

Parameters

• name – Name of the semaphore.
• initial_count – Initial semaphore count.
• count_limit – Maximum permitted semaphore count.
Functions

```c
int k_sem_init(struct k_sem *sem, unsigned int initial_count, unsigned int limit)
```
Initialize a semaphore.
This routine initializes a semaphore object, prior to its first use.

**See also:**

*K_SEM_MAX_LIMIT*

**Parameters**
- `sem` – Address of the semaphore.
- `initial_count` – Initial semaphore count.
- `limit` – Maximum permitted semaphore count.

**Return values**
- `0` – Semaphore created successfully
- `-EINVAL` – Invalid values

```c
int k_sem_take(struct k_sem *sem, k_timeout_t timeout)
```
Take a semaphore.
This routine takes `sem`.

**Function properties (list may not be complete)**

`isr-ok`

**Note:** `timeout` must be set to K_NO_WAIT if called from ISR.

**Parameters**
- `sem` – Address of the semaphore.
- `timeout` – Waiting period to take the semaphore, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**
- `0` – Semaphore taken.
- `-EBUSY` – Returned without waiting.
- `-EAGAIN` – Waiting period timed out, or the semaphore was reset during the waiting period.

```c
void k_sem_give(struct k_sem *sem)
```
Give a semaphore.
This routine gives `sem`, unless the semaphore is already at its maximum permitted count.

**Function properties (list may not be complete)**

`isr-ok`

**Parameters**
void \texttt{k\_sem\_reset} (\texttt{struct k\_sem *sem})
\begin{quote}
Resets a semaphore's count to zero.
\end{quote}
This routine sets the count of \textit{sem} to zero. Any outstanding semaphore takes will be aborted with \texttt{-EAGAIN}.

\textbf{Parameters}
\begin{itemize}
  \item \texttt{sem} – Address of the semaphore.
\end{itemize}

unsigned int \texttt{k\_sem\_count\_get} (\texttt{struct k\_sem *sem})
\begin{quote}
Get a semaphore's count.
\end{quote}
This routine returns the current count of \textit{sem}.

\textbf{Parameters}
\begin{itemize}
  \item \texttt{sem} – Address of the semaphore.
\end{itemize}

\textbf{Returns}
Current semaphore count.

\textbf{User Mode Semaphore API Reference} The \texttt{sys\_sem} exists in user memory working as counter semaphore for user mode thread when user mode enabled. When user mode isn't enabled, \texttt{sys\_sem} behaves like \texttt{k\_sem}.

\section*{group user\_semaphore\_apis}

\textbf{Defines}

\texttt{SYS\_SEM\_DEFINE\!(\_name, \_initial\_count, \_count\_limit)}
\begin{quote}
Statically define and initialize a \texttt{sys\_sem}.
\end{quote}
The semaphore can be accessed outside the module where it is defined using:

\begin{verbatim}
extern struct sys\_sem \texttt{name};
\end{verbatim}

Route this to memory domains using \texttt{K\_APP\_DMEM}().

\textbf{Parameters}
\begin{itemize}
  \item \texttt{_name} – Name of the semaphore.
  \item \texttt{_initial\_count} – Initial semaphore count.
  \item \texttt{_count\_limit} – Maximum permitted semaphore count.
\end{itemize}

\textbf{Functions}

\texttt{int sys\_sem\_init\!(\texttt{struct sys\_sem *sem, unsigned int initial\_count, unsigned int limit})}
\begin{quote}
Initialize a semaphore.
\end{quote}
This routine initializes a semaphore instance, prior to its first use.

\textbf{Parameters}
\begin{itemize}
  \item \texttt{sem} – Address of the semaphore.
  \item \texttt{initial\_count} – Initial semaphore count.
  \item \texttt{limit} – Maximum permitted semaphore count.
\end{itemize}
Return values
• 0 – Initial success.
• -EINVAL – Bad parameters, the value of limit should be located in (0, INT_MAX] and initial_count shouldn’t be greater than limit.

int sys_sem_give(struct sys_sem *sem)
Give a semaphore.
This routine gives _sem_, unless the semaphore is already at its maximum permitted count.

Parameters
• _sem_ – Address of the semaphore.

Return values
• 0 – Semaphore given.
• -EINVAL – Parameter address not recognized.
• -EACCES – Caller does not have enough access.
• -EAGAIN – Count reached Maximum permitted count and try again.

int sys_sem_take(struct sys_sem *sem, _k_timeout_t_ timeout)
Take a sys_sem.
This routine takes _sem_.

Parameters
• _sem_ – Address of the sys_sem.
• _timeout_ – Waiting period to take the sys_sem, or one of the special values _K_NO_WAIT_ and _K_FOREVER_.

Return values
• 0 – sys_sem taken.
• -EINVAL – Parameter address not recognized.
• -ETIMEDOUT – Waiting period timed out.
• -EACCES – Caller does not have enough access.

unsigned int sys_sem_count_get(struct sys_sem *sem)
Get sys_sem’s value.
This routine returns the current value of _sem_.

Parameters
• _sem_ – Address of the sys_sem.

Returns
Current value of sys_sem.

Mutexes

A mutex is a kernel object that implements a traditional reentrant mutex. A mutex allows multiple threads to safely share an associated hardware or software resource by ensuring mutually exclusive access to the resource.
Concepts  Any number of mutexes can be defined (limited only by available RAM). Each mutex is referenced by its memory address.

A mutex has the following key properties:

- A **lock count** that indicates the number of times the mutex has been locked by the thread that has locked it. A count of zero indicates that the mutex is unlocked.

- An **owning thread** that identifies the thread that has locked the mutex, when it is locked.

A mutex must be initialized before it can be used. This sets its lock count to zero.

A thread that needs to use a shared resource must first gain exclusive rights to access it by **locking** the associated mutex. If the mutex is already locked by another thread, the requesting thread may choose to wait for the mutex to be unlocked.

After locking a mutex, the thread may safely use the associated resource for as long as needed; however, it is considered good practice to hold the lock for as short a time as possible to avoid negatively impacting other threads that want to use the resource. When the thread no longer needs the resource it must **unlock** the mutex to allow other threads to use the resource.

Any number of threads may wait on a locked mutex simultaneously. When the mutex becomes unlocked it is then locked by the highest-priority thread that has waited the longest.

**Note:** Mutex objects are not designed for use by ISRs.

**Reentrant Locking**  A thread is permitted to lock a mutex it has already locked. This allows the thread to access the associated resource at a point in its execution when the mutex may or may not already be locked.

A mutex that is repeatedly locked by a thread must be unlocked an equal number of times before the mutex becomes fully unlocked so it can be claimed by another thread.

**Priority Inheritance**  The thread that has locked a mutex is eligible for *priority inheritance*. This means the kernel will temporarily elevate the thread’s priority if a higher priority thread begins waiting on the mutex. This allows the owning thread to complete its work and release the mutex more rapidly by executing at the same priority as the waiting thread. Once the mutex...
has been unlocked, the unlocking thread resets its priority to the level it had before locking that mutex.

**Note:** The CONFIG_PRIORITY_CEILING configuration option limits how high the kernel can raise a thread's priority due to priority inheritance. The default value of 0 permits unlimited elevation.

The owning thread's base priority is saved in the mutex when it obtains the lock. Each time a higher priority thread waits on a mutex, the kernel adjusts the owning thread's priority. When the owning thread releases the lock (or if the high priority waiting thread times out), the kernel restores the thread's base priority from the value saved in the mutex.

This works well for priority inheritance as long as only one locked mutex is involved. However, if multiple mutexes are involved, sub-optimal behavior will be observed if the mutexes are not unlocked in the reverse order in which the owning thread's priority was previously raised. Consequently it is recommended that a thread lock only a single mutex at a time when multiple mutexes are shared between threads of different priorities.

**Implementation**

**Defining a Mutex** A mutex is defined using a variable of type `k_mutex`. It must then be initialized by calling `k_mutex_init()`.

The following code defines and initializes a mutex.

```c
struct k_mutex my_mutex;
k_mutex_init(&my_mutex);
```

Alternatively, a mutex can be defined and initialized at compile time by calling `K_MUTEX_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_MUTEX_DEFINE(my_mutex);
```

**Locking a Mutex** A mutex is locked by calling `k_mutex_lock()`.

The following code builds on the example above, and waits indefinitely for the mutex to become available if it is already locked by another thread.

```c
k_mutex_lock(&my_mutex, K_FOREVER);
```

The following code waits up to 100 milliseconds for the mutex to become available, and gives a warning if the mutex does not become available.

```c
if (k_mutex_lock(&my_mutex, K_MSEC(100)) == 0) {
  /* mutex successfully locked */
} else {
  printf("Cannot lock XYZ display\n");
}
```

**Unlocking a Mutex** A mutex is unlocked by calling `k_mutex_unlock()`.

The following code builds on the example above, and unlocks the mutex that was previously locked by the thread.

```c
k_mutex_unlock(&my_mutex);
```
**Suggested Uses**  Use a mutex to provide exclusive access to a resource, such as a physical device.

**Configuration Options**  Related configuration options:
- CONFIG_PRIORITY_CEILING

**API Reference**

*group* mutex_apis

**Defines**

**K_MUTEX_DEFINE(name)**

Statically define and initialize a mutex.

The mutex can be accessed outside the module where it is defined using:

```c
extern struct k_mutex <name> ;
```

**Parameters**
- **name** – Name of the mutex.

**Functions**

**int k_mutex_init(struct k_mutex *mutex)**

Initialize a mutex.

This routine initializes a mutex object, prior to its first use.

Upon completion, the mutex is available and does not have an owner.

**Parameters**
- **mutex** – Address of the mutex.

**Return values**
- 0 – Mutex object created

**int k_mutex_lock(struct k_mutex *mutex, k_timeout_t timeout)**

Lock a mutex.

This routine locks `mutex`. If the mutex is locked by another thread, the calling thread waits until the mutex becomes available or until a timeout occurs.

A thread is permitted to lock a mutex it has already locked. The operation completes immediately and the lock count is increased by 1.

Mutexes may not be locked in ISRs.

**Parameters**
- **mutex** – Address of the mutex.
- **timeout** – Waiting period to lock the mutex, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**
- 0 – Mutex locked.
- -EBUSY – Returned without waiting.
• -EAGAIN – Waiting period timed out.

int k_mutex_unlock(struct k_mutex *mutex)
Unlock a mutex.

This routine unlocks mutex. The mutex must already be locked by the calling thread. The mutex cannot be claimed by another thread until it has been unlocked by the calling thread as many times as it was previously locked by that thread.

Mutexes may not be unlocked in ISRs, as mutexes must only be manipulated in thread context due to ownership and priority inheritance semantics.

Parameters
• mutex – Address of the mutex.

Return values
• 0 – Mutex unlocked.
• -EPERM – The current thread does not own the mutex
• -EINVAL – The mutex is not locked

struct k_mutex
#include <kernel.h> Mutex Structure.

Public Members

_wait_q_t wait_q
Mutex wait queue.

struct k_thread *owner
Mutex owner.

uint32_t lock_count
Current lock count.

int owner_orig_prio
Original thread priority.

Futex API Reference k_futex is a lightweight mutual exclusion primitive designed to minimize kernel involvement. Uncontended operation relies only on atomic access to shared memory. k_futex are tracked as kernel objects and can live in user memory so that any access bypasses the kernel object permission management mechanism.

group futex_apis

Functions

int k_futex_wait(struct k_futex *futex, int expected, k_timeout_t timeout)
Pend the current thread on a futex.

Tests that the supplied futex contains the expected value, and if so, goes to sleep until some other thread calls k_futex_wake() on it.
Parameters

- **futex** – Address of the futex.
- **expected** – Expected value of the futex, if it is different the caller will not wait on it.
- **timeout** – Non-negative waiting period on the futex, or one of the special values K_NO_WAIT or K_FOREVER.

Return values

- **-EACCES** – Caller does not have read access to futex address.
- **-EAGAIN** – If the futex value did not match the expected parameter.
- **-EINVAL** – Futex parameter address not recognized by the kernel.
- **-ETIMEDOUT** – Thread woke up due to timeout and not a futex wakeup.
- **0** – if the caller went to sleep and was woken up. The caller should check the futex's value on wakeup to determine if it needs to block again.

```c
int k_futex_wake(struct k_futex *futex, bool wake_all)
```

Wake one/all threads pending on a futex.

Wake up the highest priority thread pending on the supplied futex, or wakeup all the threads pending on the supplied futex, and the behavior depends on `wake_all`.

Parameters

- **futex** – Futex to wake up pending threads.
- **wake_all** – If true, wake up all pending threads; If false, wakeup the highest priority thread.

Return values

- **-EACCES** – Caller does not have access to the futex address.
- **-EINVAL** – Futex parameter address not recognized by the kernel.
- **Number** – of threads that were woken up.

**User Mode Mutex API Reference** sys_mutex behaves almost exactly like k_mutex, with the added advantage that a sys_mutex instance can reside in user memory. When user mode isn't enabled, sys_mutex behaves like k_mutex.

```c
SYS_MUTEX_DEFINE(name)
```

Statically define and initialize a sys_mutex.

The mutex can be accessed outside the module where it is defined using:

```c
extern struct sys_mutex <name>;
```

Route this to memory domains using K_APP_DMEM().

Parameters

- **name** – Name of the mutex.

3.1. Kernel Services
Functions

static inline void sys_mutex_init(struct sys_mutex *mutex)
Initialize a mutex.
This routine initializes a mutex object, prior to its first use.
Upon completion, the mutex is available and does not have an owner.
This routine is only necessary to call when userspace is disabled and the mutex was
not created with SYS_MUTEX_DEFINE().

Parameters

• mutex – Address of the mutex.

static inline int sys_mutex_lock(struct sys_mutex *mutex, k_timeout_t timeout)
Lock a mutex.
This routine locks mutex. If the mutex is locked by another thread, the calling thread
waits until the mutex becomes available or until a timeout occurs.
A thread is permitted to lock a mutex it has already locked. The operation completes
immediately and the lock count is increased by 1.

Parameters

• mutex – Address of the mutex, which may reside in user memory
• timeout – Waiting period to lock the mutex, or one of the special values
  K_NO_WAIT and K_FOREVER.

Return values

• 0 – Mutex locked.
• -EBUSY – Returned without waiting.
• -EAGAIN – Waiting period timed out.
• -EACCES – Caller has no access to provided mutex address
• -EINVAL – Provided mutex not recognized by the kernel

static inline int sys_mutex_unlock(struct sys_mutex *mutex)
Unlock a mutex.
This routine unlocks mutex. The mutex must already be locked by the calling thread.
The mutex cannot be claimed by another thread until it has been unlocked by the call-
ing thread as many times as it was previously locked by that thread.

Parameters

• mutex – Address of the mutex, which may reside in user memory

Return values

• 0 – Mutex unlocked
• -EACCES – Caller has no access to provided mutex address
• -EINVAL – Provided mutex not recognized by the kernel or mutex wasn’t
  locked
• -EPERM – Caller does not own the mutex
Condition Variables

A condition variable is a synchronization primitive that enables threads to wait until a particular condition occurs.

- **Concepts**
- **Implementation**
  - Defining a Condition Variable
  - Waiting on a Condition Variable
  - Signaling a Condition Variable
- **Suggested Uses**
- **Configuration Options**
- **API Reference**

Concepts Any number of condition variables can be defined (limited only by available RAM). Each condition variable is referenced by its memory address.

To wait for a condition to become true, a thread can make use of a condition variable.

A condition variable is basically a queue of threads that threads can put themselves on when some state of execution (i.e., some condition) is not as desired (by waiting on the condition). The function `k_condvar_wait()` performs atomically the following steps;

1. Releases the last acquired mutex.
2. Puts the current thread in the condition variable queue.

Some other thread, when it changes said state, can then wake one (or more) of those waiting threads and thus allow them to continue by signaling on the condition using `k_condvar_signal()` or `k_condvar_broadcast()` then it:

1. Re-acquires the mutex previously released.
2. Returns from `k_condvar_wait()`.

A condition variable must be initialized before it can be used.

Implementation

**Defining a Condition Variable** A condition variable is defined using a variable of type `k_condvar`. It must then be initialized by calling `k_condvar_init()`.

The following code defines a condition variable:

```c
struct k_condvar my_condvar;
k_condvar_init(&my_condvar);
```

Alternatively, a condition variable can be defined and initialized at compile time by calling `K_CONDVAR_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_CONDVAR_DEFINE(my_condvar);
```
Waiting on a Condition Variable  A thread can wait on a condition by calling `k_condvar_wait()`.

The following code waits on the condition variable.

```c
K_MUTEX_DEFINE(mutex);
K_CONDVAR_DEFINE(condvar)

int main(void)
{
    k_mutex_lock(&mutex, K_FOREVER);
    /* block this thread until another thread signals cond. While
     * blocked, the mutex is released, then re-acquired before this
     * thread is woken up and the call returns.
     */
    k_condvar_wait(&condvar, &mutex, K_FOREVER);
    ...
    k_mutex_unlock(&mutex);
}
```

Signaling a Condition Variable  A condition variable is signaled on by calling `k_condvar_signal()` for one thread or by calling `k_condvar_broadcast()` for multiple threads.

The following code builds on the example above.

```c
void worker_thread(void)
{
    k_mutex_lock(&mutex, K_FOREVER);
    /*
     * Do some work and fulfill the condition
     */
    ...
    ...
    k_condvar_signal(&condvar);
    k_mutex_unlock(&mutex);
}
```

Suggested Uses  Use condition variables with a mutex to signal changing states (conditions) from one thread to another thread. Condition variables are not the condition itself and they are not events. The condition is contained in the surrounding programming logic.

Mutexes alone are not designed for use as a notification/synchronization mechanism. They are meant to provide mutually exclusive access to a shared resource only.

Configuration Options  Related configuration options:

- None.

API Reference  Related code samples

Condition Variables

Manipulate condition variables in a multithreaded application.
Defines

\textbf{K\_CONDVAR\_DEFINE} (name)

Statically define and initialize a condition variable.

The condition variable can be accessed outside the module where it is defined using:

\begin{verbatim}
extern struct k\_condvar \textless\textgreater name;\end{verbatim}

**Parameters**

- \textit{name} – Name of the condition variable.

Functions

\textbf{int} \textbf{k\_condvar\_init} (struct k\_condvar *\textit{condvar})

Initialize a condition variable.

**Parameters**

- \textit{condvar} – pointer to a \textit{k\_condvar} structure

**Return values**

\begin{verbatim}
0 – Condition variable created successfully
\end{verbatim}

\textbf{int} \textbf{k\_condvar\_signal} (struct k\_condvar *\textit{condvar})

Signals one thread that is pending on the condition variable.

**Parameters**

- \textit{condvar} – pointer to a \textit{k\_condvar} structure

**Return values**

\begin{verbatim}
0 – On success
\end{verbatim}

\textbf{int} \textbf{k\_condvar\_broadcast} (struct k\_condvar *\textit{condvar})

Unblock all threads that are pending on the condition variable.

**Parameters**

- \textit{condvar} – pointer to a \textit{k\_condvar} structure

**Returns**

An integer with number of woken threads on success

\textbf{int} \textbf{k\_condvar\_wait} (struct k\_condvar *\textit{condvar}, struct \textit{k\_mutex} *\textit{mutex}, \textit{k\_timeout\_t} \textit{timeout})

Waits on the condition variable releasing the mutex lock.

Atomically releases the currently owned mutex, blocks the current thread waiting on the condition variable specified by \textit{condvar}, and finally acquires the mutex again.

The waiting thread unblocks only after another thread calls \textbf{k\_condvar\_signal}, or \textbf{k\_condvar\_broadcast} with the same condition variable.

**Parameters**

- \textit{condvar} – pointer to a \textit{k\_condvar} structure
- \textit{mutex} – Address of the mutex.
- \textit{timeout} – Waiting period for the condition variable or one of the special values \textit{K\_NO\_WAIT} and \textit{K\_FOREVER}.

**Return values**
• 0 – On success
• -EAGAIN – Waiting period timed out.

Events

An event object is a kernel object that implements traditional events.

Concepts

Any number of event objects can be defined (limited only by available RAM). Each event object is referenced by its memory address. One or more threads may wait on an event object until the desired set of events has been delivered to the event object. When new events are delivered to the event object, all threads whose wait conditions have been satisfied become ready simultaneously.

An event object has the following key properties:

• A 32-bit value that tracks which events have been delivered to it.

An event object must be initialized before it can be used.

Events may be delivered by a thread or an ISR. When delivering events, the events may either overwrite the existing set of events or add to them in a bitwise fashion. When overwriting the existing set of events, this is referred to as setting. When adding to them in a bitwise fashion, this is referred to as posting. Both posting and setting events have the potential to fulfill match conditions of multiple threads waiting on the event object. All threads whose match conditions have been met are made active at the same time.

Threads may wait on one or more events. They may either wait for all of the requested events, or for any of them. Furthermore, threads making a wait request have the option of resetting the current set of events tracked by the event object prior to waiting. Care must be taken with this option when multiple threads wait on the same event object.

Note: The kernel does allow an ISR to query an event object, however the ISR must not attempt to wait for the events.

Implementation

Defining an Event Object

An event object is defined using a variable of type `k_event`. It must then be initialized by calling `k_event_init()`.

The following code defines an event object.
struct k_event my_event;
k_event_init(&my_event);

Alternatively, an event object can be defined and initialized at compile time by calling `K_EVENT_DEFINE`.

The following code has the same effect as the code segment above.

`K_EVENT_DEFINE(my_event);`

**Setting Events**  Events in an event object are set by calling `k_event_set()`.

The following code builds on the example above, and sets the events tracked by the event object to 0x001.

```c
void input_available_interrupt_handler(void *arg)
{
    /* notify threads that data is available */
    k_event_set(&my_event, 0x001);
    ...
}
```

**Posting Events**  Events are posted to an event object by calling `k_event_post()`.

The following code builds on the example above, and posts a set of events to the event object.

```c
void input_available_interrupt_handler(void *arg)
{
    /* notify threads that more data is available */
    k_event_post(&my_event, 0x120);
    ...
}
```

**Waiting for Events**  Threads wait for events by calling `k_event_wait()`.

The following code builds on the example above, and waits up to 50 milliseconds for any of the specified events to be posted. A warning is issued if none of the events are posted in time.

```c
void consumer_thread(void)
{
    uint32_t events;
    events = k_event_wait(&my_event, 0xFFF, false, K_MSEC(50));
    if (events == 0) {
        printk("No input devices are available!");
    } else {
        /* Access the desired input device(s) */
        ...
    }
    ...
}
```
Alternatively, the consumer thread may desire to wait for all the events before continuing.

```c
void consumer_thread(void)
{
    uint32_t events;

    events = k_event_wait_all(&my_event, 0x121, false, K_MSEC(50));
    if (events == 0) {
        printk("At least one input device is not available!\n");
    } else {
        /* Access the desired input devices */
        ...
    }
    ...
}
```

**Suggested Uses**  Use events to indicate that a set of conditions have occurred. Use events to pass small amounts of data to multiple threads at once.

**Configuration Options**  Related configuration options:

- CONFIG_EVENTS

**API Reference**

*group event_apis*

**Defines**

*K_EVENT_DEFINE(name)*

Statically define and initialize an event object.

The event can be accessed outside the module where it is defined using:

```c
extern struct k_event <name>;
```

**Parameters**

- *name* – Name of the event object.

**Functions**

```c
void k_event_init(struct k_event *event)
```

Initialize an event object.

This routine initializes an event object, prior to its first use.

**Parameters**

- *event* – Address of the event object.
uint32_t k_event_post(struct k_event *event, uint32_t events)
    Post one or more events to an event object.

This routine posts one or more events to an event object. All tasks waiting on the event object event whose waiting conditions become met by this posting immediately unpend.

Posting differs from setting in that posted events are merged together with the current set of events tracked by the event object.

Parameters
    • event – Address of the event object
    • events – Set of events to post to event

Return values
    Previous – value of the events in event

uint32_t k_event_set(struct k_event *event, uint32_t events)
Set the events in an event object.

This routine sets the events stored in event object to the specified value. All tasks waiting on the event object event whose waiting conditions become met by this immediately unpend.

Setting differs from posting in that set events replace the current set of events tracked by the event object.

Parameters
    • event – Address of the event object
    • events – Set of events to set in event

Return values
    Previous – value of the events in event

uint32_t k_event_set_masked(struct k_event *event, uint32_t events, uint32_t events_mask)
Set or clear the events in an event object.

This routine sets the events stored in event object to the specified value. All tasks waiting on the event object event whose waiting conditions become met by this immediately unpend. Unlike k_event_set, this routine allows specific event bits to be set and cleared as determined by the mask.

Parameters
    • event – Address of the event object
    • events – Set of events to set/clear in event
    • events_mask – Mask to be applied to events

Return values
    Previous – value of the events in events_mask

uint32_t k_event_clear(struct k_event *event, uint32_t events)
Clear the events in an event object.

This routine clears (resets) the specified events stored in an event object.

Parameters
    • event – Address of the event object
    • events – Set of events to clear in event
Return values
Previous – value of the events in event

uint32_t k_event_wait(struct k_event *event, uint32_t events, bool reset, k_timeout_t timeout)

Wait for any of the specified events.

This routine waits on event object event until any of the specified events have been delivered to the event object, or the maximum wait time timeout has expired. A thread may wait on up to 32 distinctly numbered events that are expressed as bits in a single 32-bit word.

Note: The caller must be careful when resetting if there are multiple threads waiting for the event object event.

Parameters
• event – Address of the event object
• events – Set of desired events on which to wait
• reset – If true, clear the set of events tracked by the event object before waiting. If false, do not clear the events.
• timeout – Waiting period for the desired set of events or one of the special values K_NO_WAIT and K_FOREVER.

Return values
• set – of matching events upon success
• 0 – if matching events were not received within the specified time

uint32_t k_event_wait_all(struct k_event *event, uint32_t events, bool reset, k_timeout_t timeout)

Wait for all of the specified events.

This routine waits on event object event until all of the specified events have been delivered to the event object, or the maximum wait time timeout has expired. A thread may wait on up to 32 distinctly numbered events that are expressed as bits in a single 32-bit word.

Note: The caller must be careful when resetting if there are multiple threads waiting for the event object event.

Parameters
• event – Address of the event object
• events – Set of desired events on which to wait
• reset – If true, clear the set of events tracked by the event object before waiting. If false, do not clear the events.
• timeout – Waiting period for the desired set of events or one of the special values K_NO_WAIT and K_FOREVER.

Return values
• set – of matching events upon success
• 0 – if matching events were not received within the specified time
static inline uint32_t k_event_test(struct k_event *event, uint32_t events_mask)
    Test the events currently tracked in the event object.

**Parameters**
- **event** – Address of the event object
- **events_mask** – Set of desired events to test

**Return values**
- **Current** – value of events in `events_mask`

```c
struct k_event
#include <kernel.h> Event Structure.
```

## Symmetric Multiprocessing

On multiprocessor architectures, Zephyr supports the use of multiple physical CPUs running Zephyr application code. This support is “symmetric” in the sense that no specific CPU is treated specially by default. Any processor is capable of running any Zephyr thread, with access to all standard Zephyr APIs supported.

No special application code needs to be written to take advantage of this feature. If there are two Zephyr application threads runnable on a supported dual processor device, they will both run simultaneously.

SMP configuration is controlled under the `CONFIG_SMP` kconfig variable. This must be set to “y” to enable SMP features, otherwise a uniprocessor kernel will be built. In general the platform default will have enabled this anywhere it's supported. When enabled, the number of physical CPUs available is visible at build time as `CONFIG_MP_MAX_NUM_CPUS`. Likewise, the default for this will be the number of available CPUs on the platform and it is not expected that typical apps will change it. But it is legal and supported to set this to a smaller (but obviously not larger) number for special purposes (e.g. for testing, or to reserve a physical CPU for running non-Zephyr code).

## Synchronization

At the application level, core Zephyr IPC and synchronization primitives all behave identically under an SMP kernel. For example semaphores used to implement blocking mutual exclusion continue to be a proper application choice.

At the lowest level, however, Zephyr code has often used the `irq_lock()`/`irq_unlock()` primitives to implement fine grained critical sections using interrupt masking. These APIs continue to work via an emulation layer (see below), but the masking technique does not: the fact that your CPU will not be interrupted while you are in your critical section says nothing about whether a different CPU will be running simultaneously and be inspecting or modifying the same data!

**Spinlocks**

SMP systems provide a more constrained `k_spin_lock()` primitive that not only masks interrupts locally, as done by `irq_lock()`, but also atomically validates that a shared lock variable has been modified before returning to the caller, “spinning” on the check if needed to wait for the other CPU to exit the lock. The default Zephyr implementation of `k_spin_lock()` and `k_spin_unlock()` is built on top of the pre-existing `atomic_layer` (itself usually implemented using compiler intrinsics), though facilities exist for architectures to define their own for performance reasons.

One important difference between IRQ locks and spinlocks is that the earlier API was naturally recursive: the lock was global, so it was legal to acquire a nested lock inside of a critical section. Spinlocks are separable: you can have many locks for separate subsystems or data structures, preventing CPUs from contending on a single global resource. But that means that spinlocks must not be used recursively. Code that holds a specific lock must not try to re-acquire it or
it will deadlock (it is perfectly legal to nest distinct spinlocks, however). A validation layer is available to detect and report bugs like this.

When used on a uniprocessor system, the data component of the spinlock (the atomic lock variable) is unnecessary and elided. Except for the recursive semantics above, spinlocks in single-CPU contexts produce identical code to legacy IRQ locks. In fact the entirety of the Zephyr core kernel has now been ported to use spinlocks exclusively.

**Legacy irq_lock() emulation** For the benefit of applications written to the uniprocessor locking API, *irq_lock()* and *irq_unlock()* continue to work compatibly on SMP systems with identical semantics to their legacy versions. They are implemented as a single global spinlock, with a nesting count and the ability to be atomically reacquired on context switch into locked threads. The kernel will ensure that only one thread across all CPUs can hold the lock at any time, that it is released on context switch, and that it is re-acquired when necessary to restore the lock state when a thread is switched in. Other CPUs will spin waiting for the release to happen.

The overhead involved in this process has measurable performance impact, however. Unlike uniprocessor apps, SMP apps using *irq_lock()* are not simply invoking a very short (often ~1 instruction) interrupt masking operation. That, and the fact that the IRQ lock is global, means that code expecting to be run in an SMP context should be using the spinlock API wherever possible.

**CPU Mask** It is often desirable for real time applications to deliberately partition work across physical CPUs instead of relying solely on the kernel scheduler to decide on which threads to execute. Zephyr provides an API, controlled by the CONFIG_SCHED_CPU_MASK kconfig variable, which can associate a specific set of CPUs with each thread, indicating on which CPUs it can run.

By default, new threads can run on any CPU. Calling *k_thread_cpu_mask_disable()* with a particular CPU ID will prevent that thread from running on that CPU in the future. Likewise *k_thread_cpu_mask_enable()* will re-enable execution. There are also *k_thread_cpu_mask_clear()* and *k_thread_cpu_mask_enable_all()* APIs available for convenience. For obvious reasons, these APIs are illegal if called on a runnable thread. The thread must be blocked or suspended, otherwise an -EINVAL will be returned.

Note that when this feature is enabled, the scheduler algorithm involved in doing the per-CPU mask test requires that the list be traversed in full. The kernel does not keep a per-CPU run queue. That means that the performance benefits from the CONFIG_SCHED_SCALABLE and CONFIG_SCHED_MULTIQ scheduler backends cannot be realized. CPU mask processing is available only when CONFIG_SCHED_DUMB is the selected backend. This requirement is enforced in the configuration layer.

**SMP Boot Process** A Zephyr SMP kernel begins boot identically to a uniprocessor kernel. Auxiliary CPUs begin in a disabled state in the architecture layer. All standard kernel initialization, including device initialization, happens on a single CPU before other CPUs are brought online.

Just before entering the application *main()* function, the kernel calls z_smp_init() to launch the SMP initialization process. This enumerates over the configured CPUs, calling into the architecture layer using *arch_start_cpu()* for each one. This function is passed a memory region to use as a stack on the foreign CPU (in practice it uses the area that will become that CPU's interrupt stack), the address of a local smp_init_top() callback function to run on that CPU, and a pointer to a “start flag” address which will be used as an atomic signal.

The local SMP initialization (smp_init_top()) on each CPU is then invoked by the architecture layer. Note that interrupts are still masked at this point. This routine is responsible for calling smp_timer_init() to set up any needed stat in the timer driver. On many architectures the timer is a per-CPU device and needs to be configured specially on auxiliary CPUs. Then it waits (spinning) for the atomic “start flag” to be released in the main thread, to guarantee that all SMP
initialization is complete before any Zephyr application code runs, and finally calls `z_swap()` to transfer control to the appropriate runnable thread via the standard scheduler API.

![Diagram of SMP initialization process with two CPUs and two app threads](image)

**Fig. 1:** Example SMP initialization process, showing a configuration with two CPUs and two app threads which begin operating simultaneously.

**Interprocessor Interrupts** When running in multiprocessor environments, it is occasionally the case that state modified on the local CPU needs to be synchronously handled on a different processor.

One example is the Zephyr `k_thread_abort()` API, which cannot return until the thread that had been aborted is no longer runnable. If it is currently running on another CPU, that becomes difficult to implement.

Another is low power idle. It is a firm requirement on many devices that system idle be implemented using a low-power mode with as many interrupts (including periodic timer interrupts) disabled or deferred as is possible. If a CPU is in such a state, and on another CPU a thread becomes runnable, the idle CPU has no way to “wake up” to handle the newly-runnable load.

So where possible, Zephyr SMP architectures should implement an interprocessor interrupt. The current framework is very simple: the architecture provides a `arch_sched_ipi()` call, which when invoked will flag an interrupt on all CPUs (except the current one, though that is allowed behavior) which will then invoke the `z_sched_ipi()` function implemented in the scheduler. The expectation is that these APIs will evolve over time to encompass more functionality (e.g. cross-CPU calls), and that the scheduler-specific calls here will be implemented in terms of a more general framework.

Note that not all SMP architectures will have a usable IPI mechanism (either missing, or just undocumented/unimplemented). In those cases Zephyr provides fallback behavior that is correct,
but perhaps suboptimal.

Using this, `k_thread_abort()` becomes only slightly more complicated in SMP: for the case where a thread is actually running on another CPU (we can detect this atomically inside the scheduler), we broadcast an IPI and spin, waiting for the thread to either become “DEAD” or for it to re-enter the queue (in which case we terminate it the same way we would have in uniprocessor mode). Note that the “aborted” check happens on any interrupt exit, so there is no special handling needed in the IPI per se. This allows us to implement a reasonable fallback when IPI is not available: we can simply spin, waiting until the foreign CPU receives any interrupt, though this may be a much longer time!

Likewise idle wakeups are trivially implementable with an empty IPI handler. If a thread is added to an empty run queue (i.e. there may have been idle CPUs), we broadcast an IPI. A foreign CPU will then be able to see the new thread when exiting from the interrupt and will switch to it if available.

Without an IPI, however, a low power idle that requires an interrupt will not work to synchronously run new threads. The workaround in that case is more invasive: Zephyr will not enter the system idle handler and will instead spin in its idle loop, testing the scheduler state at high frequency (not spinning on it though, as that would involve severe lock contention) for new threads. The expectation is that power constrained SMP applications are always going to provide an IPI, and this code will only be used for testing purposes or on systems without power consumption requirements.

**SMP Kernel Internals** In general, Zephyr kernel code is SMP-agnostic and, like application code, will work correctly regardless of the number of CPUs available. But in a few areas there are notable changes in structure or behavior.

**Per-CPU data** Many elements of the core kernel data need to be implemented for each CPU in SMP mode. For example, the `_current` thread pointer obviously needs to reflect what is running locally, there are many threads running concurrently. Likewise a kernel-provided interrupt stack needs to be created and assigned for each physical CPU, as does the interrupt nesting count used to detect ISR state.

These fields are now moved into a separate struct `_cpu` instance within the `_kernel` struct, which has a `cpus[]` array indexed by ID. Compatibility fields are provided for legacy uniprocessor code trying to access the fields of `cpus[0]` using the older syntax and assembly offsets.

Note that an important requirement on the architecture layer is that the pointer to this CPU struct be available rapidly when in kernel context. The expectation is that `arch_curr_cpu()` will be implemented using a CPU-provided register or addressing mode that can store this value across arbitrary context switches or interrupts and make it available to any kernel-mode code.

Similarly, where on a uniprocessor system Zephyr could simply create a global “idle thread” at the lowest priority, in SMP we may need one for each CPU. This makes the internal predicate test for “is_idle()” in the scheduler, which is a hot path performance environment, more complicated than simply testing the thread pointer for equality with a known static variable. In SMP mode, idle threads are distinguished by a separate field in the thread struct.

**Switch-based context switching** The traditional Zephyr context switch primitive has been `z_swap()`. Unfortunately, this function takes no argument specifying a thread to switch to. The expectation has always been that the scheduler has already made its preemption decision when its state was last modified and cached the resulting “next thread” pointer in a location where architecture context switch primitives can find it via a simple struct offset. That technique will not work in SMP, because the other CPU may have modified scheduler state since the current CPU last exited the scheduler (for example: it might already be running that cached thread!).

Instead, the SMP “switch to” decision needs to be made synchronously with the swap call, and as we don’t want per-architecture assembly code to be handling scheduler internal state, Zephyr
requires a somewhat lower-level context switch primitives for SMP systems: \textit{arch_switch()} is always called with interrupts masked, and takes exactly two arguments. The first is an opaque (architecture defined) handle to the context to which it should switch, and the second is a pointer to such a handle into which it should store the handle resulting from the thread that is being switched out. The kernel then implements a portable \textit{z_swap()} implementation on top of this primitive which includes the relevant scheduler logic in a location where the architecture doesn't need to understand it.

Similarly, on interrupt exit, switch-based architectures are expected to call \textit{z_get_next_switch_handle()} to retrieve the next thread to run from the scheduler. The argument to \textit{z_get_next_switch_handle()} is either the interrupted thread's “handle” reflecting the same opaque type used by \textit{arch_switch()}, or NULL if that thread cannot be released to the scheduler just yet. The choice between a handle value or NULL depends on the way CPU interrupt mode is implemented.

Architectures with a large CPU register file would typically preserve only the caller-saved registers on the current thread's stack when interrupted in order to minimize interrupt latency, and preserve the callee-saved registers only when \textit{arch_switch()} is called to minimize context switching latency. Such architectures must use NULL as the argument to \textit{z_get_next_switch_handle()} to determine if there is a new thread to schedule, and follow through with their own \textit{arch_switch()} or derivative if so, or directly leave interrupt mode otherwise. In the former case it is up to that switch code to store the handle resulting from the thread that is being switched out in that thread's “switch_handle” field after its context has fully been saved.

Architectures whose entry in interrupt mode already preserves the entire thread state may pass that thread's handle directly to \textit{z_get_next_switch_handle()} and be done in one step.

Note that while SMP requires \texttt{CONFIG_USE_SWITCH}, the reverse is not true. A uniprocessor architecture built with \texttt{CONFIG_SMP} set to No might still decide to implement its context switching using \textit{arch_switch()}.

### API Reference

\texttt{group spinlock\_apis}

Spinlock APIs.

\textbf{Defines}

\texttt{K\_SPINLOCK\_BREAK}

Leaves a code block guarded with \texttt{K\_SPINLOCK} after releasing the lock.

See \texttt{K\_SPINLOCK} for details.

\texttt{K\_SPINLOCK(lck)}

Guards a code block with the given spinlock, automatically acquiring the lock before executing the code block.

The lock will be released either when reaching the end of the code block or when leaving the block with \texttt{K\_SPINLOCK\_BREAK}.

Example usage:

\begin{verbatim}
K_SPINLOCK(&mylock) {
  ...execute statements with the lock held...
  if (some_condition) {
    ...release the lock and leave the guarded section prematurely:
  }
}
\end{verbatim}
Behind the scenes this pattern expands to a for-loop whose body is executed exactly once:

```c
for (k_spinlock_key_t key = k_spin_lock(&mylock); ...; k_spin_unlock(&mylock, key)) {
    ...
}
```

**Note:** In user mode the spinlock must be placed in memory accessible to the application, see `K_APP_DMEM` and `K_APP_BMEM` macros for details.

**Warning:** The code block must execute to its end or be left by calling `K_SPINLOCK_BREAK`. Otherwise, e.g. if exiting the block with a break, goto or return statement, the spinlock will not be released on exit.

**Parameters**
- `lck` – Spinlock used to guard the enclosed code block.

**Typedefs**

```c
typedef struct z_spinlock_key k_spinlock_key_t

Spinlock key type.
```

This type defines a “key” value used by a spinlock implementation to store the system interrupt state at the time of a call to `k_spin_lock()`. It is expected to be passed to a matching `k_spin_unlock()`.

This type is opaque and should not be inspected by application code.

**Functions**

```c
ALWAYS_INLINE static k_spinlock_key_t k_spin_lock(struct k_spinlock *l)

Lock a spinlock.
```

This routine locks the specified spinlock, returning a key handle representing interrupt state needed at unlock time. Upon returning, the calling thread is guaranteed not to be suspended or interrupted on its current CPU until it calls `k_spin_unlock()`. The implementation guarantees mutual exclusion: exactly one thread on one CPU will return from `k_spin_lock()` at a time. Other CPUs trying to acquire a lock already held by another CPU will enter an implementation-defined busy loop (“spinning”) until the lock is released.

Separate spin locks may be nested. It is legal to lock an (unlocked) spin lock while holding a different lock. Spin locks are not recursive, however: an attempt to acquire a spin lock that the CPU already holds will deadlock.
In circumstances where only one CPU exists, the behavior of \texttt{k\_spin\_lock()} remains as specified above, though obviously no spinning will take place. Implementations may be free to optimize in uniprocessor contexts such that the locking reduces to an interrupt mask operation.

**Parameters**

- \texttt{l} – A pointer to the spinlock to lock

**Returns**

A key value that must be passed to \texttt{k\_spin\_unlock()} when the lock is released.

```c
ALWAYS_INLINE static int k_spin_trylock(struct k_spinlock *l, k_spinlock_key_t *k)
```

Attempt to lock a spinlock.

This routine makes one attempt to lock \texttt{l}. If it is successful, then it will store the key into \texttt{k}.

See also:

\texttt{k\_spin\_lock}

See also:

\texttt{k\_spin\_unlock}

**Parameters**

- \texttt{l} – [in] A pointer to the spinlock to lock
- \texttt{k} – [out] A pointer to the spinlock key

**Return values**

- \texttt{0} – on success
- \texttt{-EBUSY} – if another thread holds the lock

```c
ALWAYS_INLINE static void k_spin_unlock(struct k_spinlock *l, k_spinlock_key_t key)
```

Unlock a spin lock.

This releases a lock acquired by \texttt{k\_spin\_lock()}. After this function is called, any CPU will be able to acquire the lock. If other CPUs are currently spinning inside \texttt{k\_spin\_lock()} waiting for this lock, exactly one of them will return synchronously with the lock held.

Spin locks must be properly nested. A call to \texttt{k\_spin\_unlock()} must be made on the lock object most recently locked using \texttt{k\_spin\_lock()}, using the key value that it returned. Attempts to unlock mis-nested locks, or to unlock locks that are not held, or to passing a key parameter other than the one returned from \texttt{k\_spin\_lock()}, are illegal. When \texttt{CONFIG_SPIN_VALIDATE} is set, some of these errors can be detected by the framework.

**Parameters**

- \texttt{l} – A pointer to the spinlock to release
- \texttt{key} – The value returned from \texttt{k\_spin\_lock()} when this lock was acquired

```c
struct k_spinlock
```

```
#include <spinlock.h> Kernel Spin Lock.
```

This struct defines a spin lock record on which CPUs can wait with \texttt{k\_spin\_lock()}. Any number of spinlocks may be defined in application code.

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### 3.1.2 Data Passing

These pages cover kernel objects which can be used to pass data between threads and ISRs. The following table summarizes their high-level features.

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<th>Object</th>
<th>Bidirectional?</th>
<th>Data structure</th>
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</thead>
<tbody>
<tr>
<td>Stack</td>
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<td>Array</td>
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<td>Word</td>
<td>Yes [3]</td>
<td>Yes</td>
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</tr>
<tr>
<td>Message queue</td>
<td>No</td>
<td>Ring buffer</td>
<td>Arbitrary</td>
<td>Power of two</td>
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<td>Yes</td>
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</tr>
<tr>
<td>Mailbox</td>
<td>Yes</td>
<td>Queue</td>
<td>Arbitrary</td>
<td>Arbi-trary [1]</td>
<td>No</td>
<td>No</td>
<td>N/A</td>
</tr>
</tbody>
</table>

[1] Callers allocate space for queue overhead in the data elements themselves.

[2] Objects added with `k_fifo_alloc_put()` and `k_lifo_alloc_put()` do not have alignment constraints, but use temporary memory from the calling thread's resource pool.

[3] ISRs can receive only when passing `K_NO_WAIT` as the timeout argument.


[5] ISRS can send and/or receive only when passing `K_NO_WAIT` as the timeout argument.

[6] Data item size must be a multiple of the data alignment.

### Queues

A Queue in Zephyr is a kernel object that implements a traditional queue, allowing threads and ISRs to add and remove data items of any size. The queue is similar to a FIFO and serves as the underlying implementation for both `k_fifo` and `k_lifo`. For more information on usage see `k_fifo`.

### Configuration Options

- Related configuration options:
  - None

### API Reference

`group queue_apis`
Defines

*K_QUEUE_DEFINE*(name)

Statically define and initialize a queue.

The queue can be accessed outside the module where it is defined using:

```c
extern struct k_queue <name>;
```

**Parameters**

- `name` – Name of the queue.

Functions

```c
void k_queue_init(struct k_queue *queue)
```

Initialize a queue.

This routine initializes a queue object, prior to its first use.

**Parameters**

- `queue` – Address of the queue.

```c
void k_queue_cancel_wait(struct k_queue *queue)
```

Cancel waiting on a queue.

This routine causes first thread pending on `queue`, if any, to return from `k_queue_get()` call with NULL value (as if timeout expired). If the queue is being waited on by `k_poll()`, it will return with -EINVAL and K_POLL_STATE_CANCELLED state (and per above, subsequent `k_queue_get()` will return NULL).

**Function properties (list may not be complete)**

`isr-ok`

**Parameters**

- `queue` – Address of the queue.

```c
void k_queue_append(struct k_queue *queue, void *data)
```

Append an element to the end of a queue.

This routine appends a data item to `queue`. A queue data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel's use.

**Function properties (list may not be complete)**

`isr-ok`

**Parameters**

- `queue` – Address of the queue.
  - `data` – Address of the data item.
int32_t k_queue_alloc_append(struct k_queue *queue, void *data)

Append an element to a queue.

This routine appends a data item to `queue`. There is an implicit memory allocation to create an additional temporary bookkeeping data structure from the calling thread’s resource pool, which is automatically freed when the item is removed. The data itself is not copied.

Function properties (list may not be complete)

`isr-ok`

Parameters

- `queue` – Address of the queue.
- `data` – Address of the data item.

Return values

- 0 – on success
- -ENOMEM – if there isn’t sufficient RAM in the caller’s resource pool

void k_queue_prepend(struct k_queue *queue, void *data)

Prepend an element to a queue.

This routine prepends a data item to `queue`. A queue data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel's use.

Function properties (list may not be complete)

`isr-ok`

Parameters

- `queue` – Address of the queue.
- `data` – Address of the data item.

int32_t k_queue_alloc_prepend(struct k_queue *queue, void *data)

Prepend an element to a queue.

This routine prepends a data item to `queue`. There is an implicit memory allocation to create an additional temporary bookkeeping data structure from the calling thread’s resource pool, which is automatically freed when the item is removed. The data itself is not copied.

Function properties (list may not be complete)

`isr-ok`

Parameters

- `queue` – Address of the queue.
- `data` – Address of the data item.

Return values

- 0 – on success
- -ENOMEM – if there isn’t sufficient RAM in the caller’s resource pool
void k_queue_insert(struct k_queue *queue, void *prev, void *data)

Inserts an element to a queue.

This routine inserts a data item to queue after previous item. A queue data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel’s use.

**Function properties (list may not be complete)**

*isr-ok*

**Parameters**

- `queue` – Address of the queue.
- `prev` – Address of the previous data item.
- `data` – Address of the data item.

int k_queue_append_list(struct k_queue *queue, void *head, void *tail)

Atomically append a list of elements to a queue.

This routine adds a list of data items to queue in one operation. The data items must be in a singly-linked list, with the first word in each data item pointing to the next data item; the list must be NULL-terminated.

**Function properties (list may not be complete)**

*isr-ok*

**Parameters**

- `queue` – Address of the queue.
- `head` – Pointer to first node in singly-linked list.
- `tail` – Pointer to last node in singly-linked list.

**Return values**

- 0 – on success
- -EINVAL – on invalid supplied data

int k_queue_merge_slist(struct k_queue *queue, sys_slist_t *list)

Atomically add a list of elements to a queue.

This routine adds a list of data items to queue in one operation. The data items must be in a singly-linked list implemented using a sys_slist_t object. Upon completion, the original list is empty.

**Function properties (list may not be complete)**

*isr-ok*

**Parameters**

- `queue` – Address of the queue.
- `list` – Pointer to sys_slist_t object.

**Return values**

- 0 – on success
- -EINVAL – on invalid data

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void *k_queue_get(struct k_queue *queue, k_timeout_t timeout)
Get an element from a queue.
This routine removes first data item from queue. The first word of the data item is reserved for the kernel's use.

Function properties (list may not be complete)
isr-ok

Note: timeout must be set to K_NO_WAIT if called from ISR.

Parameters
• queue – Address of the queue.
• timeout – Non-negative waiting period to obtain a data item or one of the special values K_NO_WAIT and K_FOREVER.

Returns
Address of the data item if successful; NULL if returned without waiting, or waiting period timed out.

bool k_queue_remove(struct k_queue *queue, void *data)
Remove an element from a queue.
This routine removes data item from queue. The first word of the data item is reserved for the kernel's use. Removing elements from k_queue rely on sys_slist_find_and_remove which is not a constant time operation.

Function properties (list may not be complete)
isr-ok

Note: timeout must be set to K_NO_WAIT if called from ISR.

Parameters
• queue – Address of the queue.
• data – Address of the data item.

Returns
true if data item was removed

bool k_queue_unique_append(struct k_queue *queue, void *data)
Append an element to a queue only if it's not present already.
This routine appends data item to queue. The first word of the data item is reserved for the kernel's use. Appending elements to k_queue rely on sys_slist_is_node_in_list which is not a constant time operation.

Function properties (list may not be complete)
isr-ok

Parameters
• queue – Address of the queue.
• **data** – Address of the data item.

**Returns**
true if data item was added, false if not

```c
int k_queue_is_empty(struct k_queue *queue)
```

Query a queue to see if it has data available. Note that the data might be already gone by the time this function returns if other threads are also trying to read from the queue.

**Function properties (list may not be complete)**

**isr-ok**

**Parameters**

• **queue** – Address of the queue.

**Returns**
Non-zero if the queue is empty.

**Returns**
0 if data is available.

```c
void *k_queue_peek_head(struct k_queue *queue)
```

Peek element at the head of queue.

Return element from the head of queue without removing it.

**Parameters**

• **queue** – Address of the queue.

**Returns**
Head element, or NULL if queue is empty.

```c
void *k_queue_peek_tail(struct k_queue *queue)
```

Peek element at the tail of queue.

Return element from the tail of queue without removing it.

**Parameters**

• **queue** – Address of the queue.

**Returns**
Tail element, or NULL if queue is empty.

**FIFOs**

A **FIFO** is a kernel object that implements a traditional first in, first out (FIFO) queue, allowing threads and ISRs to add and remove data items of any size.

- **Concepts**
- **Implementation**
  - *Defining a FIFO*
  - *Writing to a FIFO*
  - *Reading from a FIFO*
Any number of FIFOs can be defined (limited only by available RAM). Each FIFO is referenced by its memory address.

A FIFO has the following key properties:

- A queue of data items that have been added but not yet removed. The queue is implemented as a simple linked list.

A FIFO must be initialized before it can be used. This sets its queue to empty.

FIFO data items must be aligned on a word boundary, as the kernel reserves the first word of an item for use as a pointer to the next data item in the queue. Consequently, a data item that holds N bytes of application data requires N+4 (or N+8) bytes of memory. There are no alignment or reserved space requirements for data items if they are added with `k_fifo_alloc_put()`, instead additional memory is temporarily allocated from the calling thread's resource pool.

**Note:** FIFO data items are restricted to single active instance across all FIFO data queues. Any attempt to re-add a FIFO data item to a queue before it has been removed from the queue to which it was previously added will result in undefined behavior.

A data item may be **added** to a FIFO by a thread or an ISR. The item is given directly to a waiting thread, if one exists; otherwise the item is added to the FIFO's queue. There is no limit to the number of items that may be queued.

A data item may be **removed** from a FIFO by a thread. If the FIFO's queue is empty a thread may choose to wait for a data item to be given. Any number of threads may wait on an empty FIFO simultaneously. When a data item is added, it is given to the highest priority thread that has waited longest.

**Note:** The kernel does allow an ISR to remove an item from a FIFO, however the ISR must not attempt to wait if the FIFO is empty.

If desired, multiple data items can be added to a FIFO in a single operation if they are chained together into a singly-linked list. This capability can be useful if multiple writers are adding sets of related data items to the FIFO, as it ensures the data items in each set are not interleaved with other data items. Adding multiple data items to a FIFO is also more efficient than adding them one at a time, and can be used to guarantee that anyone who removes the first data item in a set will be able to remove the remaining data items without waiting.

**Implementation**

**Defining a FIFO**  A FIFO is defined using a variable of type `k_fifo`. It must then be initialized by calling `k_fifo_init()`.

The following code defines and initializes an empty FIFO.

```c
struct k_fifo my_fifo;
k_fifo_init(&my_fifo);
```
Alternatively, an empty FIFO can be defined and initialized at compile time by calling `K_FIFO_DEFINE`.

The following code has the same effect as the code segment above.

```
K_FIFO_DEFINE(my_fifo);
```

**Writing to a FIFO**  A data item is added to a FIFO by calling `k_fifo_put()`.

The following code builds on the example above, and uses the FIFO to send data to one or more consumer threads.

```c
struct data_item_t {
    void *fifo_reserved;  /* 1st word reserved for use by FIFO */
    ...
};
struct data_item_t tx_data;
void producer_thread(int unused1, int unused2, int unused3)
{
    while (1) {
        /* create data item to send */
        tx_data = ...
        /* send data to consumers */
        k_fifo_put(&my_fifo, &tx_data);
        ...
    }
}
```

Additionally, a singly-linked list of data items can be added to a FIFO by calling `k_fifo_put_list()` or `k_fifo_put_slist()`.

Finally, a data item can be added to a FIFO with `k_fifo_alloc_put()`. With this API, there is no need to reserve space for the kernel's use in the data item, instead additional memory will be allocated from the calling thread's resource pool until the item is read.

**Reading from a FIFO**  A data item is removed from a FIFO by calling `k_fifo_get()`.

The following code builds on the example above, and uses the FIFO to obtain data items from a producer thread, which are then processed in some manner.

```c
void consumer_thread(int unused1, int unused2, int unused3)
{
    struct data_item_t *rx_data;
    while (1) {
        rx_data = k_fifo_get(&my_fifo, K_FOREVER);
        /* process FIFO data item */
        ...
    }
}
```

**Suggested Uses**  Use a FIFO to asynchronously transfer data items of arbitrary size in a “first in, first out” manner.
Configuration Options  Related configuration options:
  • None

API Reference

group fifo_apis

Defines

k_fifo_init(fifo)
Initialize a FIFO queue.
This routine initializes a FIFO queue, prior to its first use.

Parameters
  • fifo – Address of the FIFO queue.

k_fifo_cancel_wait(fifo)
Cancel waiting on a FIFO queue.
This routine causes first thread pending on fifo, if any, to return from k_fifo_get() call with NULL value (as if timeout expired).

Function properties (list may not be complete)
  isr-ok

Parameters
  • fifo – Address of the FIFO queue.

k_fifo_put(fifo, data)
Add an element to a FIFO queue.
This routine adds a data item to fifo. A FIFO data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel's use.

Function properties (list may not be complete)
  isr-ok

Parameters
  • fifo – Address of the FIFO.
  • data – Address of the data item.

k_fifo_alloc_put(fifo, data)
Add an element to a FIFO queue.
This routine adds a data item to fifo. There is an implicit memory allocation to create an additional temporary bookkeeping data structure from the calling thread's resource pool, which is automatically freed when the item is removed. The data itself is not copied.

Function properties (list may not be complete)
  isr-ok
Parameters

- `fifo` – Address of the FIFO.
- `data` – Address of the data item.

Return values

- `0` – on success
- `-ENOMEM` – if there isn’t sufficient RAM in the caller’s resource pool

```c
k_fifo_put_list(fifo, head, tail)
```
Atomically add a list of elements to a FIFO.

This routine adds a list of data items to `fifo` in one operation. The data items must be in a singly-linked list, with the first word of each data item pointing to the next data item; the list must be NULL-terminated.

Function properties (list may not be complete)

`isr-ok`

Parameters

- `fifo` – Address of the FIFO queue.
- `head` – Pointer to first node in singly-linked list.
- `tail` – Pointer to last node in singly-linked list.

```c
k_fifo_put_slist(fifo, list)
```
Atomically add a list of elements to a FIFO queue.

This routine adds a list of data items to `fifo` in one operation. The data items must be in a singly-linked list implemented using a `sys_slist_t` object. Upon completion, the `sys_slist_t` object is invalid and must be re-initialized via `sys_slist_init()`.

Function properties (list may not be complete)

`isr-ok`

Parameters

- `fifo` – Address of the FIFO queue.
- `list` – Pointer to `sys_slist_t` object.

```c
k_fifo_get(fifo, timeout)
```
Get an element from a FIFO queue.

This routine removes a data item from `fifo` in a “first in, first out” manner. The first word of the data item is reserved for the kernel’s use.

Function properties (list may not be complete)

`isr-ok`

Note: `timeout` must be set to `K_NO_WAIT` if called from ISR.

Parameters

- `fifo` – Address of the FIFO queue.
• **timeout** – Waiting period to obtain a data item, or one of the special values K_NO_WAIT and K_FOREVER.

**Returns**
Address of the data item if successful; NULL if returned without waiting, or waiting period timed out.

`k_fifo_is_empty(fifo)`
Query a FIFO queue to see if it has data available.

Note that the data might be already gone by the time this function returns if other threads is also trying to read from the FIFO.

**Function properties (list may not be complete)**

**isr-ok**

**Parameters**
• `fifo` – Address of the FIFO queue.

**Returns**
Non-zero if the FIFO queue is empty.

**Returns**
0 if data is available.

`k_fifo_peek_head(fifo)`
Peek element at the head of a FIFO queue.

Return element from the head of FIFO queue without removing it. A usecase for this is if elements of the FIFO object are themselves containers. Then on each iteration of processing, a head container will be peeked, and some data processed out of it, and only if the container is empty, it will be completely remove from the FIFO queue.

**Parameters**
• `fifo` – Address of the FIFO queue.

**Returns**
Head element, or NULL if the FIFO queue is empty.

`k_fifo_peek_tail(fifo)`
Peek element at the tail of FIFO queue.

Return element from the tail of FIFO queue (without removing it). A usecase for this is if elements of the FIFO queue are themselves containers. Then it may be useful to add more data to the last container in a FIFO queue.

**Parameters**
• `fifo` – Address of the FIFO queue.

**Returns**
Tail element, or NULL if a FIFO queue is empty.

`K_FIFO_DEFINE(name)`
Statically define and initialize a FIFO queue.

The FIFO queue can be accessed outside the module where it is defined using:

```c
extern struct k_fifo <name>;
```

**Parameters**
• `name` – Name of the FIFO queue.
**LIFOs**

A **LIFO** is a kernel object that implements a traditional last in, first out (LIFO) queue, allowing threads and ISRs to add and remove data items of any size.

- **Concepts**
- **Implementation**
  - Defining a LIFO
  - Writing to a LIFO
  - Reading from a LIFO
- **Suggested Uses**
- **Configuration Options**
- **API Reference**

**Concepts**  Any number of LIFOs can be defined (limited only by available RAM). Each LIFO is referenced by its memory address.

A LIFO has the following key properties:

- A **queue** of data items that have been added but not yet removed. The queue is implemented as a simple linked list.

A LIFO must be initialized before it can be used. This sets its queue to empty.

LIFO data items must be aligned on a word boundary, as the kernel reserves the first word of an item for use as a pointer to the next data item in the queue. Consequently, a data item that holds \( N \) bytes of application data requires \( N+4 \) (or \( N+8 \)) bytes of memory. There are no alignment or reserved space requirements for data items if they are added with `k_lifo_alloc_put()`, instead additional memory is temporarily allocated from the calling thread's resource pool.

**Note:** LIFO data items are restricted to single active instance across all LIFO data queues. Any attempt to re-add a LIFO data item to a queue before it has been removed from the queue to which it was previously added will result in undefined behavior.

A data item may be **added** to a LIFO by a thread or an ISR. The item is given directly to a waiting thread, if one exists; otherwise the item is added to the LIFO's queue. There is no limit to the number of items that may be queued.

A data item may be **removed** from a LIFO by a thread. If the LIFO's queue is empty a thread may choose to wait for a data item to be given. Any number of threads may wait on an empty LIFO simultaneously. When a data item is added, it is given to the highest priority thread that has waited longest.

**Note:** The kernel does allow an ISR to remove an item from a LIFO, however the ISR must not attempt to wait if the LIFO is empty.

**Implementation**

**Defining a LIFO** A LIFO is defined using a variable of type `k_lifo`. It must then be initialized by calling `k_lifo_init()`.

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The following defines and initializes an empty LIFO.

```c
struct k_lifo my_lifo;
k_lifo_init(&my_lifo);
```

Alternatively, an empty LIFO can be defined and initialized at compile time by calling `K_LIFO_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_LIFO_DEFINE(my_lifo);
```

**Writing to a LIFO** A data item is added to a LIFO by calling `k_lifo_put()`.

The following code builds on the example above, and uses the LIFO to send data to one or more consumer threads.

```c
struct data_item_t {
    void *LIFO_reserved;  /* 1st word reserved for use by LIFO */
    ...
};
struct data_item_t tx_data;

void producer_thread(int unused1, int unused2, int unused3)
{
    while (1) {
        /* create data item to send */
        tx_data = ...
        /* send data to consumers */
        k_lifo_put(&my_lifo, &tx_data);
        ...
    }
}
```

A data item can be added to a LIFO with `k_lifo_alloc_put()`. With this API, there is no need to reserve space for the kernel's use in the data item, instead additional memory will be allocated from the calling thread’s resource pool until the item is read.

**Reading from a LIFO** A data item is removed from a LIFO by calling `k_lifo_get()`.

The following code builds on the example above, and uses the LIFO to obtain data items from a producer thread, which are then processed in some manner.

```c
void consumer_thread(int unused1, int unused2, int unused3)
{
    struct data_item_t  *rx_data;

    while (1) {
        rx_data = k_lifo_get(&my_lifo, K_FOREVER);
        /* process LIFO data item */
        ...
    }
}
```
**Suggested Uses**  Use a LIFO to asynchronously transfer data items of arbitrary size in a “last in, first out” manner.

**Configuration Options**  Related configuration options:
- None.

**API Reference**

*group lifo_apis*

**Defines**

\[k_{\text{lifo\_init}}(\text{lifo})\]

Initialize a LIFO queue.

This routine initializes a LIFO queue object, prior to its first use.

**Parameters**
- \(\text{lifo} – \) Address of the LIFO queue.

\[k_{\text{lifo\_put}}(\text{lifo}, \text{data})\]

Add an element to a LIFO queue.

This routine adds a data item to \(\text{lifo}\). A LIFO queue data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel's use.

**Function properties (list may not be complete)**

\(\text{isr-ok}\)

**Parameters**
- \(\text{lifo} – \) Address of the LIFO queue.
- \(\text{data} – \) Address of the data item.

\[k_{\text{lifo\_alloc\_put}}(\text{lifo}, \text{data})\]

Add an element to a LIFO queue.

This routine adds a data item to \(\text{lifo}\). There is an implicit memory allocation to create an additional temporary bookkeeping data structure from the calling thread's resource pool, which is automatically freed when the item is removed. The data itself is not copied.

**Function properties (list may not be complete)**

\(\text{isr-ok}\)

**Parameters**
- \(\text{lifo} – \) Address of the LIFO.
- \(\text{data} – \) Address of the data item.

**Return values**
- \(0 – \) on success
- \(-\text{ENOMEM} – \) if there isn't sufficient RAM in the caller’s resource pool
**k_lifo_get** (lifo, timeout)

Get an element from a LIFO queue.

This routine removes a data item from LIFO in a “last in, first out” manner. The first word of the data item is reserved for the kernel's use.

**Function properties (list may not be complete)**

- **isr-ok**

**Note:** `timeout` must be set to `K_NO_WAIT` if called from ISR.

**Parameters**

- `lifo` – Address of the LIFO queue.
- `timeout` – Waiting period to obtain a data item, or one of the special values `K_NO_WAIT` and `K_FOREVER`.

**Returns**

Address of the data item if successful; NULL if returned without waiting, or waiting period timed out.

**K_LIFO_DEFINE**(name)

Statically define and initialize a LIFO queue.

The LIFO queue can be accessed outside the module where it is defined using:

```c
extern struct k_lifo <name>;
```

**Parameters**

- `name` – Name of the fifo.

**Stacks**

A stack is a kernel object that implements a traditional last in, first out (LIFO) queue, allowing threads and ISRs to add and remove a limited number of integer data values.

- **Concepts**
- **Implementation**
  - *Defining a Stack*
  - *Pushing to a Stack*
  - *Popping from a Stack*
- **Suggested Uses**
- **Configuration Options**
- **API Reference**

**Concepts** Any number of stacks can be defined (limited only by available RAM). Each stack is referenced by its memory address.

A stack has the following key properties:
A queue of integer data values that have been added but not yet removed. The queue is implemented using an array of stack_data_t values and must be aligned on a native word boundary. The stack_data_t type corresponds to the native word size i.e. 32 bits or 64 bits depending on the CPU architecture and compilation mode.

A maximum quantity of data values that can be queued in the array.

A stack must be initialized before it can be used. This sets its queue to empty.

A data value can be added to a stack by a thread or an ISR. The value is given directly to a waiting thread, if one exists; otherwise the value is added to the LIFO's queue.

Note: If CONFIG_NO_RUNTIME_CHECKS is enabled, the kernel will not detect and prevent attempts to add a data value to a stack that has already reached its maximum quantity of queued values. Adding a data value to a stack that is already full will result in array overflow, and lead to unpredictable behavior.

A data value may be removed from a stack by a thread. If the stack's queue is empty a thread may choose to wait for it to be given. Any number of threads may wait on an empty stack simultaneously. When a data item is added, it is given to the highest priority thread that has waited longest.

Note: The kernel does allow an ISR to remove an item from a stack, however the ISR must not attempt to wait if the stack is empty.

Implementation

Defining a Stack  A stack is defined using a variable of type k_stack. It must then be initialized by calling k_stack_init() or k_stack_alloc_init(). In the latter case, a buffer is not provided and it is instead allocated from the calling thread's resource pool.

The following code defines and initializes an empty stack capable of holding up to ten word-sized data values.

```c
#define MAX_ITEMS 10

stack_data_t my_stack_array[MAX_ITEMS];
struct k_stack my_stack;

k_stack_init(&my_stack, my_stack_array, MAX_ITEMS);
```

Alternatively, a stack can be defined and initialized at compile time by calling K_STACK_DEFINE.

The following code has the same effect as the code segment above. Observe that the macro defines both the stack and its array of data values.

```c
K_STACK_DEFINE(my_stack, MAX_ITEMS);
```

Pushing to a Stack  A data item is added to a stack by calling k_stack_push().

The following code builds on the example above, and shows how a thread can create a pool of data structures by saving their memory addresses in a stack.

```c
/* define array of data structures */
struct my_buffer_type {
    int field;
};
```
Zephyr Project Documentation, Release 3.6.0-rc3

Popping from a Stack

A data item is taken from a stack by calling `k_stack_pop()`. The following code builds on the example above, and shows how a thread can dynamically allocate an unused data structure. When the data structure is no longer required, the thread must push its address back on the stack to allow the data structure to be reused.

```c
struct my_buffer_type *new_buffer;

k_stack_pop(&buffer_stack, (stack_data_t *)&new_buffer, K_FOREVER);
new_buffer->field1 = ...
```

Suggested Uses

Use a stack to store and retrieve integer data values in a “last in, first out” manner, when the maximum number of stored items is known.

Configuration Options

Related configuration options:

- None.

API Reference

group stack_apis

Defines

```c
K_STACK_DEFINE(name, stack_num_entries)

Statically define and initialize a stack.

The stack can be accessed outside the module where it is defined using:

```c
extern struct k_stack <name>;
```

Parameters

- `name` – Name of the stack.
- `stack_num_entries` – Maximum number of values that can be stacked.

Functions

```c
void k_stack_init(struct k_stack *stack, stack_data_t *buffer, uint32_t num_entries)

Initialize a stack.

This routine initializes a stack object, prior to its first use.
```

Parameters
- **stack** – Address of the stack.
- **buffer** – Address of array used to hold stacked values.
- **num_entries** – Maximum number of values that can be stacked.

```c
int32_t k_stack_alloc_init(struct k_stack *stack, uint32_t num_entries)
```

Initialize a stack.

This routine initializes a stack object, prior to its first use. Internal buffers will be allocated from the calling thread’s resource pool. This memory will be released if `k_stack_cleanup()` is called, or userspace is enabled and the stack object loses all references to it.

**Parameters**
- **stack** – Address of the stack.
- **num_entries** – Maximum number of values that can be stacked.

**Returns**
- `ENOMEM` if memory couldn’t be allocated

```c
int k_stack_cleanup(struct k_stack *stack)
```

Release a stack’s allocated buffer.

If a stack object was given a dynamically allocated buffer via `k_stack_alloc_init()`, this will free it. This function does nothing if the buffer wasn’t dynamically allocated.

**Parameters**
- **stack** – Address of the stack.

**Return values**
- `0` – on success
- `-EAGAIN` – when object is still in use

```c
int k_stack_push(struct k_stack *stack, stack_data_t data)
```

Push an element onto a stack.

**Function properties (list may not be complete)**

` isr-ok`

**Parameters**
- **stack** – Address of the stack.
- **data** – Value to push onto the stack.

**Return values**
- `0` – on success
- `-ENOMEM` – if stack is full

```c
int k_stack_pop(struct k_stack *stack, stack_data_t *data, k_timeout_t timeout)
```

Pop an element from a stack.

This routine removes a stack_data_t value from stack in a “last in, first out” manner and stores the value in `data`. 

3.1. Kernel Services
Function properties (list may not be complete)

isr-ok

Note: timeout must be set to K_NO_WAIT if called from ISR.

Parameters

- stack – Address of the stack.
- data – Address of area to hold the value popped from the stack.
- timeout – Waiting period to obtain a value, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

- 0 – Element popped from stack.
- -EBUSY – Returned without waiting.
- -EAGAIN – Waiting period timed out.

Message Queues

A message queue is a kernel object that implements a simple message queue, allowing threads and ISRs to asynchronously send and receive fixed-size data items.

- Concepts
- Implementation
  - Defining a Message Queue
  - Writing to a Message Queue
  - Reading from a Message Queue
  - Peeking into a Message Queue
- Suggested Uses
- Configuration Options
- API Reference

Concepts

Any number of message queues can be defined (limited only by available RAM). Each message queue is referenced by its memory address.

A message queue has the following key properties:

- A ring buffer of data items that have been sent but not yet received.
- A data item size, measured in bytes.
- A maximum quantity of data items that can be queued in the ring buffer.

A message queue must be initialized before it can be used. This sets its ring buffer to empty.

A data item can be sent to a message queue by a thread or an ISR. The data item pointed at by the sending thread is copied to a waiting thread, if one exists; otherwise the item is copied to the message queue's ring buffer, if space is available. In either case, the size of the data area being sent must equal the message queue's data item size.
If a thread attempts to send a data item when the ring buffer is full, the sending thread may choose to wait for space to become available. Any number of sending threads may wait simultaneously when the ring buffer is full; when space becomes available it is given to the highest priority sending thread that has waited the longest.

A data item can be received from a message queue by a thread. The data item is copied to the area specified by the receiving thread; the size of the receiving area must equal the message queue's data item size.

If a thread attempts to receive a data item when the ring buffer is empty, the receiving thread may choose to wait for a data item to be sent. Any number of receiving threads may wait simultaneously when the ring buffer is empty; when a data item becomes available it is given to the highest priority receiving thread that has waited the longest.

A thread can also peek at the message on the head of a message queue without removing it from the queue. The data item is copied to the area specified by the receiving thread; the size of the receiving area must equal the message queue's data item size.

**Note:** The kernel does allow an ISR to receive an item from a message queue, however the ISR must not attempt to wait if the message queue is empty.

**Note:** Alignment of the message queue's ring buffer is not necessary. The underlying implementation uses `memcpy()` (which is alignment-agnostic) and does not expose any internal pointers.

### Implementation

#### Defining a Message Queue

A message queue is defined using a variable of type `k_msgq`. It must then be initialized by calling `k_msgq_init()`.

The following code defines and initializes an empty message queue that is capable of holding 10 items, each of which is 12 bytes long.

```c
struct data_item_type {
    uint32_t field1;
    uint32_t field2;
    uint32_t field3;
};

char my_msgq_buffer[10 * sizeof(struct data_item_type)];
struct k_msgq my_msgq;

k_msgq_init(&my_msgq, my_msgq_buffer, sizeof(struct data_item_type), 10);
```

Alternatively, a message queue can be defined and initialized at compile time by calling `K_MSGQ_DEFINE`.

The following code has the same effect as the code segment above. Observe that the macro defines both the message queue and its buffer.

```c
K_MSGQ_DEFINE(my_msgq, sizeof(struct data_item_type), 10, 1);
```

#### Writing to a Message Queue

A data item is added to a message queue by calling `k_msgq_put()`.

The following code builds on the example above, and uses the message queue to pass data items from a producing thread to one or more consuming threads. If the message queue fills up because the consumers can't keep up, the producing thread throws away all existing data so the newer data can be saved.
`void producer_thread(void)`

```c
    struct data_item_type data;

    while (!) {
        /* create data item to send (e.g. measurement, timestamp, ...) */
        data = ...;

        /* send data to consumers */
        while (k_msgq_put(&my_msgq, &data, K_NO_WAIT) != 0) {
            /* message queue is full: purge old data & try again */
            k_msgq_purge(&my_msgq);
        }

        /* data item was successfully added to message queue */
    }
```

**Reading from a Message Queue**  A data item is taken from a message queue by calling `k_msgq_get()`.

The following code builds on the example above, and uses the message queue to process data items generated by one or more producing threads. Note that the return value of `k_msgq_get()` should be tested as −ENOMEM can be returned due to `k_msgq_purge()`.

`void consumer_thread(void)`

```c
    struct data_item_type data;

    while (!) {
        /* get a data item */
        k_msgq_get(&my_msgq, &data, K_FOREVER);

        /* process data item */
        ...
    }
```

**Peeking into a Message Queue**  A data item is read from a message queue by calling `k_msgq_peek()`.

The following code peeks into the message queue to read the data item at the head of the queue that is generated by one or more producing threads.

`void consumer_thread(void)`

```c
    struct data_item_type data;

    while (!) {
        /* read a data item by peeking into the queue */
        k_msgq_peek(&my_msgq, &data);

        /* process data item */
        ...
    }
```

**Suggested Uses**  Use a message queue to transfer small data items between threads in an asynchronous manner.
**Note:** A message queue can be used to transfer large data items, if desired. However, this can increase interrupt latency as interrupts are locked while a data item is written or read. The time to write or read a data item increases linearly with its size since the item is copied in its entirety to or from the buffer in memory. For this reason, it is usually preferable to transfer large data items by exchanging a pointer to the data item, rather than the data item itself.

A synchronous transfer can be achieved by using the kernel’s mailbox object type.

**Configuration Options**  
Related configuration options:
- None.

**API Reference**  
*group msgq_apis*

**Defines**

```c
K_MSGQ_FLAG_ALLOC
K_MSGQ_DEFINE(q_name, q_msg_size, q_max_msgs, q_align)
```

Statically define and initialize a message queue.

The message queue's ring buffer contains space for `q_max_msgs` messages, each of which is `q_msg_size` bytes long. Alignment of the message queue's ring buffer is not necessary, setting `q_align` to 1 is sufficient.

The message queue can be accessed outside the module where it is defined using:

```c
extern struct k_msgq <name>;
```

**Parameters**
- `q_name` – Name of the message queue.
- `q_msg_size` – Message size (in bytes).
- `q_max_msgs` – Maximum number of messages that can be queued.
- `q_align` – Alignment of the message queue's ring buffer (power of 2).

**Functions**

```c
void k_msgq_init(struct k_msgq *msgq, char *buffer, size_t msg_size, uint32_t max_msgs)
```

Initialize a message queue.

This routine initializes a message queue object, prior to its first use.

The message queue's ring buffer must contain space for `max_msgs` messages, each of which is `msg_size` bytes long. Alignment of the message queue's ring buffer is not necessary.

**Parameters**
- `msgq` – Address of the message queue.
- `buffer` – Pointer to ring buffer that holds queued messages.
• **msg_size** – Message size (in bytes).
• **max_msgs** – Maximum number of messages that can be queued.

```c
int k_msgq_alloc_init(struct k_msgq *msgq, size_t msg_size, uint32_t max_msgs)
```

Initialize a message queue.

This routine initializes a message queue object, prior to its first use, allocating its internal ring buffer from the calling thread’s resource pool.

Memory allocated for the ring buffer can be released by calling `k_msgq_cleanup()`, or if userspace is enabled and the msgq object loses all of its references.

**Parameters**

• **msgq** – Address of the message queue.
• **msg_size** – Message size (in bytes).
• **max_msgs** – Maximum number of messages that can be queued.

**Returns**

0 on success, -ENOMEM if there was insufficient memory in the thread’s resource pool, or -EINVAL if the size parameters cause an integer overflow.

```c
int k_msgq_cleanup(struct k_msgq *msgq)
```

Release allocated buffer for a queue.

Releases memory allocated for the ring buffer.

**Parameters**

• **msgq** – message queue to cleanup

**Return values**

• 0 – on success
• -EBUSY – Queue not empty

```c
int k_msgq_put(struct k_msgq *msgq, const void *data, k_timeout_t timeout)
```

Send a message to a message queue.

This routine sends a message to message queue `q`.

**Function properties (list may not be complete)**

`isr-ok`

**Note:**  The message content is copied from `data` into `msgq` and the `data` pointer is not retained, so the message content will not be modified by this function.

**Parameters**

• **msgq** – Address of the message queue.
• **data** – Pointer to the message.
• **timeout** – Non-negative waiting period to add the message, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**

• 0 – Message sent.
• -ENOMEM – Returned without waiting or queue purged.
• -EAGAIN – Waiting period timed out.
int k_msgq_get(struct k_msgq *msgq, void *data, k_timeout_t timeout)
Receive a message from a message queue.
This routine receives a message from message queue q in a “first in, first out” manner.

Function properties (list may not be complete)
isr-ok

Note: timeout must be set to K_NO_WAIT if called from ISR.

Parameters
• msgq – Address of the message queue.
• data – Address of area to hold the received message.
• timeout – Waiting period to receive the message, or one of the special values K_NO_WAIT and K_FOREVER.

Return values
• 0 – Message received.
• -ENOMSG – Returned without waiting.
• -EAGAIN – Waiting period timed out.

int k_msgq_peek(struct k_msgq *msgq, void *data)
Peek/read a message from a message queue.
This routine reads a message from message queue q in a “first in, first out” manner and leaves the message in the queue.

Function properties (list may not be complete)
isr-ok

Parameters
• msgq – Address of the message queue.
• data – Address of area to hold the message read from the queue.

Return values
• 0 – Message read.
• -ENOMSG – Returned when the queue has no message.

int k_msgq_peek_at(struct k_msgq *msgq, void *data, uint32_t idx)
Peek/read a message from a message queue at the specified index.
This routine reads a message from message queue at the specified index and leaves the message in the queue. k_msgq_peek_at(msgq, data, 0) is equivalent to k_msgq_peek(msgq, data)

Function properties (list may not be complete)
isr-ok
Parameters

- `msgq` – Address of the message queue.
- `data` – Address of area to hold the message read from the queue.
- `idx` – Message queue index at which to peek

Return values

- `0` – Message read.
- `-ENOMSG` – Returned when the queue has no message at index.

```c
void k_msgq_purge(struct k_msgq *msgq)
```

Purge a message queue.

This routine discards all unreceived messages in a message queue’s ring buffer. Any threads that are blocked waiting to send a message to the message queue are unblocked and see an -ENOMSG error code.

Parameters

- `msgq` – Address of the message queue.

```c
uint32_t k_msgq_num_free_get(struct k_msgq *msgq)
```

Get the amount of free space in a message queue.

This routine returns the number of unused entries in a message queue’s ring buffer.

Parameters

- `msgq` – Address of the message queue.

Returns

Number of unused ring buffer entries.

```c
void k_msgq_get_attrs(struct k_msgq *msgq, struct k_msgqAttrs *attrs)
```

Get basic attributes of a message queue.

This routine fetches basic attributes of message queue into attr argument.

Parameters

- `msgq` – Address of the message queue.
- `attrs` – pointer to message queue attribute structure.

```c
uint32_t k_msgq_num_used_get(struct k_msgq *msgq)
```

Get the number of messages in a message queue.

This routine returns the number of messages in a message queue’s ring buffer.

Parameters

- `msgq` – Address of the message queue.

Returns

Number of messages.

```c
struct k_msgq
```

`#include <kernel.h>` Message Queue Structure.

Public Members
_wait_q_t wait_q
   Message queue wait queue.

struct k_spinlock lock
   Lock.

size_t msg_size
   Message size.

uint32_t max_msgs
   Maximal number of messages.

cchar *buffer_start
   Start of message buffer.

cchar *buffer_end
   End of message buffer.

cchar *read_ptr
   Read pointer.

cchar *write_ptr
   Write pointer.

uint32_t used_msgs
   Number of used messages.

uint8_t flags
   Message queue.

struct k_msgq_attrs
   #include <kernel.h> Message Queue Attributes.

Public Members

size_t msg_size
   Message Size.

uint32_t max_msgs
   Maximal number of messages.

uint32_t used_msgs
   Used messages.

Mailboxes

A mailbox is a kernel object that provides enhanced message queue capabilities that go beyond the capabilities of a message queue object. A mailbox allows threads to send and receive messages of any size synchronously or asynchronously.
Concepts Any number of mailboxes can be defined (limited only by available RAM). Each mailbox is referenced by its memory address.

A mailbox has the following key properties:

- A **send queue** of messages that have been sent but not yet received.
- A **receive queue** of threads that are waiting to receive a message.

A mailbox must be initialized before it can be used. This sets both of its queues to empty.

A mailbox allows threads, but not ISRs, to exchange messages. A thread that sends a message is known as the **sending thread**, while a thread that receives the message is known as the **receiving thread**. Each message may be received by only one thread (i.e. point-to-multipoint and broadcast messaging is not supported).

Messages exchanged using a mailbox are handled non-anonymously, allowing both threads participating in an exchange to know (and even specify) the identity of the other thread.

Message Format A **message descriptor** is a data structure that specifies where a message's data is located, and how the message is to be handled by the mailbox. Both the sending thread and the receiving thread supply a message descriptor when accessing a mailbox. The mailbox uses the message descriptors to perform a message exchange between compatible sending and receiving threads. The mailbox also updates certain message descriptor fields during the exchange, allowing both threads to know what has occurred.

A mailbox message contains zero or more bytes of **message data**. The size and format of the message data is application-defined, and can vary from one message to the next.

A **message buffer** is an area of memory provided by the thread that sends or receives the message data. An array or structure variable can often be used for this purpose.

A message that has neither form of message data is called an **empty message**.

Note: A message whose message buffer exists, but contains zero bytes of actual data, is **not** an empty message.
Message Lifecycle  The life cycle of a message is straightforward. A message is created when it is given to a mailbox by the sending thread. The message is then owned by the mailbox until it is given to a receiving thread. The receiving thread may retrieve the message data when it receives the message from the mailbox, or it may perform data retrieval during a second, subsequent mailbox operation. Only when data retrieval has occurred is the message deleted by the mailbox.

Thread Compatibility  A sending thread can specify the address of the thread to which the message is sent, or send it to any thread by specifying K_ANY. Likewise, a receiving thread can specify the address of the thread from which it wishes to receive a message, or it can receive a message from any thread by specifying K_ANY. A message is exchanged only when the requirements of both the sending thread and receiving thread are satisfied; such threads are said to be compatible.

For example, if thread A sends a message to thread B (and only thread B) it will be received by thread B if thread B tries to receive a message from thread A or if thread B tries to receive from any thread. The exchange will not occur if thread B tries to receive a message from thread C. The message can never be received by thread C, even if it tries to receive a message from thread A (or from any thread).

Message Flow Control  Mailbox messages can be exchanged synchronously or asynchronously. In a synchronous exchange, the sending thread blocks until the message has been fully processed by the receiving thread. In an asynchronous exchange, the sending thread does not wait until the message has been received by another thread before continuing; this allows the sending thread to do other work (such as gather data that will be used in the next message) before the message is given to a receiving thread and fully processed. The technique used for a given message exchange is determined by the sending thread.

The synchronous exchange technique provides an implicit form of flow control, preventing a sending thread from generating messages faster than they can be consumed by receiving threads. The asynchronous exchange technique provides an explicit form of flow control, which allows a sending thread to determine if a previously sent message still exists before sending a subsequent message.

Implementation

Defining a Mailbox  A mailbox is defined using a variable of type k_mbox. It must then be initialized by calling k_mbox_init().

The following code defines and initializes an empty mailbox.

```c
struct k_mbox my_mailbox;
k_mbox_init(&my_mailbox);
```

Alternatively, a mailbox can be defined and initialized at compile time by calling K_MBOX_DEFINE.

The following code has the same effect as the code segment above.

```c
K_MBOX_DEFINE(my_mailbox);
```

Message Descriptors  A message descriptor is a structure of type k_mbox_msg. Only the fields listed below should be used; any other fields are for internal mailbox use only.

info  A 32-bit value that is exchanged by the message sender and receiver, and whose meaning is defined by the application. This exchange is bi-directional, allowing the sender to pass
a value to the receiver during any message exchange, and allowing the receiver to pass a value to the sender during a synchronous message exchange.

**size**
The message data size, in bytes. Set it to zero when sending an empty message, or when sending a message buffer with no actual data. When receiving a message, set it to the maximum amount of data desired, or to zero if the message data is not wanted. The mailbox updates this field with the actual number of data bytes exchanged once the message is received.

**tx_data**
A pointer to the sending thread's message buffer. Set it to `NULL` when sending an empty message. Leave this field uninitialized when receiving a message.

**tx_target_thread**
The address of the desired receiving thread. Set it to `K_ANY` to allow any thread to receive the message. Leave this field uninitialized when receiving a message. The mailbox updates this field with the actual receiver's address once the message is received.

**rx_source_thread**
The address of the desired sending thread. Set it to `K_ANY` to receive a message sent by any thread. Leave this field uninitialized when sending a message. The mailbox updates this field with the actual sender's address when the message is put into the mailbox.

### Sending a Message

A thread sends a message by first creating its message data, if any. Next, the sending thread creates a message descriptor that characterizes the message to be sent, as described in the previous section.

Finally, the sending thread calls a mailbox send API to initiate the message exchange. The message is immediately given to a compatible receiving thread, if one is currently waiting. Otherwise, the message is added to the mailbox's send queue.

Any number of messages may exist simultaneously on a send queue. The messages in the send queue are sorted according to the priority of the sending thread. Messages of equal priority are sorted so that the oldest message can be received first.

For a synchronous send operation, the operation normally completes when a receiving thread has both received the message and retrieved the message data. If the message is not received before the waiting period specified by the sending thread is reached, the message is removed from the mailbox's send queue and the send operation fails. When a send operation completes successfully the sending thread can examine the message descriptor to determine which thread received the message, how much data was exchanged, and the application-defined info value supplied by the receiving thread.

**Note:** A synchronous send operation may block the sending thread indefinitely, even when the thread specifies a maximum waiting period. The waiting period only limits how long the mailbox waits before the message is received by another thread. Once a message is received there is no limit to the time the receiving thread may take to retrieve the message data and unblock the sending thread.

For an asynchronous send operation, the operation always completes immediately. This allows the sending thread to continue processing regardless of whether the message is given to a receiving thread immediately or added to the send queue. The sending thread may optionally specify a semaphore that the mailbox gives when the message is deleted by the mailbox, for example, when the message has been received and its data retrieved by a receiving thread. The use of a semaphore allows the sending thread to easily implement a flow control mechanism that ensures that the mailbox holds no more than an application-specified number of messages from a sending thread (or set of sending threads) at any point in time.
**Note:** A thread that sends a message asynchronously has no way to determine which thread received the message, how much data was exchanged, or the application-defined info value supplied by the receiving thread.

### Sending an Empty Message

This code uses a mailbox to synchronously pass 4 byte random values to any consuming thread that wants one. The message “info” field is large enough to carry the information being exchanged, so the data portion of the message isn’t used.

```c
void producer_thread(void)
{
    struct k_mbox_msg send_msg;

    while (1) {
        /* generate random value to send */
        uint32_t random_value = sys_rand32_get();

        /* prepare to send empty message */
        send_msg.info = random_value;
        send_msg.size = 0;
        send_msg.tx_data = NULL;
        send_msg.tx_target_thread = K_ANY;

        /* send message and wait until a consumer receives it */
        k_mbox_put(&my_mailbox, &send_msg, K_FOREVER);
    }
}
```

### Sending Data Using a Message Buffer

This code uses a mailbox to synchronously pass variable-sized requests from a producing thread to any consuming thread that wants it. The message “info” field is used to exchange information about the maximum size message buffer that each thread can handle.

```c
void producer_thread(void)
{
    char buffer[100];
    int buffer_bytes_used;

    struct k_mbox_msg send_msg;

    while (1) {
        /* generate data to send */
        ...
        buffer_bytes_used = ...
        memcpy(buffer, source, buffer_bytes_used);

        /* prepare to send message */
        send_msg.info = buffer_bytes_used;
        send_msg.size = buffer_bytes_used;
        send_msg.tx_data = buffer;
        send_msg.tx_target_thread = K_ANY;

        /* send message and wait until a consumer receives it */
        k_mbox_put(&my_mailbox, &send_msg, K_FOREVER);

        /* info, size, and tx_target_thread fields have been updated */
    }
}
```
Receiving a Message  A thread receives a message by first creating a message descriptor that characterizes the message it wants to receive. It then calls one of the mailbox receive APIs. The mailbox searches its send queue and takes the message from the first compatible thread it finds. If no compatible thread exists, the receiving thread may choose to wait for one. If no compatible thread appears before the waiting period specified by the receiving thread is reached, the receive operation fails. Once a receive operation completes successfully the receiving thread can examine the message descriptor to determine which thread sent the message, how much data was exchanged, and the application-defined info value supplied by the sending thread.

Any number of receiving threads may wait simultaneously on a mailboxes' receive queue. The threads are sorted according to their priority; threads of equal priority are sorted so that the one that started waiting first can receive a message first.

Note: Receiving threads do not always receive messages in a first in, first out (FIFO) order, due to the thread compatibility constraints specified by the message descriptors. For example, if thread A waits to receive a message only from thread X and then thread B waits to receive a message from thread Y, an incoming message from thread Y to any thread will be given to thread B and thread A will continue to wait.

The receiving thread controls both the quantity of data it retrieves from an incoming message and where the data ends up. The thread may choose to take all of the data in the message, to take only the initial part of the data, or to take no data at all. Similarly, the thread may choose to have the data copied into a message buffer of its choice.

The following sections outline various approaches a receiving thread may use when retrieving message data.

Retrieving Data at Receive Time  The most straightforward way for a thread to retrieve message data is to specify a message buffer when the message is received. The thread indicates both the location of the message buffer (which must not be NULL) and its size.

The mailbox copies the message's data to the message buffer as part of the receive operation. If the message buffer is not big enough to contain all of the message's data, any uncopied data is lost. If the message is not big enough to fill all of the buffer with data, the unused portion of the message buffer is left unchanged. In all cases the mailbox updates the receiving thread's message descriptor to indicate how many data bytes were copied (if any).

The immediate data retrieval technique is best suited for small messages where the maximum size of a message is known in advance.

The following code uses a mailbox to process variable-sized requests from any producing thread, using the immediate data retrieval technique. The message “info” field is used to exchange information about the maximum size message buffer that each thread can handle.

```c
void consumer_thread(void)
{
    struct k_mbox_msg recv_msg;
}
```
char buffer[100];

int i;
int total;

while (1) {
    /* prepare to receive message */
    recv_msg.info = 100;
    recv_msg.size = 100;
    recv_msg.rx_source_thread = K_ANY;

    /* get a data item, waiting as long as needed */
    k_mbox_get(&my_mailbox, &recv_msg, buffer, K_FOREVER);

    /* info, size, and rx_source_thread fields have been updated */
    /* verify that message data was fully received */
    if (recv_msg.info != recv_msg.size) {
        printf("some message data dropped during transfer!");
        printf("sender tried to send \%d bytes", recv_msg.info);
    }

    /* compute sum of all message bytes (from 0 to 100 of them) */
    total = 0;
    for (i = 0; i < recv_msg.size; i++) {
        total += buffer[i];
    }
}

Retrieving Data Later Using a Message Buffer  A receiving thread may choose to defer message data retrieval at the time the message is received, so that it can retrieve the data into a message buffer at a later time. The thread does this by specifying a message buffer location of NULL and a size indicating the maximum amount of data it is willing to retrieve later.

The mailbox does not copy any message data as part of the receive operation. However, the mailbox still updates the receiving thread's message descriptor to indicate how many data bytes are available for retrieval.

The receiving thread must then respond as follows:

- If the message descriptor size is zero, then either the sender's message contained no data or the receiving thread did not want to receive any data. The receiving thread does not need to take any further action, since the mailbox has already completed data retrieval and deleted the message.

- If the message descriptor size is non-zero and the receiving thread still wants to retrieve the data, the thread must call `k_mbox_data_get()` and supply a message buffer large enough to hold the data. The mailbox copies the data into the message buffer and deletes the message.

- If the message descriptor size is non-zero and the receiving thread does not want to retrieve the data, the thread must call `k_mbox_data_get()` and specify a message buffer of NULL. The mailbox deletes the message without copying the data.

The subsequent data retrieval technique is suitable for applications where immediate retrieval of message data is undesirable. For example, it can be used when memory limitations make it impractical for the receiving thread to always supply a message buffer capable of holding the largest possible incoming message.

The following code uses a mailbox's deferred data retrieval mechanism to get message data from a producing thread only if the message meets certain criteria, thereby eliminating unneeded data

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copying. The message “info” field supplied by the sender is used to classify the message.

```c
void consumer_thread(void)
{
    struct k_mbox_msg recv_msg;
    char buffer[10000];

    while (1) {
        /* prepare to receive message */
        recv_msg.size = 10000;
        recv_msg.rx_source_thread = K_ANY;

        /* get message, but not its data */
        k_mbox_get(&my_mailbox, &recv_msg, NULL, K_FOREVER);

        /* get message data for only certain types of messages */
        if (is_message_type_ok(recv_msg.info)) {
            /* retrieve message data and delete the message */
            k_mbox_data_get(&recv_msg, buffer);

            /* process data in "buffer" */
            ...
        } else {
            /* ignore message data and delete the message */
            k_mbox_data_get(&recv_msg, NULL);
        }
    }
}
```

**Suggested Uses**  Use a mailbox to transfer data items between threads whenever the capabilities of a message queue are insufficient.

**Configuration Options**  Related configuration options:

- CONFIG_NUM_MBOX_ASYNC_MSGS

**API Reference**  `group mailbox_apis`

**Defines**

- `K_MBOX_DEFINE(name)`
  
  Statically define and initialize a mailbox.
  
  The mailbox is to be accessed outside the module where it is defined using:

  ```c
  extern struct k_mbox <name>;
  ```

  **Parameters**

  - `name` – Name of the mailbox.

  **Functions**
void k_mbox_init(struct k_mbox *mbox)
    Initialize a mailbox.

This routine initializes a mailbox object, prior to its first use.

**Parameters**

- **mbox** – Address of the mailbox.

int k_mbox_put(struct k_mbox *mbox, struct k_mbox_msg *tx_msg, k_timeout_t timeout)
    Send a mailbox message in a synchronous manner.

This routine sends a message to *mbox* and waits for a receiver to both receive and process it. The message data may be in a buffer or non-existent (i.e. an empty message).

**Parameters**

- **mbox** – Address of the mailbox.
- **tx_msg** – Address of the transmit message descriptor.
- **timeout** – Waiting period for the message to be received, or one of the special values K_NO_WAIT and K_FOREVER. Once the message has been received, this routine waits as long as necessary for the message to be completely processed.

**Return values**

- **0** – Message sent.
- **-ENOMSG** – Returned without waiting.
- **-EAGAIN** – Waiting period timed out.

void k_mbox_async_put(struct k_mbox *mbox, struct k_mbox_msg *tx_msg, struct k_sem *sem)
    Send a mailbox message in an asynchronous manner.

This routine sends a message to *mbox* without waiting for a receiver to process it. The message data may be in a buffer or non-existent (i.e. an empty message). Optionally, the semaphore *sem* will be given when the message has been both received and completely processed by the receiver.

**Parameters**

- **mbox** – Address of the mailbox.
- **tx_msg** – Address of the transmit message descriptor.
- **sem** – Address of a semaphore, or NULL if none is needed.

int k_mbox_get(struct k_mbox *mbox, struct k_mbox_msg *rx_msg, void *buffer, k_timeout_t timeout)
    Receive a mailbox message.

This routine receives a message from *mbox*, then optionally retrieves its data and disposes of the message.

**Parameters**

- **mbox** – Address of the mailbox.
- **rx_msg** – Address of the receive message descriptor.
- **buffer** – Address of the buffer to receive data, or NULL to defer data retrieval and message disposal until later.
- **timeout** – Waiting period for a message to be received, or one of the special values K_NO_WAIT and K_FOREVER.
Return values
- 0 – Message received.
- -ENOMSG – Returned without waiting.
- -EAGAIN – Waiting period timed out.

void k_mbox_data_get(struct k_mbox_msg *rx_msg, void *buffer)
Retrieve mailbox message data into a buffer.
This routine completes the processing of a received message by retrieving its data into
a buffer, then disposing of the message.
Alternatively, this routine can be used to dispose of a received message without re-
trieving its data.

Parameters
- rx_msg – Address of the receive message descriptor.
- buffer – Address of the buffer to receive data, or NULL to discard the
data.

struct k_mbox_msg
#include <kernel.h> Mailbox Message Structure.

Public Members

size_t size
size of message (in bytes)

uint32_t info
application-defined information value

void *tx_data
sender’s message data buffer

k_tid_t rx_source_thread
source thread id

k_tid_t tx_target_thread
target thread id

struct k_mbox
#include <kernel.h> Mailbox Structure.

Public Members

_wait_q_t tx_msg_queue
Transmit messages queue.

_wait_q_t rx_msg_queue
Receive message queue.
Pipes

A pipe is a kernel object that allows a thread to send a byte stream to another thread. Pipes can be used to synchronously transfer chunks of data in whole or in part.

- Concepts
- Implementation
  - Writing to a Pipe
  - Reading from a Pipe
  - Flushing a Pipe’s Buffer
  - Flushing a Pipe
- Suggested uses
- Configuration Options
- API Reference

Concepts  The pipe can be configured with a ring buffer which holds data that has been sent but not yet received; alternatively, the pipe may have no ring buffer.

Any number of pipes can be defined (limited only by available RAM). Each pipe is referenced by its memory address.

A pipe has the following key property:

- A size that indicates the size of the pipe’s ring buffer. Note that a size of zero defines a pipe with no ring buffer.

A pipe must be initialized before it can be used. The pipe is initially empty.

Data is synchronously sent either in whole or in part to a pipe by a thread. If the specified minimum number of bytes can not be immediately satisfied, then the operation will either fail immediately or attempt to send as many bytes as possible and then pend in the hope that the send can be completed later. Accepted data is either copied to the pipe’s ring buffer or directly to the waiting reader(s).

Data is synchronously received from a pipe by a thread. If the specified minimum number of bytes can not be immediately satisfied, then the operation will either fail immediately or attempt to receive as many bytes as possible and then pend in the hope that the receive can be completed later. Accepted data is either copied from the pipe’s ring buffer or directly from the waiting sender(s).

Data may also be flushed from a pipe by a thread. Flushing can be performed either on the entire pipe or on only its ring buffer. Flushing the entire pipe is equivalent to reading all the information in the ring buffer and waiting to be written into a giant temporary buffer which is then discarded. Flushing the ring buffer is equivalent to reading only the data in the ring buffer into a temporary buffer which is then discarded. Flushing the ring buffer does not guarantee that the ring buffer will stay empty; flushing it may allow a pended writer to fill the ring buffer.

Note:  Flushing does not in practice allocate or use additional buffers.

Note:  The kernel does allow for an ISR to flush a pipe from an ISR. It also allows it to send/receive data to/from one provided it does not attempt to wait for space/data.
**Implementation**  A pipe is defined using a variable of type `k_pipe` and an optional character buffer of type `unsigned char`. It must then be initialized by calling `k_pipe_init()`.

The following code defines and initializes an empty pipe that has a ring buffer capable of holding 100 bytes and is aligned to a 4-byte boundary.

```c
unsigned char __aligned__(4) my_ring_buffer[100];
struct k_pipe my_pipe;
k_pipe_init(&my_pipe, my_ring_buffer, sizeof(my_ring_buffer));
```

Alternatively, a pipe can be defined and initialized at compile time by calling `K_PIPE_DEFINE`.

The following code has the same effect as the code segment above. Observe that that macro defines both the pipe and its ring buffer.

```c
K_PIPE_DEFINE(my_pipe, 100, 4);
```

**Writing to a Pipe**  Data is added to a pipe by calling `k_pipe_put()`.

The following code builds on the example above, and uses the pipe to pass data from a producing thread to one or more consuming threads. If the pipe's ring buffer fills up because the consumers can't keep up, the producing thread waits for a specified amount of time.

```c
struct message_header {
    ...
};

void producer_thread(void) {
    unsigned char *data;
    size_t total_size;
    size_t bytes_written;
    int rc;
    ...

    while (1) {
        /* Craft message to send in the pipe */
        data = ...;
        total_size = ...;

        /* send data to the consumers */
        rc = k_pipe_put(&my_pipe, data, total_size, &bytes_written,
                        sizeof(struct message_header), K_NO_WAIT);

        if (rc < 0) {
            /* Incomplete message header sent */
            ...
        } else if (bytes_written < total_size) {
            /* Some of the data was sent */
            ...
        } else {
            /* All data sent */
            ...
        }
    }
}
```

**Reading from a Pipe**  Data is read from the pipe by calling `k_pipe_get()`.

---

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The following code builds on the example above, and uses the pipe to process data items generated by one or more producing threads.

```c
void consumer_thread(void)
{
    unsigned char buffer[120];
    size_t bytes_read;
    struct message_header *header = (struct message_header *)buffer;

    while (!)
    {
        rc = k_pipe_get(&my_pipe, buffer, sizeof(buffer), &bytes_read,
                        sizeof(*header), K_MSEC(100));

        if ((rc < 0) || (bytes_read < sizeof(*header))) {
            /* Incomplete message header received */
            ...
        } else if (header->num_data_bytes + sizeof(*header) > bytes_read) {
            /* Only some data was received */
            ...
        } else {
            /* All data was received */
            ...
        }
    }
}
```

Use a pipe to send streams of data between threads.

**Note:** A pipe can be used to transfer long streams of data if desired. However it is often preferable to send pointers to large data items to avoid copying the data.

### Flushing a Pipe's Buffer

Data is flushed from the pipe's ring buffer by calling `k_pipe_buffer_flush()`.

The following code builds on the examples above, and flushes the pipe's buffer.

```c
void monitor_thread(void)
{
    while (!)
    {
        /* Pipe buffer contains stale data. Flush it. */
        k_pipe_buffer_flush(&my_pipe);
        ...
    }
}
```

### Flushing a Pipe

All data in the pipe is flushed by calling `k_pipe_flush()`.

The following code builds on the examples above, and flushes all the data in the pipe.

```c
void monitor_thread(void)
{
    while (!)
    {
        /* Critical error detected. Flush the entire pipe to reset it. */
        k_pipe_flush(&my_pipe);
        ...
    }
}
```
Suggested uses  Use a pipe to send streams of data between threads.

Note: A pipe can be used to transfer long streams of data if desired. However it is often preferable to send pointers to large data items to avoid copying the data. Copying large data items will negatively impact interrupt latency as a spinlock is held while copying that data.

Configuration Options  Related configuration options:

- CONFIG_PIPES

API Reference

group pipe_apis

Defines

\[ \text{K_PIPE_DEFINE(name, pipe_buffer_size, pipe_align)} \]

Statically define and initialize a pipe.

The pipe can be accessed outside the module where it is defined using:

\[
\text{extern struct k_pipe <name>;}\]

Parameters

- name – Name of the pipe.
- pipe_buffer_size – Size of the pipe's ring buffer (in bytes), or zero if no ring buffer is used.
- pipe_align – Alignment of the pipe's ring buffer (power of 2).

Functions

\[ \text{void k_pipe_init(struct k_pipe *pipe, unsigned char *buffer, size_t size)} \]

Initialize a pipe.

This routine initializes a pipe object, prior to its first use.

Parameters

- pipe – Address of the pipe.
- buffer – Address of the pipe's ring buffer, or NULL if no ring buffer is used.
- size – Size of the pipe's ring buffer (in bytes), or zero if no ring buffer is used.

\[ \text{int k_pipe_cleanup(struct k_pipe *pipe)} \]

Release a pipe's allocated buffer.

If a pipe object was given a dynamically allocated buffer via \[ \text{k_pipe_alloc_init()} \], this will free it. This function does nothing if the buffer wasn't dynamically allocated.

Parameters

- pipe – Address of the pipe.
Return values

- 0 – on success
- -ENOMEM – if memory couldn’t be allocated

int k_pipe_alloc_init(struct k_pipe *pipe, size_t size)
Initialize a pipe and allocate a buffer for it.
Storage for the buffer region will be allocated from the calling thread’s resource pool. This memory will be released if k_pipe_cleanup() is called, or userspace is enabled and the pipe object loses all references to it.
This function should only be called on uninitialized pipe objects.

Parameters

- pipe – Address of the pipe.
- size – Size of the pipe’s ring buffer (in bytes), or zero if no ring buffer is used.

Return values

- 0 – on success
- -ENOMEM – if memory couldn’t be allocated

int k_pipe_put(struct k_pipe *pipe, const void *data, size_t bytes_to_write, size_t *bytes_written, size_t min_xfer, k_timeout_t timeout)
Write data to a pipe.
This routine writes up to bytes_to_write bytes of data to pipe.

Parameters

- pipe – Address of the pipe.
- data – Address of data to write.
- bytes_to_write – Size of data (in bytes).
- bytes_written – Address of area to hold the number of bytes written.
- min_xfer – Minimum number of bytes to write.
- timeout – Waiting period to wait for the data to be written, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

- 0 – At least min_xfer bytes of data were written.
- -EIO – Returned without waiting; zero data bytes were written.
- -EAGAIN – Waiting period timed out; between zero and min_xfer minus one data bytes were written.

int k_pipe_get(struct k_pipe *pipe, void *data, size_t bytes_to_read, size_t *bytes_read, size_t min_xfer, k_timeout_t timeout)
Read data from a pipe.
This routine reads up to bytes_to_read bytes of data from pipe.

Parameters

- pipe – Address of the pipe.
- data – Address to place the data read from pipe.
- bytes_to_read – Maximum number of data bytes to read.
- bytes_read – Address of area to hold the number of bytes read.
• min_xfer – Minimum number of data bytes to read.
• timeout – Waiting period to wait for the data to be read, or one of the special values K_NO_WAIT and K_FOREVER.

Return values
• 0 – At least min_xfer bytes of data were read.
• -EINVAL – invalid parameters supplied
• -EIO – Returned without waiting; zero data bytes were read.
• -EAGAIN – Waiting period timed out; between zero and min_xfer minus one data bytes were read.

size_t k_pipe_read_avail(struct k_pipe *pipe)
Query the number of bytes that may be read from pipe.

Parameters
• pipe – Address of the pipe.

Return values
a – number n such that 0 <= n <= k_pipe::size; the result is zero for unbuffered pipes.

size_t k_pipe_write_avail(struct k_pipe *pipe)
Query the number of bytes that may be written to pipe.

Parameters
• pipe – Address of the pipe.

Return values
a – number n such that 0 <= n <= k_pipe::size; the result is zero for unbuffered pipes.

void k_pipe_flush(struct k_pipe *pipe)
Flush the pipe of write data.

This routine flushes the pipe. Flushing the pipe is equivalent to reading both all the data in the pipe's buffer and all the data waiting to go into that pipe into a large temporary buffer and discarding the buffer. Any writers that were previously pended become unpended.

Parameters
• pipe – Address of the pipe.

void k_pipe_buffer_flush(struct k_pipe *pipe)
Flush the pipe's internal buffer.

This routine flushes the pipe's internal buffer. This is equivalent to reading up to N bytes from the pipe (where N is the size of the pipe's buffer) into a temporary buffer and then discarding that buffer. If there were writers previously pending, then some may unpend as they try to fill up the pipe's emptied buffer.

Parameters
• pipe – Address of the pipe.
Public Members

unsigned char *buffer
    Pipe buffer: may be NULL.

size_t size
    Buffer size.

size_t bytes_used

size_t read_index
    Where in buffer to read from.

size_t write_index
    Where in buffer to write.

struct k_spinlock lock
    Synchronization lock.

_wait_q_t readers
    Reader wait queue.

_wait_q_t writers
    Writer wait queue.

uint8_t flags
    Wait queue.
    Flags

3.1.3 Memory Management

See Memory Management.

3.1.4 Timing

These pages cover timing related services.
Kernel Timing

Zephyr provides a robust and scalable timing framework to enable reporting and tracking of timed events from hardware timing sources of arbitrary precision.

Time Units  Kernel time is tracked in several units which are used for different purposes.

Real time values, typically specified in milliseconds or microseconds, are the default presentation of time to application code. They have the advantages of being universally portable and pervasively understood, though they may not match the precision of the underlying hardware perfectly.

The kernel presents a “cycle” count via the \( k\_cycle\_get\_32() \) and \( k\_cycle\_get\_64() \) APIs. The intent is that this counter represents the fastest cycle counter that the operating system is able to present to the user (for example, a CPU cycle counter) and that the read operation is very fast. The expectation is that very sensitive application code might use this in a polling manner to achieve maximal precision. The frequency of this counter is required to be steady over time, and is available from \( \text{sys\_clock\_hw\_cycles\_per\_sec()} \) (which on almost all platforms is a runtime constant that evaluates to \( \text{CONFIG\_SYS\_CLOCK\_HW\_CYCLES\_PER\_SEC} \)).

For asynchronous timekeeping, the kernel defines a “ticks” concept. A “tick” is the internal count in which the kernel does all its internal uptime and timeout bookkeeping. Interrupts are expected to be delivered on tick boundaries to the extent practical, and no fractional ticks are tracked. The choice of tick rate is configurable via \( \text{CONFIG\_SYS\_CLOCK\_TICKS\_PER\_SEC} \). Defaults on most hardware platforms (ones that support setting arbitrary interrupt timeouts) are expected to be in the range of 10 kHz, with software emulation platforms and legacy drivers using a more traditional 100 Hz value.

Conversion  Zephyr provides an extensively enumerated conversion library with rounding control for all time units. Any unit of “ms” (milliseconds), “us” (microseconds), “tick”, or “cyc” can be converted to any other. Control of rounding is provided, and each conversion is available in “floor” (round down to nearest output unit), “ceil” (round up) and “near” (round to nearest).

Finally the output precision can be specified as either 32 or 64 bits.

For example: \( k\_ms\_to\_ticks\_ceil32() \) will convert a millisecond input value to the next higher number of ticks, returning a result truncated to 32 bits of precision; and \( k\_cyc\_to\_us\_floor64() \) will convert a measured cycle count to an elapsed number of microseconds in a full 64 bits of precision. See the reference documentation for the full enumeration of conversion routines.

On most platforms, where the various counter rates are integral multiples of each other and where the output fits within a single word, these conversions expand to a 2-4 operation sequence, requiring full precision only where actually required and requested.

Uptime The kernel tracks a system uptime count on behalf of the application. This is available at all times via \( k\_uptime\_get() \), which provides an uptime value in milliseconds since system boot. This is expected to be the utility used by most portable application code.

The internal tracking, however, is as a 64 bit integer count of ticks. Apps with precise timing requirements (that are willing to do their own conversions to portable real time units) may access this with \( k\_uptime\_ticks() \).

Timeouts The Zephyr kernel provides many APIs with a “timeout” parameter. Conceptually, this indicates the time at which an event will occur. For example:

- Kernel blocking operations like \( k\_sem\_take() \) or \( k\_queue\_get() \) may provide a timeout after which the routine will return with an error code if no data is available.
• Kernel k_timer objects must specify delays for their duration and period.

• The kernel k_work_delayable API provides a timeout parameter indicating when a work queue item will be added to the system queue.

All these values are specified using a k_timeout_t value. This is an opaque struct type that must be initialized using one of a family of kernel timeout macros. The most common, K_MSEC, defines a time in milliseconds after the current time.

What is meant by “current time” for relative timeouts depends on the context:

• When scheduling a relative timeout from within a timeout callback (e.g. from within the expiry function passed to k_timer_init() or the work handler passed to k_work_init_delayable()), “current time” is the exact time at which the currently firing timeout was originally scheduled even if the “real time” will already have advanced. This is to ensure that timers scheduled from within another timer’s callback will always be calculated with a precise offset to the firing timer. It is thereby possible to fire at regular intervals without introducing systematic clock drift over time.

• When scheduling a timeout from application context, “current time” means the value returned by k_uptime_ticks() at the time at which the kernel receives the timeout value.

Other options for timeout initialization follow the unit conventions described above: K_NSEC(), K_USEC, K_TICKS and K_CYC() specify timeout values that will expire after specified numbers of nanoseconds, microseconds, ticks and cycles, respectively.

Precision of k_timeout_t values is configurable, with the default being 32 bits. Large uptime counts in non-tick units will experience complicated rollover semantics, so it is expected that timing-sensitive applications with long uptimes will be configured to use a 64 bit timeout type.

Finally, it is possible to specify timeouts as absolute times since system boot. A timeout initialized with K_TIMEOUT_ABS_MS indicates a timeout that will expire after the system uptime reaches the specified value. There are likewise nanosecond, microsecond, cycles and ticks variants of this API.

Timing Internals

Timeout Queue All Zephyr k_timeout_t events specified using the API above are managed in a single, global queue of events. Each event is stored in a double-linked list, with an attendant delta count in ticks from the previous event. The action to take on an event is specified as a callback function pointer provided by the subsystem requesting the event, along with a _timeout tracking struct that is expected to be embedded within subsystem-defined data structures (for example: a wait_q struct, or a k_tid_t thread struct).

Note that all variant units passed via a k_timeout_t are converted to ticks once on insertion into the list. There no multiple-conversion steps internal to the kernel, so precision is guaranteed at the tick level no matter how many events exist or how long a timeout might be.

Note that the list structure means that the CPU work involved in managing large numbers of timeouts is quadratic in the number of active timeouts. The API design of the timeout queue was intended to permit a more scalable backend data structure, but no such implementation exists currently.

Timer Drivers Kernel timing at the tick level is driven by a timer driver with a comparatively simple API.

• The driver is expected to be able to “announce” new ticks to the kernel via the sys_clock_announce() call, which passes an integer number of ticks that have elapsed since the last announce call (or system boot). These calls can occur at any time, but the driver is expected to attempt to ensure (to the extent practical given interrupt latency interactions) that they occur near tick boundaries (i.e. not “halfway through” a tick), and most
importantly that they be correct over time and subject to minimal skew vs. other counters and real world time.

- The driver is expected to provide a `sys_clock_set_timeout()` call to the kernel which indicates how many ticks may elapse before the kernel must receive an announce call to trigger registered timeouts. It is legal to announce new ticks before that moment (though they must be correct) but delay after that will cause events to be missed. Note that the timeout value passed here is in a delta from current time, but that does not absolve the driver of the requirement to provide ticks at a steady rate over time. Naive implementations of this function are subject to bugs where the fractional tick gets “reset” incorrectly and causes clock skew.

- The driver is expected to provide a `sys_clock_elapsed()` call which provides a current indication of how many ticks have elapsed (as compared to a real world clock) since the last call to `sys_clock_announce()`, which the kernel needs to test newly arriving timeouts for expiration.

Note that a natural implementation of this API results in a “tickless” kernel, which receives and processes timer interrupts only for registered events, relying on programmable hardware counters to provide irregular interrupts. But a traditional, “ticked” or “dumb” counter driver can be trivially implemented also:

- The driver can receive interrupts at a regular rate corresponding to the OS tick rate, calling `sys_clock_announce()` with an argument of one each time.

- The driver can ignore calls to `sys_clock_set_timeout()`, as every tick will be announced regardless of timeout status.

- The driver can return zero for every call to `sys_clock_elapsed()` as no more than one tick can be detected as having elapsed (because otherwise an interrupt would have been received).

**SMP Details**  In general, the timer API described above does not change when run in a multiprocessor context. The kernel will internally synchronize all access appropriately, and ensure that all critical sections are small and minimal. But some notes are important to detail:

- Zephyr is agnostic about which CPU services timer interrupts. It is not illegal (though probably undesirable in some circumstances) to have every timer interrupt handled on a single processor. Existing SMP architectures implement symmetric timer drivers.

- The `sys_clock_announce()` call is expected to be globally synchronized at the driver level. The kernel does not do any per-CPU tracking, and expects that if two timer interrupts fire near simultaneously, that only one will provide the current tick count to the timing subsystem. The other may legally provide a tick count of zero if no ticks have elapsed. It should not “skip” the announce call because of timeslicing requirements (see below).

- Some SMP hardware uses a single, global timer device, others use a per-CPU counter. The complexity here (for example: ensuring counter synchronization between CPUs) is expected to be managed by the driver, not the kernel.

- The next timeout value passed back to the driver via `sys_clock_set_timeout()` is done identically for every CPU. So by default, every CPU will see simultaneous timer interrupts for every event, even though by definition only one of them should see a non-zero ticks argument to `sys_clock_announce()`. This is probably a correct default for timing sensitive applications (because it minimizes the chance that an errant ISR or interrupt lock will delay a timeout), but may be a performance problem in some cases. The current design expects that any such optimization is the responsibility of the timer driver.

**Time Slicing**  An auxiliary job of the timing subsystem is to provide tick counters to the scheduler that allow implementation of time slicing of threads. A thread time-slice cannot be a time-
out value, as it does not reflect a global expiration but instead a per-CPU value that needs to be tracked independently on each CPU in an SMP context.

Because there may be no other hardware available to drive timeslicing, Zephyr multiplexes the existing timer driver. This means that the value passed to `sys_clock_set_timeout()` may be clamped to a smaller value than the current next timeout when a time sliced thread is currently scheduled.

**Subsystems that keep millisecond APIs** In general, code like this will port just like applications code will. Millisecond values from the user may be treated any way the subsystem likes, and then converted into kernel timeouts using `K_MSEC()` at the point where they are presented to the kernel.

Obviously this comes at the cost of not being able to use new features, like the higher precision timeout constructors or absolute timeouts. But for many subsystems with simple needs, this may be acceptable.

One complexity is `K_FOREVER`. Subsystems that might have been able to accept this value to their millisecond API in the past no longer can, because it is no longer an integral type. Such code will need to use a different, integer-valued token to represent “forever”. `K_NO_WAIT` has the same typesafety concern too, of course, but as it is (and has always been) simply a numerical zero, it has a natural porting path.

**Subsystems using k_timeout_t** Ideally, code that takes a “timeout” parameter specifying a time to wait should be using the kernel native abstraction where possible. But `k_timeout_t` is opaque, and needs to be converted before it can be inspected by an application.

Some conversions are simple. Code that needs to test for `K_FOREVER` can simply use the `K_TIMEOUT_EQ()` macro to test the opaque struct for equality and take special action.

The more complicated case is when the subsystem needs to take a timeout and loop, waiting for it to finish while doing some processing that may require multiple blocking operations on underlying kernel code. For example, consider this design:

```c
void my_wait_for_event(struct my_subsys *obj, int32_t timeout_in_ms) {
    while (true) {
        uint32_t start = k_uptime_get_32();
        if (is_event_complete(obj)) {
            return;
        }
        /* Wait for notification of state change */
        k_sem_take(obj->sem, timeout_in_ms);
        /* Subtract elapsed time */
        timeout_in_ms -= (k_uptime_get_32() - start);
    }
}
```

This code requires that the timeout value be inspected, which is no longer possible. For situations like this, the new API provides the internal `sys_timepoint_calc()` and `sys_timepoint_timeout()` routines that converts an arbitrary timeout to and from a timepoint value based on an uptime tick at which it will expire. So such a loop might look like:

```c
void my_wait_for_event(struct my_subsys *obj, k_timeout_t timeout) {
    /* Compute the end time from the timeout */
    k_timepoint_t end = sys_timepoint_calc(timeout);
}
```

(continues on next page)
do {
    if (is_event_complete(obj)) {
        return;
    }

    /* Update timeout with remaining time */
    timeout = sys_timepoint_timeout(end);

    /* Wait for notification of state change */
    k_sem_take(obj->sem, timeout);
} while (!K_TIMEOUT_EQ(timeout, K_NO_WAIT));

Note that `sys_timepoint_calc()` accepts special values `K_FOREVER` and `K_NO_WAIT`, and works identically for absolute timeouts as well as conventional ones. Conversely, `sys_timepoint_timeout()` may return `K_FOREVER` or `K_NO_WAIT` if those were used to create the timepoint, the later also being returned if the timepoint is now in the past. For simple cases, `sys_timepoint_expired()` can be used as well.

But some care is still required for subsystems that use those. Note that delta timeouts need to be interpreted relative to a “current time”, and obviously that time is the time of the call to `sys_timepoint_calc()`. But the user expects that the time is the time they passed the timeout to you. Care must be taken to call this function just once, as synchronously as possible to the timeout creation in user code. It should not be used on a “stored” timeout value, and should never be called iteratively in a loop.

**API Reference**

**group clock_apis**

System Clock APIs.

**Defines**

```c
#define K_NO_WAIT
```

Generate null timeout delay.

This macro generates a timeout delay that instructs a kernel API not to wait if the requested operation cannot be performed immediately.

**Returns**

Timeout delay value.

```c
#define K_NSEC(t)
```

Generate timeout delay from nanoseconds.

This macro generates a timeout delay that instructs a kernel API to wait up to \( t \) nanoseconds to perform the requested operation. Note that timer precision is limited to the tick rate, not the requested value.

**Parameters**

- \( t \) – Duration in nanoseconds.

**Returns**

Timeout delay value.
K_USEC(t)
Generate timeout delay from microseconds.
This macro generates a timeout delay that instructs a kernel API to wait up to $t$ microseconds to perform the requested operation. Note that timer precision is limited to the tick rate, not the requested value.

**Parameters**
- $t$ – Duration in microseconds.

**Returns**
Timeout delay value.

K_CYC(t)
Generate timeout delay from cycles.
This macro generates a timeout delay that instructs a kernel API to wait up to $t$ cycles to perform the requested operation.

**Parameters**
- $t$ – Duration in cycles.

**Returns**
Timeout delay value.

K_TICKS(t)
Generate timeout delay from system ticks.
This macro generates a timeout delay that instructs a kernel API to wait up to $t$ ticks to perform the requested operation.

**Parameters**
- $t$ – Duration in system ticks.

**Returns**
Timeout delay value.

K_MSEC(ms)
Generate timeout delay from milliseconds.
This macro generates a timeout delay that instructs a kernel API to wait up to $ms$ milliseconds to perform the requested operation.

**Parameters**
- $ms$ – Duration in milliseconds.

**Returns**
Timeout delay value.

K_SECONDS(s)
Generate timeout delay from seconds.
This macro generates a timeout delay that instructs a kernel API to wait up to $s$ seconds to perform the requested operation.

**Parameters**
- $s$ – Duration in seconds.

**Returns**
Timeout delay value.
K_MINUTES\((m)\)
Generate timeout delay from minutes.
This macro generates a timeout delay that instructs a kernel API to wait up to \(m\) minutes to perform the requested operation.

**Parameters**
- \(m\) – Duration in minutes.

**Returns**
Timeout delay value.

K_HOURS\((h)\)
Generate timeout delay from hours.
This macro generates a timeout delay that instructs a kernel API to wait up to \(h\) hours to perform the requested operation.

**Parameters**
- \(h\) – Duration in hours.

**Returns**
Timeout delay value.

K_FOREVER
Generate infinite timeout delay.
This macro generates a timeout delay that instructs a kernel API to wait as long as necessary to perform the requested operation.

**Returns**
Timeout delay value.

K_TICKS_FOREVER
K_TIMEOUT_EQ\((a, b)\)
Compare timeouts for equality.
The \(k\_timeout\_t\) object is an opaque struct that should not be inspected by application code. This macro exists so that users can test timeout objects for equality with known constants (e.g. K_NO_WAIT and K_FOREVER) when implementing their own APIs in terms of Zephyr timeout constants.

**Returns**
True if the timeout objects are identical

NSEC_PER_USEC
number of nanoseconds per micorsecond

NSEC_PER_MSEC
number of nanoseconds per millisecond

USEC_PER_MSEC
number of microseconds per millisecond

MSEC_PER_SEC
number of milliseconds per second
SEC_PER_MIN
number of seconds per minute

MIN_PER_HOUR
number of minutes per hour

HOUR_PER_DAY
number of hours per day

USEC_PER_SEC
number of microseconds per second

NSEC_PER_SEC
number of nanoseconds per second

SYS_CLOCK_HW_CYCLES_TO_NS_AVG(\text{\textit{X}}, \text{NCYCLES})
SYS_CLOCK_HW_CYCLES_TO_NS_AVG converts CPU clock cycles to nanoseconds and calculates the average cycle time.

**Typedefs**

typedef uint32_t k_ticks_t
Tick precision used in timeout APIs.
This type defines the word size of the timeout values used in \textit{k_timeout_t} objects, and thus defines an upper bound on maximum timeout length (or equivalently minimum tick duration). Note that this does not affect the size of the system uptime counter, which is always a 64 bit count of ticks.

**Functions**

void sys_clock_set_timeout(int32_t ticks, bool idle)
Set system clock timeout.
Informs the system clock driver that the next needed call to \textit{sys_clock_announce()} will not be until the specified number of ticks from the current time have elapsed. Note that spurious calls to \textit{sys_clock_announce()} are allowed (i.e. it’s legal to announce every tick and implement this function as a noop), the requirement is that one tick announcement should occur within one tick BEFORE the specified expiration (that is, passing ticks==1 means “announce the next tick”, this convention was chosen to match legacy usage). Similarly a ticks value of zero (or even negative) is legal and treated identically: it simply indicates the kernel would like the next tick announcement as soon as possible.
Note that ticks can also be passed the special value K_TICKS_FOREVER, indicating that no future timer interrupts are expected or required and that the system is permitted to enter an indefinite sleep even if this could cause rollover of the internal counter (i.e. the system uptime counter is allowed to be wrong.
Note also that it is conventional for the kernel to pass INT_MAX for ticks if it wants to preserve the uptime tick count but doesn’t have a specific event to await. The intent here is that the driver will schedule any needed timeout as far into the future as possible. For the specific case of INT_MAX, the next call to \textit{sys_clock_announce()} may occur
at any point in the future, not just at INT_MAX ticks. But the correspondence between
the announced ticks and real-world time must be correct.

A final note about SMP: note that the call to \texttt{sys\_clock\_set\_timeout()} is made on
any CPU, and reflects the next timeout desired globally. The resulting calls(s) to
\texttt{sys\_clock\_announce()} must be properly serialized by the driver such that a given tick
is announced exactly once across the system. The kernel does not (cannot, really) at-
ttempt to serialize things by “assigning” timeouts to specific CPUs.

\textbf{Parameters}

- \texttt{ticks} – Timeout in tick units
- \texttt{idle} – Hint to the driver that the system is about to enter the idle state
  immediately after setting the timeout

\begin{verbatim}
void sys_clock_idle_exit(void)
    Timer idle exit notification.
    This notifies the timer driver that the system is exiting the idle and allows it to do
    whatever bookkeeping is needed to restore timer operation and compute elapsed ticks.
\end{verbatim}

\begin{verbatim}
void sys_clock_announce(int32_t ticks)
    Announce time progress to the kernel.
    Informs the kernel that the specified number of ticks have elapsed since the last call to
    \texttt{sys\_clock\_announce()} (or system startup for the first call). The timer driver is expected
to delivery these announcements as close as practical (subject to hardware and latency
limitations) to tick boundaries.
\end{verbatim}

\begin{verbatim}
Parameters
- \texttt{ticks} – Elapsed time, in ticks
\end{verbatim}

uint32_t sys_clock_elapsed(void)
    Ticks elapsed since last \texttt{sys\_clock\_announce()} call.
    Queries the clock driver for the current time elapsed since the last call to
    \texttt{sys\_clock\_announce()} was made. The kernel will call this with appropriate locking,
    the driver needs only provide an instantaneous answer.

void sys_clock_disable(void)
    Disable system timer.

\begin{verbatim}
Note: Not all system timer drivers has the capability of being disabled. The config
enna CONFIG\_SYSTEM\_TIMER\_HAS\_DISABLE\_SUPPORT can be used to check if the system timer
has the capability of being disabled.
\end{verbatim}

uint32_t sys_clock_cycle_get_32(void)
    Hardware cycle counter.
    Timer drivers are generally responsible for the system cycle counter as well as the tick
    announcements. This function is generally called out of the architecture layer (See also:
    \texttt{arch\_k\_cycle\_get\_32()}) to implement the cycle counter, though the user-facing API
    is owned by the architecture, not the driver. The rate must match CONFIG\_SYS\_CLOCK\_HW\_CYCLES\_PER\_SEC.
Note: If the counter clock is large enough for this to wrap its full range within a few seconds (i.e. CONFIG_SYS_CLOCK_HW_CYCLES_PER_SEC is greater than 50Mhz) then it is recommended to also implement \texttt{sys\_clock\_cycle\_get\_64()}.

Returns
The current cycle time. This should count up monotonically through the full 32 bit space, wrapping at 0xffffffff. Hardware with fewer bits of precision in the timer is expected to synthesize a 32 bit count.

\textbf{uint64-t} \texttt{sys\_clock\_cycle\_get\_64}(\texttt{void})

64 bit hardware cycle counter

As for \texttt{sys\_clock\_cycle\_get\_32()}, but with a 64 bit return value. Not all hardware has 64 bit counters. This function need be implemented only if \texttt{CONFIG\_TIMER\_HAS\_64BIT\_CYCLE\_COUNTER} is set.

Note: If the counter clock is large enough for \texttt{sys\_clock\_cycle\_get\_32()} to wrap its full range within a few seconds (i.e. CONFIG_SYS_CLOCK_HW_CYCLES_PER_SEC is greater than 50Mhz) then it is recommended to implement this API.

Returns
The current cycle time. This should count up monotonically through the full 64 bit space, wrapping at \(2^{64}-1\). Hardware with fewer bits of precision in the timer is generally not expected to implement this API.

\textbf{int64-t} \texttt{k\_uptime\_ticks}(\texttt{void})

Get system uptime, in system ticks.

This routine returns the elapsed time since the system booted, in ticks (c.f. \texttt{CONFIG\_SYS\_CLOCK\_TICKS\_PER\_SEC}), which is the fundamental unit of resolution of kernel timekeeping.

Returns
Current uptime in ticks.

\textbf{static inline} \textbf{int64-t} \texttt{k\_uptime\_get}(\texttt{void})

Get system uptime.

This routine returns the elapsed time since the system booted, in milliseconds.

Note: While this function returns time in milliseconds, it does not mean it has millisecond resolution. The actual resolution depends on \texttt{CONFIG\_SYS\_CLOCK\_TICKS\_PER\_SEC} config option.

Returns
Current uptime in milliseconds.

\textbf{static inline} \textbf{uint32-t} \texttt{k\_uptime\_get\_32}(\texttt{void})

Get system uptime (32-bit version).

This routine returns the lower 32 bits of the system uptime in milliseconds.

Because correct conversion requires full precision of the system clock there is no benefit to using this over \texttt{k\_uptime\_get()} unless you know the application will never run long enough for the system clock to approach \(2^{32}\) ticks. Calls to this function may involve interrupt blocking and 64-bit math.
Note: While this function returns time in milliseconds, it does not mean it has millisecond resolution. The actual resolution depends on CONFIG_SYS_CLOCK_TICKS_PER_SEC config option.

Returns
The low 32 bits of the current uptime, in milliseconds.

static inline int64_t k_uptime_delta(int64_t *reftime)
Get elapsed time.
This routine computes the elapsed time between the current system uptime and an earlier reference time, in milliseconds.

Parameters
- reftime – Pointer to a reference time, which is updated to the current uptime upon return.

Returns
Elapsed time.

static inline uint32_t k_cycle_get_32(void)
Read the hardware clock.
This routine returns the current time, as measured by the system's hardware clock.

Returns
Current hardware clock up-counter (in cycles).

static inline uint64_t k_cycle_get_64(void)
Read the 64-bit hardware clock.
This routine returns the current time in 64-bits, as measured by the system's hardware clock, if available.

See also:
CONFIG_TIMER_HAS_64BIT_CYCLE_COUNTER

Returns
Current hardware clock up-counter (in cycles).

uint32_t sys_clock_tick_get_32(void)
Return the lower part of the current system tick count.

Returns
the current system tick count

int64_t sys_clock_tick_get(void)
Return the current system tick count.

Returns
the current system tick count

\[ k_{timeout_t} \] sys_timepoint_calc(k_timeout_t timeout)
Calculate a timepoint value.
Returns a timepoint corresponding to the expiration (relative to an unlocked “now”!) of a timeout object. When used correctly, this should be called once, synchronously with the user passing a new timeout value. It should not be used iteratively to adjust a timeout (see \[ sys_timepoint_timeout() \] for that purpose).
See also:
sys_timepoint_timeout()

See also:
sys_timepoint_expired()

Parameters

- timeout – Timeout value relative to current time (may also be K_FOREVER or K_NO_WAIT).

Return values

- Timepoint – value corresponding to given timeout

_k_timeout_t sys_timepoint_timeout(_k_timepoint_t timepoint)

Remaining time to given timepoint.

Returns the timeout interval between current time and provided timepoint. If the time-
point is now in the past or if it was created with K_NO_WAIT then K_NO_WAIT is returned. If it was created with K_FOREVER then K_FOREVER is returned.

See also:
sys_timepoint_calc()

Parameters

- timepoint – Timepoint for which a timeout value is wanted.

Return values

- Corresponding – timeout value.

static inline uint64_t sys_clock_timeout_end_calc(_k_timeout_t timeout)

Provided for backward compatibility.

This is deprecated. Consider sys_timepoint_calc() instead.

See also:
sys_timepoint_calc()

static inline int sys_timepoint_cmp(_k_timepoint_t a, _k_timepoint_t b)

Compare two timepoint values.

This function is used to compare two timepoint values.

Parameters

- a – Timepoint to compare
- b – Timepoint to compare against.

Returns

- zero if both timepoints are the same. Negative value if timepoint a is before timepoint b, positive otherwise.
static inline bool sys_timepoint_expired(k_timepoint_t timepoint)
    Indicates if timepoint is expired.

See also:
sys_timepoint_calc()  

Parameters
• timepoint – Timepoint to evaluate

Return values
true – if the timepoint is in the past, false otherwise

struct k_timeout_t
#include <sys_clock.h> Kernel timeout type.
Timeout arguments presented to kernel APIs are stored in this opaque type, which is capable of representing times in various formats and units. It should be constructed from application data using one of the macros defined for this purpose (e.g. K_MSEC(), K_TIMEOUT_ABS_TICKS(), etc...), or be one of the two constants K_NO_WAIT or K_FOREVER. Applications should not inspect the internal data once constructed. Timeout values may be compared for equality with the K_TIMEOUT_EQ() macro.

struct k_timepoint_t
#include <sys_clock.h> Kernel timepoint type.
Absolute timepoints are stored in this opaque type. It is best not to inspect its content directly.

See also:
sys_timepoint_calc()  
See also:
sys_timepoint_timeout()  
See also:
sys_timepoint_expired()  

Timers

A timer is a kernel object that measures the passage of time using the kernel's system clock. When a timer's specified time limit is reached it can perform an application-defined action, or it can simply record the expiration and wait for the application to read its status.

• Concepts
• Implementation
  – Defining a Timer
  – Using a Timer Expiry Function
  – Reading Timer Status
  – Using Timer Status Synchronization
Any number of timers can be defined (limited only by available RAM). Each timer is referenced by its memory address.

A timer has the following key properties:

- A **duration** specifying the time interval before the timer expires for the first time. This is a \texttt{k_timeout_t} value that may be initialized via different units.

- A **period** specifying the time interval between all timer expirations after the first one, also a \texttt{k_timeout_t}. It must be non-negative. A period of \texttt{K_NO_WAIT} (i.e. zero) or \texttt{K_FOREVER} means that the timer is a one-shot timer that stops after a single expiration. (For example then, if a timer is started with a duration of 200 and a period of 75, it will first expire after 200 ms and then every 75 ms after that.)

- An **expiry function** that is executed each time the timer expires. The function is executed by the system clock interrupt handler. If no expiry function is required a \texttt{NULL} function can be specified.

- A **stop function** that is executed if the timer is stopped prematurely while running. The function is executed by the thread that stops the timer. If no stop function is required a \texttt{NULL} function can be specified.

- A **status** value that indicates how many times the timer has expired since the status value was last read.

A timer must be initialized before it can be used. This specifies its expiry function and stop function values, sets the timer's status to zero, and puts the timer into the **stopped** state.

A timer is **started** by specifying a duration and a period. The timer's status is reset to zero, and then the timer enters the **running** state and begins counting down towards expiry.

Note that the timer’s duration and period parameters specify **minimum** delays that will elapse. Because of internal system timer precision (and potentially runtime interactions like interrupt delay) it is possible that more time may have passed as measured by reads from the relevant system time APIs. But at least this much time is guaranteed to have elapsed.

When a running timer expires its status is incremented and the timer executes its expiry function, if one exists; If a thread is waiting on the timer, it is unblocked. If the timer’s period is zero the timer enters the stopped state; otherwise, the timer restarts with a new duration equal to its period.

A running timer can be stopped in mid-countdown, if desired. The timer’s status is left unchanged, then the timer enters the stopped state and executes its stop function, if one exists. If a thread is waiting on the timer, it is unblocked. Attempting to stop a non-running timer is permitted, but has no effect on the timer since it is already stopped.

A running timer can be restarted in mid-countdown, if desired. The timer’s status is reset to zero, then the timer begins counting down using the new duration and period values specified by the caller. If a thread is waiting on the timer, it continues waiting.

A timer’s status can be read directly at any time to determine how many times the timer has expired since its status was last read. Reading a timer’s status resets its value to zero. The amount of time remaining before the timer expires can also be read; a value of zero indicates that the timer is stopped.

A thread may read a timer's status indirectly by **synchronizing** with the timer. This blocks the thread until the timer's status is non-zero (indicating that it has expired at least once) or the timer is stopped; if the timer status is already non-zero or the timer is already stopped the thread...
continues without waiting. The synchronization operation returns the timer's status and resets it to zero.

**Note:** Only a single user should examine the status of any given timer, since reading the status (directly or indirectly) changes its value. Similarly, only a single thread at a time should synchronize with a given timer. ISRs are not permitted to synchronize with timers, since ISRs are not allowed to block.

### Implementation

#### Defining a Timer

A timer is defined using a variable of type `k_timer`. It must then be initialized by calling `k_timer_init()`.

The following code defines and initializes a timer.

```c
struct k_timer my_timer;
extern void my_expiry_function(struct k_timer *timer_id);
k_timer_init(&my_timer, my_expiry_function, NULL);
```

Alternatively, a timer can be defined and initialized at compile time by calling `K_TIMER_DEFINE`. The following code has the same effect as the code segment above.

```c
K_TIMER_DEFINE(my_timer, my_expiry_function, NULL);
```

#### Using a Timer Expiry Function

The following code uses a timer to perform a non-trivial action on a periodic basis. Since the required work cannot be done at the interrupt level, the timer's expiry function submits a work item to the `system workqueue`, whose thread performs the work.

```c
void my_work_handler(struct k_work *work)
{
    /* do the processing that needs to be done periodically */
    ...
}
K_WORK_DEFINE(my_work, my_work_handler);

void my_timer_handler(struct k_timer *dummy)
{
    k_work_submit(&my_work);
}
K_TIMER_DEFINE(my_timer, my_timer_handler, NULL);
...

/* start a periodic timer that expires once every second */
k_timer_start(&my_timer, K_SECONDS(1), K_SECONDS(1));
```

#### Reading Timer Status

The following code reads a timer's status directly to determine if the timer has expired or not.
K_TIMER_DEFINE(my_status_timer, NULL, NULL);

...  

/* start a one-shot timer that expires after 200 ms */
k_timer_start(&my_status_timer, K_MSEC(200), K_NO_WAIT);
/* do work */
...

/* check timer status */
if (k_timer_status_get(&my_status_timer) > 0) {
    /* timer has expired */
} else if (k_timer_remaining_get(&my_status_timer) == 0) {
    /* timer was stopped (by someone else) before expiring */
} else {
    /* timer is still running */
}

Using Timer Status Synchronization  The following code performs timer status synchronization to allow a thread to do useful work while ensuring that a pair of protocol operations are separated by the specified time interval.

K_TIMER_DEFINE(my_sync_timer, NULL, NULL);

...  

/* do first protocol operation */
...

/* start a one-shot timer that expires after 500 ms */
k_timer_start(&my Sync Timer, K_MSEC(500), K_NO_WAIT);

/* do other work */
...

/* ensure timer has expired (waiting for expiry, if necessary) */
k_timer_status_sync(&my_sync_timer);
/* do second protocol operation */
...

Note: If the thread had no other work to do it could simply sleep between the two protocol operations, without using a timer.

Suggested Uses  Use a timer to initiate an asynchronous operation after a specified amount of time.

Use a timer to determine whether or not a specified amount of time has elapsed. In particular, timers should be used when higher precision and/or unit control is required than that afforded by the simpler k_sleep() and k_usleep() calls.

Use a timer to perform other work while carrying out operations involving time limits.

Note: If a thread needs to measure the time required to perform an operation it can read the system clock or the hardware clock directly, rather than using a timer.

3.1. Kernel Services
**Configuration Options**  
Related configuration options:  
- None

**API Reference**

**Related code samples**

**KSCAN**  
Use the KSCAN API to read key presses and releases on a keyboard matrix.

```plaintext
**group timer_apis**

**Defines**

*K_TIMER_DEFINE*(name, expiry_fn, stop_fn)  
Statically define and initialize a timer.  
The timer can be accessed outside the module where it is defined using:

```c
extern struct k_timer <name>;
```

**Parameters**

- `name` – Name of the timer variable.  
- `expiry_fn` – Function to invoke each time the timer expires.  
- `stop_fn` – Function to invoke if the timer is stopped while running.

**Typedefs**

typedef void (*_k_timer_expiry_t)(struct k_timer *timer)  
Timer expiry function type.  
A timer's expiry function is executed by the system clock interrupt handler each time  
the timer expires. The expiry function is optional, and is only invoked if the timer has  
been initialized with one.

**Param timer**  
Address of timer.

typedef void (*_k_timer_stop_t)(struct k_timer *timer)  
Timer stop function type.  
A timer's stop function is executed if the timer is stopped prematurely. The function  
runs in the context of call that stops the timer. As `_k_timer_stop()` can be invoked from  
an ISR, the stop function must be callable from interrupt context (isr-ok).  
The stop function is optional, and is only invoked if the timer has been initialized with  
one.

**Param timer**  
Address of timer.
Functions

```c
void k_timer_init(struct k_timer *timer, k_timer_expiry_t expiry_fn, k_timer_stop_t stop_fn)
```

Initialize a timer.

This routine initializes a timer, prior to its first use.

**Parameters**

- `timer` – Address of timer.
- `expiry_fn` – Function to invoke each time the timer expires.
- `stop_fn` – Function to invoke if the timer is stopped while running.

```c
void k_timer_start(struct k_timer *timer, k_timeout_t duration, k_timeout_t period)
```

Start a timer.

This routine starts a timer, and resets its status to zero. The timer begins counting down using the specified duration and period values.

Attempting to start a timer that is already running is permitted. The timer’s status is reset to zero and the timer begins counting down using the new duration and period values.

**Parameters**

- `timer` – Address of timer.
- `duration` – Initial timer duration.
- `period` – Timer period.

```c
void k_timer_stop(struct k_timer *timer)
```

Stop a timer.

This routine stops a running timer prematurely. The timer’s stop function, if one exists, is invoked by the caller.

Attempting to stop a timer that is not running is permitted, but has no effect on the timer.

**Function properties (list may not be complete)**

`isr-ok`

**Note:** The stop handler has to be callable from ISRs if `k_timer_stop` is to be called from ISRs.

```c
uint32_t k_timer_status_get(struct k_timer *timer)
```

Read timer status.

This routine reads the timer’s status, which indicates the number of times it has expired since its status was last read.

Calling this routine resets the timer’s status to zero.

**Parameters**

- `timer` – Address of timer.
Returns
Timer status.

uint32_t k_timer_status_sync(struct k_timer *timer)
Synchronize thread to timer expiration.
This routine blocks the calling thread until the timer's status is non-zero (indicating that it has expired at least once since it was last examined) or the timer is stopped. If the timer status is already non-zero, or the timer is already stopped, the caller continues without waiting.
Calling this routine resets the timer's status to zero.
This routine must not be used by interrupt handlers, since they are not allowed to block.

Parameters
- timer – Address of timer.

Returns
Timer status.

k_ticks_t k_timer_expires_ticks(const struct k_timer *timer)
Get next expiration time of a timer, in system ticks.
This routine returns the future system uptime reached at the next time of expiration of the timer, in units of system ticks. If the timer is not running, current system time is returned.

Parameters
- timer – The timer object

Returns
Uptime of expiration, in ticks

k_ticks_t k_timer_remaining_ticks(const struct k_timer *timer)
Get time remaining before a timer next expires, in system ticks.
This routine computes the time remaining before a running timer next expires, in units of system ticks. If the timer is not running, it returns zero.

static inline uint32_t k_timer_remaining_get(struct k_timer *timer)
Get time remaining before a timer next expires.
This routine computes the (approximate) time remaining before a running timer next expires. If the timer is not running, it returns zero.

Parameters
- timer – Address of timer.

Returns
Remaining time (in milliseconds).

void k_timer_user_data_set(struct k_timer *timer, void *user_data)
Associate user-specific data with a timer.
This routine records the user_data with the timer, to be retrieved later.
It can be used e.g. in a timer handler shared across multiple subsystems to retrieve data specific to the subsystem this timer is associated with.

Parameters
- timer – Address of timer.
- user_data – User data to associate with the timer.
void *k_timer_user_data_get(const struct k_timer *timer)

Retrieve the user-specific data from a timer.

**Parameters**

- **timer** – Address of timer.

**Returns**

The user data.

### 3.1.5 Other

These pages cover other kernel services.

#### Atomic Services

An atomic variable is one that can be read and modified by threads and ISRs in an uninterruptible manner. It is a 32-bit variable on 32-bit machines and a 64-bit variable on 64-bit machines.

- **Concepts**
- **Implementation**
  - Defining an Atomic Variable
  - Manipulating an Atomic Variable
  - Manipulating an Array of Atomic Variables
  - Memory Ordering
- **Suggested Uses**
- **Configuration Options**
- **API Reference**

**Concepts** Any number of atomic variables can be defined (limited only by available RAM). Using the kernel's atomic APIs to manipulate an atomic variable guarantees that the desired operation occurs correctly, even if higher priority contexts also manipulate the same variable. The kernel also supports the atomic manipulation of a single bit in an array of atomic variables.

**Implementation**

**Defining an Atomic Variable** An atomic variable is defined using a variable of type `atomic_t`.

By default an atomic variable is initialized to zero. However, it can be given a different value using `ATOMIC_INIT`:

```c
atomic_t flags = ATOMIC_INIT(0xFF);
```
Manipulating an Atomic Variable   An atomic variable is manipulated using the APIs listed at the end of this section.

The following code shows how an atomic variable can be used to keep track of the number of times a function has been invoked. Since the count is incremented atomically, there is no risk that it will become corrupted in mid-increment if a thread calling the function is interrupted if by a higher priority context that also calls the routine.

```
atomic_t call_count;

int call_counting_routine(void)
{
    /* increment invocation counter */
    atomic_inc(&call_count);

    /* do rest of routine's processing */
    ...  
}
```

Manipulating an Array of Atomic Variables   An array of 32-bit atomic variables can be defined in the conventional manner. However, you can also define an N-bit array of atomic variables using `ATOMIC_DEFINE`.

A single bit in array of atomic variables can be manipulated using the APIs listed at the end of this section that end with `_bit()`.

The following code shows how a set of 200 flag bits can be implemented using an array of atomic variables.

```
#define NUM_FLAG_BITS 200

ATOMIC_DEFINE(flag_bits, NUM_FLAG_BITS);

/* set specified flag bit & return its previous value */
int set_flag_bit(int bit_position)
{
    return (int)atomic_set_bit(flag_bits, bit_position);
}
```

Memory Ordering   For consistency and correctness, all Zephyr atomic APIs are expected to include a full memory barrier (in the sense of e.g. “serializing” instructions on x86, “DMB” on ARM, or a “sequentially consistent” operation as defined by the C++ memory model) where needed by hardware to guarantee a reliable picture across contexts. Any architecture-specific implementations are responsible for ensuring this behavior.

Suggested Uses   Use an atomic variable to implement critical section processing that only requires the manipulation of a single 32-bit value.

Use multiple atomic variables to implement critical section processing on a set of flag bits in a bit array longer than 32 bits.

Note:   Using atomic variables is typically far more efficient than using other techniques to implement critical sections such as using a mutex or locking interrupts.

Configuration Options   Related configuration options:

- CONFIG_ATOMIC_OPERATIONS_BUILTIN
API Reference

Important: All atomic services APIs can be used by both threads and ISRs.


group atomic_apis

Defines

ATOMIC_INIT(i)
Initialize an atomic variable.
This macro can be used to initialize an atomic variable. For example,

```
atomic_t my_var = ATOMIC_INIT(75);
```

Parameters

- i – Value to assign to atomic variable.

ATOMIC_PTR_INIT(p)
Initialize an atomic pointer variable.
This macro can be used to initialize an atomic pointer variable. For example,

```
atomic_ptr_t my_ptr = ATOMIC_PTR_INIT(&data);
```

Parameters

- p – Pointer value to assign to atomic pointer variable.

ATOMIC_BITMAP_SIZE(num_bits)
This macro computes the number of atomic variables necessary to represent a bitmap with num_bits.

Parameters

- num_bits – Number of bits.

ATOMIC_DEFINE(name, num_bits)
Define an array of atomic variables.
This macro defines an array of atomic variables containing at least num_bits bits.

Note: If used from file scope, the bits of the array are initialized to zero; if used from within a function, the bits are left uninitialized.

Parameters

- name – Name of array of atomic variables.
- num_bits – Number of bits needed.
Functions

static inline bool atomic_test_bit(const atomic_t *target, int bit)

Atomically test a bit.

This routine tests whether bit number `bit` of `target` is set or not. The target may be a single atomic variable or an array of them.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
- `target` – Address of atomic variable or array.
- `bit` – Bit number (starting from 0).

**Returns**
true if the bit was set, false if it wasn’t.

static inline bool atomic_test_and_clear_bit(atomic_t *target, int bit)

Atomically test and clear a bit.

Atomically clear bit number `bit` of `target` and return its old value. The target may be a single atomic variable or an array of them.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
- `target` – Address of atomic variable or array.
- `bit` – Bit number (starting from 0).

**Returns**
false if the bit was already cleared, true if it wasn’t.

static inline bool atomic_test_and_set_bit(atomic_t *target, int bit)

Atomically set a bit.

Atomically set bit number `bit` of `target` and return its old value. The target may be a single atomic variable or an array of them.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
- `target` – Address of atomic variable or array.
- `bit` – Bit number (starting from 0).

**Returns**
true if the bit was already set, false if it wasn’t.
static inline void atomic_clear_bit(atomic_t *target, int bit)
    Atomically clear a bit.
    Atomically clear bit number \textit{bit} of \textit{target}. The target may be a single atomic variable or an array of them.

\textbf{Note:} As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

\textbf{Parameters}
\begin{itemize}
    \item \texttt{target} – Address of atomic variable or array.
    \item \texttt{bit} – Bit number (starting from 0).
\end{itemize}

static inline void atomic_set_bit(atomic_t *target, int bit)
    Atomically set a bit.
    Atomically set bit number \textit{bit} of \textit{target}. The target may be a single atomic variable or an array of them.

\textbf{Note:} As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

\textbf{Parameters}
\begin{itemize}
    \item \texttt{target} – Address of atomic variable or array.
    \item \texttt{bit} – Bit number (starting from 0).
\end{itemize}

static inline void atomic_set_bit_to(atomic_t *target, int bit, bool val)
    Atomically set a bit to a given value.
    Atomically set bit number \textit{bit} of \textit{target} to value \texttt{val}. The target may be a single atomic variable or an array of them.

\textbf{Note:} As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

\textbf{Parameters}
\begin{itemize}
    \item \texttt{target} – Address of atomic variable or array.
    \item \texttt{bit} – Bit number (starting from 0).
    \item \texttt{val} – true for 1, false for 0.
\end{itemize}

bool atomic_cas(atomic_t *target, atomic_val_t old_value, atomic_val_t new_value)
    Atomic compare-and-set.
    This routine performs an atomic compare-and-set on \texttt{target}. If the current value of \texttt{target} equals \texttt{old_value}, \texttt{target} is set to \texttt{new_value}. If the current value of \texttt{target} does not equal \texttt{old_value}, \texttt{target} is left unchanged.

\textbf{Note:} As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).
Parameters

- **target** – Address of atomic variable.
- **old_value** – Original value to compare against.
- **new_value** – New value to store.

Returns

true if **new_value** is written, false otherwise.

```c
bool atomic_ptr_cas(atomic_ptr_t *target, atomic_ptr_val_t old_value, atomic_ptr_val_t new_value)
```

Atomic compare-and-set with pointer values.

This routine performs an atomic compare-and-set on **target**. If the current value of **target** equals **old_value**, **target** is set to **new_value**. If the current value of **target** does not equal **old_value**, **target** is left unchanged.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters

- **target** – Address of atomic variable.
- **old_value** – Original value to compare against.
- **new_value** – New value to store.

Returns

true if **new_value** is written, false otherwise.

```c
atomic_val_t atomic_add(atomic_t *target, atomic_val_t value)
```

Atomic addition.

This routine performs an atomic addition on **target**.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters

- **target** – Address of atomic variable.
- **value** – Value to add.

Returns

Previous value of **target**.

```c
atomic_val_t atomic_sub(atomic_t *target, atomic_val_t value)
```

Atomic subtraction.

This routine performs an atomic subtraction on **target**.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).
• **target** – Address of atomic variable.
• **value** – Value to subtract.

**Returns**
Previous value of `target`.

```c
atomic_val_t atomic_inc(atomic_t *target)
```
Atomic increment.
This routine performs an atomic increment by 1 on `target`.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
• **target** – Address of atomic variable.

**atomic_val_t atomic_dec(atomic_t *target)**
Atomic decrement.
This routine performs an atomic decrement by 1 on `target`.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
• **target** – Address of atomic variable.

**atomic_val_t atomic_get(const atomic_t *target)**
Atomic get.
This routine performs an atomic read on `target`.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
• **target** – Address of atomic variable.

**atomic_ptr_val_t atomic_ptr_get(const atomic_ptr_t *target)**
Atomic get a pointer value.
This routine performs an atomic read on `target`.
Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**

- `target` – Address of pointer variable.

**Returns**

Value of `target`.

atomic_val_t atomic_set(atomic_t *target, atomic_val_t value)

Atomic get-and-set.

This routine atomically sets `target` to `value` and returns the previous value of `target`.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**

- `target` – Address of atomic variable.
- `value` – Value to write to `target`.

**Returns**

Previous value of `target`.

atomic_ptr_val_t atomic_ptr_set(atomic_ptr_t *target, atomic_ptr_val_t value)

Atomic get-and-set for pointer values.

This routine atomically sets `target` to `value` and returns the previous value of `target`.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**

- `target` – Address of atomic variable.
- `value` – Value to write to `target`.

**Returns**

Previous value of `target`.

atomic_val_t atomic_clear(atomic_t *target)

Atomic clear.

This routine atomically sets `target` to zero and returns its previous value. (Hence, it is equivalent to atomic_set(target, 0).)

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).
atomic_ptr_val_t atomic_ptr_clear(atomic_ptr_t *target)

Atomic clear of a pointer value.

This routine atomically sets target to zero and returns its previous value. (Hence, it is equivalent to atomic_set(target, 0).)

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
- target – Address of atomic variable.

**Returns**
Previous value of target.

atomic_val_t atomic_or(atomic_t *target, atomic_val_t value)

Atomic bitwise inclusive OR.

This routine atomically sets target to the bitwise inclusive OR of target and value.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
- target – Address of atomic variable.
- value – Value to OR.

**Returns**
Previous value of target.

atomic_val_t atomic_xor(atomic_t *target, atomic_val_t value)

Atomic bitwise exclusive OR (XOR).

This routine atomically sets target to the bitwise exclusive OR (XOR) of target and value.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).
atomic_val_t atomic_and(atomic_t *target, atomic_val_t value)
Atomic bitwise AND.
This routine atomically sets target to the bitwise AND of target and value.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• value – Value to AND.

Returns
Previous value of target.

atomic_val_t atomic_nand(atomic_t *target, atomic_val_t value)
Atomic bitwise NAND.
This routine atomically sets target to the bitwise NAND of target and value. (This operation is equivalent to target = ~(target & value).)

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• value – Value to NAND.

Returns
Previous value of target.

Floating Point Services

The kernel allows threads to use floating point registers on board configurations that support these registers.

Note: Floating point services are currently available only for boards based on ARM Cortex-M SoCs supporting the Floating Point Extension, the Intel x86 architecture, the SPARC architecture and ARCv2 SoCs supporting the Floating Point Extension. The services provided are architecture specific.

The kernel does not support the use of floating point registers by ISRs.

• Concepts
  – No FP registers mode
  – Unshared FP registers mode
  – Shared FP registers mode
• Implementation
  – Performing Floating Point Arithmetic
Concepts  The kernel can be configured to provide only the floating point services required by an application. Three modes of operation are supported, which are described below. In addition, the kernel's support for the SSE registers can be included or omitted, as desired.

**No FP registers mode**  This mode is used when the application has no threads that use floating point registers. It is the kernel's default floating point services mode.

If a thread uses any floating point register, the kernel generates a fatal error condition and aborts the thread.

**Unshared FP registers mode**  This mode is used when the application has only a single thread that uses floating point registers.

On x86 platforms, the kernel initializes the floating point registers so they can be used by any thread (initialization in skipped on ARM Cortex-M platforms and ARCv2 platforms). The floating point registers are left unchanged whenever a context switch occurs.

**Note:** The behavior is undefined, if two or more threads attempt to use the floating point registers, as the kernel does not attempt to detect (or prevent) multiple threads from using these registers.

**Shared FP registers mode**  This mode is used when the application has two or more threads that use floating point registers. Depending upon the underlying CPU architecture, the kernel supports one or more of the following thread sub-classes:

- non-user: A thread that cannot use any floating point registers
- FPU user: A thread that can use the standard floating point registers
- SSE user: A thread that can use both the standard floating point registers and SSE registers

The kernel initializes and enables access to the floating point registers, so they can be used by any thread, then saves and restores these registers during context switches to ensure the computations performed by each FPU user or SSE user are not impacted by the computations performed by the other users.

**ARM Cortex-M architecture (with the Floating Point Extension)**

**Note:** The Shared FP registers mode is the default Floating Point Services mode in ARM Cortex-M.

On the ARM Cortex-M architecture with the Floating Point Extension, the kernel treats all threads as FPU users when shared FP registers mode is enabled. This means that any thread is allowed to access the floating point registers. The ARM kernel automatically detects that a given thread is using the floating point registers the first time the thread accesses them.

Pretag a thread that intends to use the FP registers by using one of the techniques listed below.
• A statically-created ARM thread can be pretagged by passing the `K_FP_REGS` option to `K_THREAD_DEFINE`.

• A dynamically-created ARM thread can be pretagged by passing the `K_FP_REGS` option to `k_thread_create()`.

Pretagging a thread with the `K_FP_REGS` option instructs the MPU-based stack protection mechanism to properly configure the size of the thread's guard region to always guarantee stack overflow detection, and enable lazy stacking for the given thread upon thread creation.

During thread context switching the ARM kernel saves the callee-saved floating point registers, if the switched-out thread has been using them. Additionally, the caller-saved floating point registers are saved on the thread's stack. If the switched-in thread has been using the floating point registers, the kernel restores the callee-saved FP registers of the switched-in thread and the caller-saved FP context is restored from the thread's stack. Thus, the kernel does not save or restore the FP context of threads that are not using the FP registers.

Each thread that intends to use the floating point registers must provide an extra 72 bytes of stack space where the callee-saved FP context can be saved.

Lazy Stacking is currently enabled in Zephyr applications on ARM Cortex-M architecture, minimizing interrupt latency, when the floating point context is active.

When the MPU-based stack protection mechanism is not enabled, lazy stacking is always active in the Zephyr application. When the MPU-based stack protection is enabled, the following rules apply with respect to lazy stacking:

- Lazy stacking is activated by default on threads that are pretagged with `K_FP_REGS`.
- Lazy stacking is activated dynamically on threads that are not pretagged with `K_FP_REGS`, as soon as the kernel detects that they are using the floating point registers.

If an ARM thread does not require use of the floating point registers any more, it can call `k_float_disable()`. This instructs the kernel not to save or restore its FP context during thread context switching.

ARM64 architecture

Note: The Shared FP registers mode is the default Floating Point Services mode on ARM64. The compiler is free to optimize code using FP/SIMD registers, and library functions such as memcpy are known to make use of them.

On the ARM64 (Aarch64) architecture the kernel treats each thread as a FPU user on a case-by-case basis. A “lazy save” algorithm is used during context switching which updates the floating point registers only when it is absolutely necessary. For example, the registers are not saved when switching from an FPU user to a non-user thread, and then back to the original FPU user. FPU register usage by ISRs is supported although not recommended. When an ISR uses floating point or SIMD registers, then the access is trapped, the current FPU user context is saved in the thread object and the ISR is resumed with interrupts disabled so to prevent another IRQ from interrupting the ISR and potentially requesting FPU usage. Because ISR don’t have a persistent register context, there are no provision for saving an ISR's FPU context either, hence the IRQ disabling.

Each thread object becomes 512 bytes larger when Shared FP registers mode is enabled.

ARCv2 architecture  On the ARCv2 architecture, the kernel treats each thread as a non-user or FPU user and the thread must be tagged by one of the following techniques.

• A statically-created ARC thread can be tagged by passing the `K_FP_REGS` option to `K_THREAD_DEFINE`.
A dynamically-created ARC thread can be tagged by passing the \texttt{K_FP_REGS} to \texttt{k_thread_create()}. If an ARC thread does not require use of the floating point registers any more, it can call \texttt{k_float_disable()}. This instructs the kernel not to save or restore its FP context during thread context switching.

During thread context switching the ARC kernel saves the \textit{callee-saved} floating point registers, if the switched-out thread has been using them. Additionally, the \textit{caller-saved} floating point registers are saved on the thread's stack. If the switched-in thread has been using the floating point registers, the kernel restores the \textit{callee-saved} FP registers of the switched-in thread and the \textit{caller-saved} FP context is restored from the thread's stack. Thus, the kernel does not save or restore the FP context of threads that are not using the FP registers. An extra 16 bytes (single floating point hardware) or 32 bytes (double floating point hardware) of stack space is required to load and store floating point registers.

**RISC-V architecture** On the RISC-V architecture the kernel treats each thread as an FPU user on a case-by-case basis with the FPU access allocated on demand. A “lazy save” algorithm is used during context switching which updates the floating point registers only when it is absolutely necessary. For example, the FPU registers are not saved when switching from an FPU user to a non-user thread (or an FPU user that doesn't touch the FPU during its scheduling slot), and then back to the original FPU user.

FPU register usage by ISRs is supported although not recommended. When an ISR uses floating point or SIMD registers, then the access is trapped, the current FPU user context is saved in the thread object and the ISR is resumed with interrupts disabled so to prevent another IRQ from interrupting the ISR and potentially requesting FPU usage. Because ISRs don’t have a persistent register context, there are no provision for saving an ISR’s FPU context either, hence the IRQ disabling.

As an optimization, the FPU context is preemptively restored upon scheduling back an “active FPU user” thread that had its FPU context saved away due to FPU usage by another thread. Active FPU users are so designated when they make the FPU state “dirty” during their most recent scheduling slot before being scheduled out. So if a thread doesn’t modify the FPU state within its scheduling slot and another thread claims the FPU for itself afterwards then that first thread will be subjected to the on-demand regime and won’t have its FPU context restored until it attempts to access it again. But if that thread does modify the FPU before being scheduled out then it is likely to continue using it when scheduled back in and preemptively restoring its FPU context saves on the exception trap overhead that would occur otherwise.

Each thread object becomes 136 bytes (single-precision floating point hardware) or 264 bytes (double-precision floating point hardware) larger when Shared FP registers mode is enabled.

**SPARC architecture** On the SPARC architecture, the kernel treats each thread as a non-user or FPU user and the thread must be tagged by one of the following techniques:

- A statically-created thread can be tagged by passing the \texttt{K_FP_REGS} option to \texttt{K_THREAD_DEFINE}.
- A dynamically-created thread can be tagged by passing the \texttt{K_FP_REGS} to \texttt{k_thread_create()}.

During thread context switch at exit from interrupt handler, the SPARC kernel saves all floating point registers, if the FPU was enabled in the switched-out thread. Floating point registers are saved on the thread's stack. Floating point registers are restored when a thread context is restored if they were saved at the context save. Saving and restoring of the floating point registers is synchronous and thus not lazy. The FPU is always disabled when an ISR is called (independent of \texttt{CONFIG_FPU_SHARING}).

Floating point disabling with \texttt{k_float_disable()} is not implemented.
When `CONFIG_FPU_SHARING` is used, then 136 bytes of stack space is required for each FPU user thread to load and store floating point registers. No extra stack is required if `CONFIG_FPU_SHARING` is not used.

### x86 architecture

On the x86 architecture the kernel treats each thread as a non-user, FPU user or SSE user on a case-by-case basis. A “lazy save” algorithm is used during context switching which updates the floating point registers only when it is absolutely necessary. For example, the registers are not saved when switching from an FPU user to a non-user thread, and then back to the original FPU user. The following table indicates the amount of additional stack space a thread must provide so the registers can be saved properly.

<table>
<thead>
<tr>
<th>Thread type</th>
<th>FP register use</th>
<th>Extra stack space required</th>
</tr>
</thead>
<tbody>
<tr>
<td>cooperative</td>
<td>any</td>
<td>0 bytes</td>
</tr>
<tr>
<td>preemptive</td>
<td>none</td>
<td>0 bytes</td>
</tr>
<tr>
<td>preemptive</td>
<td>FPU</td>
<td>108 bytes</td>
</tr>
<tr>
<td>preemptive</td>
<td>SSE</td>
<td>464 bytes</td>
</tr>
</tbody>
</table>

The x86 kernel automatically detects that a given thread is using the floating point registers the first time the thread accesses them. The thread is tagged as an SSE user if the kernel has been configured to support the SSE registers, or as an FPU user if the SSE registers are not supported. If this would result in a thread that is an FPU user being tagged as an SSE user, or if the application wants to avoid the exception handling overhead involved in auto-tagging threads, it is possible to pretag a thread using one of the techniques listed below.

- A statically-created x86 thread can be pretagged by passing the `K_FP_REGS` or `K_SSE_REGS` option to `K_THREAD_DEFINE`.
- A dynamically-created x86 thread can be pretagged by passing the `K_FP_REGS` or `K_SSE_REGS` option to `k_thread_create()`.
- An already-created x86 thread can pretag itself once it has started by passing the `K_FP_REGS` or `K_SSE_REGS` option to `k_float_enable()`.

If an x86 thread uses the floating point registers infrequently it can call `k_float_disable()` to remove its tagging as an FPU user or SSE user. This eliminates the need for the kernel to take steps to preserve the contents of the floating point registers during context switches when there is no need to do so. When the thread again needs to use the floating point registers it can re-tag itself as an FPU user or SSE user by calling `k_float_enable()`.

### Implementation

#### Performing Floating Point Arithmetic

No special coding is required for a thread to use floating point arithmetic if the kernel is properly configured.

The following code shows how a routine can use floating point arithmetic to avoid overflow issues when computing the average of a series of integer values.

```c
int average(int *values, int num_values) {
    double sum;
    int i;
    sum = 0.0;
    for (i = 0; i < num_values; i++) {
        sum += *values;
        values++;
    }
    return (int)sum / num_values;
}
```
return (int)((sum / num_values) + 0.5);
}

Suggested Uses  Use the kernel floating point services when an application needs to perform floating point operations.

Configuration Options  To configure unshared FP registers mode, enable the CONFIG_FPU configuration option and leave the CONFIG_FPU_SHARING configuration option disabled.

To configure shared FP registers mode, enable both the CONFIG_FPU configuration option and the CONFIG_FPU_SHARING configuration option. Also, ensure that any thread that uses the floating point registers has sufficient added stack space for saving floating point register values during context switches, as described above.

For x86, use the CONFIG_X86_SSE configuration option to enable support for SSEx instructions.

API Reference

group float APIs

Functions

int k_float_disable(struct k_thread *thread)
Disable preservation of floating point context information.

This routine informs the kernel that the specified thread will no longer be using the floating point registers.

Warning: Some architectures apply restrictions on how the disabling of floating point preservation may be requested, see arch_float_disable.

Warning: This routine should only be used to disable floating point support for a thread that currently has such support enabled.

Parameters

• thread – ID of thread.

Return values

• 0 – On success.
• -ENOTSUP – If the floating point disabling is not implemented. -EINVAL If the floating point disabling could not be performed.

int k_float_enable(struct k_thread *thread, unsigned int options)
Enable preservation of floating point context information.

This routine informs the kernel that the specified thread will use the floating point registers.
Invoking this routine initializes the thread's floating point context info to that of an FPU that has been reset. The next time the thread is scheduled by \textit{z\_swap()} it will either inherit an FPU that is guaranteed to be in a “sane” state (if the most recent user of the FPU was cooperatively swapped out) or the thread's own floating point context will be loaded (if the most recent user of the FPU was preempted, or if this thread is the first user of the FPU). Thereafter, the kernel will protect the thread's FP context so that it is not altered during a preemptive context switch.

The \textit{options} parameter indicates which floating point register sets will be used by the specified thread. For x86 options:

- K\_FP\_REGS indicates x87 FPU and MMX registers only
- K\_SSE\_REGS indicates SSE registers (and also x87 FPU and MMX registers)

\textbf{Warning:} Some architectures apply restrictions on how the enabling of floating point preservation may be requested, see arch\_float\_enable.

\textbf{Warning:} This routine should only be used to enable floating point support for a thread that currently has such support enabled.

\textbf{Parameters}

- \textit{thread} – ID of thread.
- \textit{options} – architecture dependent options

\textbf{Return values}

- \texttt{0} – On success.
- \texttt{-ENOTSUP} – If the floating point enabling is not implemented. \texttt{-EINVAL} If the floating point enabling could not be performed.

\section*{Version}

Kernel version handling and APIs related to kernel version being used.

\textbf{API Reference}

\begin{verbatim}
uint32_t sys_kernel_version_get(void)
\end{verbatim}

Return the kernel version of the present build.

The kernel version is a four-byte value, whose format is described in the file “kernel\_version.h”.

\textbf{Returns}

- \texttt{kernel version}

- \texttt{SYS\_KERNEL\_VER\_MAJOR} (ver)
- \texttt{SYS\_KERNEL\_VER\_MINOR} (ver)
- \texttt{SYS\_KERNEL\_VER\_PATCHLEVEL} (ver)
Fatal Errors

Software Errors Triggered in Source Code Zephyr provides several methods for inducing fatal error conditions through either build-time checks, conditionally compiled assertions, or deliberately invoked panic or oops conditions.

Runtime Assertions Zephyr provides some macros to perform runtime assertions which may be conditionally compiled. Their definitions may be found in include/zephyr/sys/__assert.h.

Assertions are enabled by setting the __ASSERT_ON preprocessor symbol to a non-zero value. There are two ways to do this:

- Use the CONFIG_ASSERT and CONFIG_ASSERT_LEVEL kconfig options.
- Add -D__ASSERT_ON=<level> to the project's CFLAGS, either on the build command line or in a CMakeLists.txt.

The __ASSERT_ON method takes precedence over the kconfig option if both are used.

Specifying an assertion level of 1 causes the compiler to issue warnings that the kernel contains debug-type __ASSERT() statements; this reminder is issued since assertion code is not normally present in a final product. Specifying assertion level 2 suppresses these warnings.

Assertions are enabled by default when running Zephyr test cases, as configured by the CONFIG_TEST option.

The policy for what to do when encountering a failed assertion is controlled by the implementation of assert_post_action(). Zephyr provides a default implementation with weak linkage which invokes a kernel oops if the thread that failed the assertion was running in user mode, and a kernel panic otherwise.

__ASSERT() The __ASSERT() macro can be used inside kernel and application code to perform optional runtime checks which will induce a fatal error if the check does not pass. The macro takes a string message which will be printed to provide context to the assertion. In addition, the kernel will print a text representation of the expression code that was evaluated, and the file and line number where the assertion can be found.

For example:

```
__ASSERT(foo == 0xF0CACC1A, "Invalid value of foo, got 0x%x", foo);
```

If at runtime foo had some unexpected value, the error produced may look like the following:

```
ASSERTION FAIL [foo == 0xF0CACC1A] @ ZEPHYR_BASE/tests/kernel/fatal/src/main.c:367
  Invalid value of foo, got 0xdeadbeef
  
  [00:00:00.000,000] <err> os: r0/a1: 0x00000004 r1/a2: 0x0000016f r2/a3: 0x00000000
  [00:00:00.000,000] <err> os: r3/a4: 0x00000000 r12/ip: 0x00000000 r14/lr: 0x00000a6d
  [00:00:00.000,000] <err> os: xpsr: 0x61000000
  [00:00:00.000,000] <err> os: Faulting instruction address (r15/pc): 0x000009fe4
  [00:00:00.000,000] <err> os: >>> ZEPHYR FATAL ERROR 4: Kernel panic
  [00:00:00.000,000] <err> os: Current thread: 0x20000414 (main)
  [00:00:00.000,000] <err> os: Halting system
```

__ASSERT_EVAL() The __ASSERT_EVAL() macro can also be used inside kernel and application code, with special semantics for the evaluation of its arguments.

It makes use of the __ASSERT() macro, but has some extra flexibility. It allows the developer to specify different actions depending whether the __ASSERT() macro is enabled or not. This can be particularly useful to prevent the compiler from generating comments (errors, warnings or remarks) about variables that are only used with __ASSERT() being assigned a value, but otherwise unused when the __ASSERT() macro is disabled.
Consider the following example:

```c
int x;
x = foo();
__ASSERT(x != 0, "foo() returned zero!");
```

If `__ASSERT()` is disabled, then `x` is assigned a value, but never used. This type of situation can be resolved using the `__ASSERT_EVAL()` macro.

```c
__ASSERT_EVAL((void) foo(),
         int x = foo(),
         x != 0,
         "foo() returned zero!");
```

The first parameter tells `__ASSERT_EVAL()` what to do if `__ASSERT()` is disabled. The second parameter tells `__ASSERT_EVAL()` what to do if `__ASSERT()` is enabled. The third and fourth parameters are the parameters it passes to `__ASSERT()`.

`__ASSERT_NO_MSG()` The `__ASSERT_NO_MSG()` macro can be used to perform an assertion that reports the failed test and its location, but lacks additional debugging information provided to assist the user in diagnosing the problem; its use is discouraged.

**Build Assertions** Zephyr provides two macros for performing build-time assertion checks. These are evaluated completely at compile-time, and are always checked.

`BUILD_ASSERT()` This has the same semantics as C's `_Static_assert` or C++’s `static_assert`. If the evaluation fails, a build error will be generated by the compiler. If the compiler supports it, the provided message will be printed to provide further context.

Unlike `__ASSERT()`, the message must be a static string, without `printf()`-like format codes or extra arguments.

For example, suppose this check fails:

```c
BUILD_ASSERT(FOO == 2000, "Invalid value of FOO");
```

With GCC, the output resembles:

```
tests/kernel/fatal/src/main.c: In function 'test_main':
include/toolchain/gcc.h:28:37: error: static assertion failed: "Invalid value of FOO"
#define BUILD_ASSERT(EXPR, MSG) _Static_assert(EXPR, "" MSG)
^~~~~~~~~~~~~~
tests/kernel/fatal/src/main.c:370:2: note: in expansion of macro 'BUILD_ASSERT'
BUILD_ASSERT(FOO == 2000,
^~~~~~~~~~~~~~
```

**Kernel Oops** A kernel oops is a software triggered fatal error invoked by `k_oops()`. This should be used to indicate an unrecoverable condition in application logic.

The fatal error reason code generated will be `K_ERR_KERNEL_OOPS`.

**Kernel Panic** A kernel error is a software triggered fatal error invoked by `k_panic()`. This should be used to indicate that the Zephyr kernel is in an unrecoverable state. Implementations of `k_sys_fatal_error_handler()` should not return if the kernel encounters a panic condition, as the entire system needs to be reset.
Threads running in user mode are not permitted to invoke `k_panic()`, and doing so will generate a kernel oops instead. Otherwise, the fatal error reason code generated will be `K_ERR_KERNEL_PANIC`.

**Exceptions**

**Spurious Interrupts** If the CPU receives a hardware interrupt on an interrupt line that has not had a handler installed with `IRQ_CONNECT()` or `irq_connect_dynamic()`, then the kernel will generate a fatal error with the reason code `K_ERR_SPURIOUS_IRQ()`.

**Stack Overflows** In the event that a thread pushes more data onto its execution stack than its stack buffer provides, the kernel may be able to detect this situation and generate a fatal error with a reason code of `K_ERR_STACK_CHK_FAIL`.

If a thread is running in user mode, then stack overflows are always caught, as the thread will simply not have permission to write to adjacent memory addresses outside of the stack buffer. Because this is enforced by the memory protection hardware, there is no risk of data corruption to memory that the thread would not otherwise be able to write to.

If a thread is running in supervisor mode, or if `CONFIG_USERSPACE` is not enabled, depending on configuration stack overflows may or may not be caught. `CONFIG_HW_STACK_PROTECTION` is supported on some architectures and will catch stack overflows in supervisor mode, including when handling a system call on behalf of a user thread. Typically this is implemented via dedicated CPU features, or read-only MMU/MPU guard regions placed immediately adjacent to the stack buffer. Stack overflows caught in this way can detect the overflow, but cannot guarantee against data corruption and should be treated as a very serious condition impacting the health of the entire system.

If a platform lacks memory management hardware support, `CONFIG_STACK_SENTINEL` is a software-only stack overflow detection feature which periodically checks if a sentinel value at the end of the stack buffer has been corrupted. It does not require hardware support, but provides no protection against data corruption. Since the checks are typically done at interrupt exit, the overflow may be detected a nontrivial amount of time after the stack actually overflowed.

Finally, Zephyr supports GCC compiler stack canaries via `CONFIG_STACK_CANARIES`. If enabled, the compiler will insert a canary value randomly generated at boot into function stack frames, checking that the canary has not been overwritten at function exit. If the check fails, the compiler invokes `__stack_chk_fail()`, whose Zephyr implementation invokes a fatal stack overflow error. An error in this case does not indicate that the entire stack buffer has overflowed, but instead that the current function stack frame has been corrupted. See the compiler documentation for more details.

**Other Exceptions** Any other type of unhandled CPU exception will generate an error code of `K_ERR_CPU_EXCEPTION`.

**Fatal Error Handling** The policy for what to do when encountering a fatal error is determined by the implementation of the `k_sys_fatal_error_handler()` function. This function has a default implementation with weak linkage that calls `LOG_PANIC()` to dump all pending logging messages and then unconditionally halts the system with `k_fatal_halt()`.

Applications are free to implement their own error handling policy by overriding the implementation of `k_sys_fatal_error_handler()`. If the implementation returns, the faulting thread will be aborted and the system will otherwise continue to function. See the documentation for this function for additional details and constraints.
API Reference

*group* fatal_apis

**Functions**

```c
FUNC_NORETURN void k_fatal_halt(unsigned int reason)

Halt the system on a fatal error.

Invokes architecture-specific code to power off or halt the system in a low power state. Lacking that, lock interrupts and sit in an idle loop.

**Parameters**
- **reason** – Fatal exception reason code
```

```c
void k_sys_fatal_error_handler(unsigned int reason, const z_arch_esf_t *esf)

Fatal error policy handler.

This function is not invoked by application code, but is declared as a weak symbol so that applications may introduce their own policy.

The default implementation of this function halts the system unconditionally. Depending on architecture support, this may be a simple infinite loop, power off the hardware, or exit an emulator.

If this function returns, then the currently executing thread will be aborted.

A few notes for custom implementations:

- If the error is determined to be unrecoverable, `LOG_PANIC()` should be invoked to flush any pending logging buffers.
- `K_ERR_KERNEL_PANIC` indicates a severe unrecoverable error in the kernel itself, and should not be considered recoverable. There is an assertion in `z_fatal_error()` to enforce this.
- Even outside of a kernel panic, unless the fault occurred in user mode, the kernel itself may be in an inconsistent state, with API calls to kernel objects possibly exhibiting undefined behavior or triggering another exception.

**Parameters**
- **reason** – The reason for the fatal error
- **esf** – Exception context, with details and partial or full register state when the error occurred. May in some cases be NULL.
```

**Thread Local Storage (TLS)**

Thread Local Storage (TLS) allows variables to be allocated on a per-thread basis. These variables are stored in the thread stack which means every thread has its own copy of these variables.

Zephyr currently requires toolchain support for TLS.

**Configuration**

To enable thread local storage in Zephyr, `CONFIG_THREAD_LOCAL_STORAGE` needs to be enabled. Note that this option may not be available if the architecture or the SoC does not have the hidden option `CONFIG_ARCH_HAS_THREAD_LOCAL_STORAGE` enabled, which means the architecture or the SoC does not have the necessary code to support thread local storage and/or the toolchain does not support TLS.
CONFIG_ERRNO_IN_TLS can be enabled together with CONFIG_ERRNO to let the variable errno be a thread local variable. This allows user threads to access the value of errno without making a system call.

**Declaring and Using Thread Local Variables**  The keyword __thread can be used to declare thread local variables.

For example, to declare a thread local variable in header files:

```c
extern __thread int i;
```

And to declare the actual variable in source files:

```c
__thread int i;
```

Keyword static can also be used to limit the variable within a source file:

```c
static __thread int j;
```

Using the thread local variable is the same as using other variable, for example:

```c
void testing(void) {
    i = 10;
}
```

### 3.2 Device Driver Model

#### 3.2.1 Introduction

The Zephyr kernel supports a variety of device drivers. Whether a driver is available depends on the board and the driver.

The Zephyr device model provides a consistent device model for configuring the drivers that are part of a system. The device model is responsible for initializing all the drivers configured into the system.

Each type of driver (e.g. UART, SPI, I2C) is supported by a generic type API.

In this model the driver fills in the pointer to the structure containing the function pointers to its API functions during driver initialization. These structures are placed into the RAM section in initialization level order.
3.2.2 Standard Drivers

Device drivers which are present on all supported board configurations are listed below.

- **Interrupt controller**: This device driver is used by the kernel's interrupt management subsystem.
- **Timer**: This device driver is used by the kernel's system clock and hardware clock subsystem.
- **Serial communication**: This device driver is used by the kernel's system console subsystem.
- **Entropy**: This device driver provides a source of entropy numbers for the random number generator subsystem.

**Important**: Use the random API functions for random values. Entropy functions should not be directly used as a random number generator source as some hardware implementations are designed to be an entropy seed source for random number generators and will not provide cryptographically secure random number streams.

3.2.3 Synchronous Calls

Zephyr provides a set of device drivers for multiple boards. Each driver should support an interrupt-based implementation, rather than polling, unless the specific hardware does not provide any interrupt.

High-level calls accessed through device-specific APIs, such as i2c.h or spi.h, are usually intended as synchronous. Thus, these calls should be blocking.
3.2.4 Driver APIs

The following APIs for device drivers are provided by device.h. The APIs are intended for use in device drivers only and should not be used in applications.

`DEVICE_DEFINE()`
Create device object and related data structures including setting it up for boot-time initialization.

`DEVICE_NAME_GET()`
Converts a device identifier to the global identifier for a device object.

`DEVICE_GET()`
Obtain a pointer to a device object by name.

`DEVICE_DECLARE()`
Declare a device object. Use this when you need a forward reference to a device that has not yet been defined.

3.2.5 Driver Data Structures

The device initialization macros populate some data structures at build time which are split into read-only and runtime-mutable parts. At a high level we have:

```c
struct device {
    const char *name;
    const void *config;
    const void *api;
    void *const data;
};
```

The `config` member is for read-only configuration data set at build time. For example, base memory mapped IO addresses, IRQ line numbers, or other fixed physical characteristics of the device. This is the `config` pointer passed to `DEVICE_DEFINE()` and related macros.

The `data` struct is kept in RAM, and is used by the driver for per-instance runtime housekeeping. For example, it may contain reference counts, semaphores, scratch buffers, etc.

The `api` struct maps generic subsystem APIs to the device-specific implementations in the driver. It is typically read-only and populated at build time. The next section describes this in more detail.

3.2.6 Subsystems and API Structures

Most drivers will be implementing a device-independent subsystem API. Applications can simply program to that generic API, and application code is not specific to any particular driver implementation.

A subsystem API definition typically looks like this:

```c
typedef int (*subsystem_do_this_t)(const struct device *dev, int foo, int bar);
typedef void (*subsystem_do_that_t)(const struct device *dev, void *baz);

struct subsystem_api {
    subsystem_do_this_t do_this;
    subsystem_do_that_t do_that;
};

static inline int subsystem_do_this(const struct device *dev, int foo, int bar)
{
    // Implementation
}
```

(continues on next page)
A driver implementing a particular subsystem will define the real implementation of these APIs, and populate an instance of subsystem_api structure:

```c
static int my_driver_do_this(const struct device *dev, int foo, int bar)
{
    ...
}
static void my_driver_do_that(const struct device *dev, void *baz)
{
    ...
}
static struct subsystem_api my_driver_api_funcs = {
    .do_this = my_driver_do_this,
    .do_that = my_driver_do_that
};
```

The driver would then pass `my_driver_api_funcs` as the `api` argument to `DEVICE_DEFINE()`.

**Note:** Since pointers to the API functions are referenced in the `api` struct, they will always be included in the binary even if unused; `gc-sections` linker option will always see at least one reference to them. Providing for link-time size optimizations with driver APIs in most cases requires that the optional feature be controlled by a Kconfig option.

### 3.2.7 Device-Specific API Extensions

Some devices can be cast as an instance of a driver subsystem such as GPIO, but provide additional functionality that cannot be exposed through the standard API. These devices combine subsystem operations with device-specific APIs, described in a device-specific header.

A device-specific API definition typically looks like this:

```c
#include <zephyr/drivers/subsystem.h>

/* When extensions need not be invoked from user mode threads */
int specific_do_that(const struct device *dev, int foo);

/* When extensions must be invokable from user mode threads */
__syscall int specific_from_user(const struct device *dev, int bar);

/* Only needed when extensions include syscalls */
#include <syscalls/specific.h>
```
A driver implementing extensions to the subsystem will define the real implementation of both the subsystem API and the specific APIs:

```c
static int generic_do_this(const struct device *dev, void *arg)
{
    ...
}

static struct generic_api api {
    ...
    .do_this = generic_do_this,
    ...
};

/* supervisor-only API is globally visible */
int specific_do_that(const struct device *dev, int foo)
{
    ...
}

/* syscall API passes through a translation */
int z_impl_specific_from_user(const struct device *dev, int bar)
{
    ...
}

#ifdef CONFIG_USERSPACE
#include <zephyr/internal/syscall_handler.h>

int z_vrfy_specific_from_user(const struct device *dev, int bar)
{
    K_OOPS(K_SYSCALL_SPECIFIC_DRIVER(dev, K_OBJ_DRIVER_GENERIC, &api));
    return z_impl_specific_do_that(dev, bar)
}
#include <syscalls/specific_from_user_mrsh.c>
#endif /* CONFIG_USERSPACE */
```

Applications use the device through both the subsystem and specific APIs.

**Note:** Public API for device-specific extensions should be prefixed with the compatible for the device to which it applies. For example, if adding special functions to support the Maxim DS3231 the identifier fragment specific in the examples above would be maxim_ds3231.

### 3.2.8 Single Driver, Multiple Instances

Some drivers may be instantiated multiple times in a given system. For example there can be multiple GPIO banks, or multiple UARTS. Each instance of the driver will have a different config struct and data struct.

Configuring interrupts for multiple drivers instances is a special case. If each instance needs to configure a different interrupt line, this can be accomplished through the use of per-instance configuration functions, since the parameters to IRQ_CONNECT() need to be resolvable at build time.

For example, let’s say we need to configure two instances of my_driver, each with a different interrupt line. In drivers/subsystem/subsystem_my_driver.h:
typedef void (*my_driver_config_irq_t)(const struct device *dev);

struct my_driver_config {
    DEVICE_MMIO_ROM;
    my_driver_config_irq_t config_func;
};

In the implementation of the common init function:

```c
void my_driver_isr(const struct device *dev)
{
    /* Handle interrupt */
    ...
}

int my_driver_init(const struct device *dev)
{
    const struct my_driver_config *config = dev->config;
    DEVICE_MMIO_MAP(dev, K_MEM_CACHE_NONE);
    /* Do other initialization stuff */
    ...
    config->config_func(dev);
    return 0;
}
```

Then when the particular instance is declared:

```c
#if CONFIG_MY_DRIVER_0
DEVICE_DECLARE(my_driver_0);

static void my_driver_config_irq_0(const struct device *dev)
{
    IRQ_CONNECT(MY_DRIVER_0_IRQ, MY_DRIVER_0_PRI, my_driver_isr,
                DEVICE_GET(my_driver_0), MY_DRIVER_0_FLAGS);
}

const static struct my_driver_config my_driver_config_0 = {
    DEVICE_MMIO_ROM_INIT(DT_DRV_INST(0)),
    .config_func = my_driver_config_irq_0
}

static struct my_data_0;

DEVICE_DEFINE(my_driver_0, MY_DRIVER_0_NAME, my_driver_init,
              NULL, &my_data_0, &my_driver_config_0,
              POST_KERNEL, MY_DRIVER_0_PRIORITY, &my_api_funcs);
#endif /* CONFIG_MY_DRIVER_0 */
```

Note the use of `DEVICE_DECLARE()` to avoid a circular dependency on providing the IRQ handler argument and the definition of the device itself.

### 3.2.9 Initialization Levels

Drivers may depend on other drivers being initialized first, or require the use of kernel services. `DEVICE_DEFINE()` and related APIs allow the user to specify at what time during the boot
sequence the init function will be executed. Any driver will specify one of four initialization levels:

**PRE_KERNEL_1**

Used for devices that have no dependencies, such as those that rely solely on hardware present in the processor/SOC. These devices cannot use any kernel services during configuration, since the kernel services are not yet available. The interrupt subsystem will be configured however so it's OK to set up interrupts. Init functions at this level run on the interrupt stack.

**PRE_KERNEL_2**

Used for devices that rely on the initialization of devices initialized as part of the PRE_KERNEL_1 level. These devices cannot use any kernel services during configuration, since the kernel services are not yet available. Init functions at this level run on the interrupt stack.

**POST_KERNEL**

Used for devices that require kernel services during configuration. Init functions at this level run in context of the kernel main task.

Within each initialization level you may specify a priority level, relative to other devices in the same initialization level. The priority level is specified as an integer value in the range 0 to 99; lower values indicate earlier initialization. The priority level must be a decimal integer literal without leading zeroes or sign (e.g. 32), or an equivalent symbolic name (e.g. \#define MY_INIT_PRIO 32); symbolic expressions are not permitted (e.g. CONFIG_KERNEL_INIT_PRIORITY_DEFAULT + 5).

Drivers and other system utilities can determine whether startup is still in pre-kernel states by using the \_is\_pre\_kernel() function.

### 3.2.10 System Drivers

In some cases you may just need to run a function at boot. For such cases, the SYS_INIT can be used. This macro does not take any config or runtime data structures and there isn't a way to later get a device pointer by name. The same device policies for initialization level and priority apply.

### 3.2.11 Inspecting the initialization sequence

Device drivers declared with DEVICE\_DEFINE (or any variations of it) and SYS_INIT are processed at boot time and the corresponding initialization functions are called sequentially according to their specified level and priority.

Sometimes it's useful to inspect the final sequence of initialization function call as produced by the linker. To do that, use the initlevels CMake target, for example west build -t initlevels.

### 3.2.12 Error handling

In general, it's best to use \_\_ASSERT() macros instead of propagating return values unless the failure is expected to occur during the normal course of operation (such as a storage device full). Bad parameters, programming errors, consistency checks, pathological/unrecoverable failures, etc., should be handled by assertions.

When it is appropriate to return error conditions for the caller to check, 0 should be returned on success and a POSIX errno.h code returned on failure. See https://github.com/zephyrproject-rtos/zephyr/wiki/Naming-Conventions#return-codes for details about this.
3.2.13 Memory Mapping

On some systems, the linear address of peripheral memory-mapped I/O (MMIO) regions cannot be known at build time:

- The I/O ranges must be probed at runtime from the bus, such as with PCI express
- A memory management unit (MMU) is active, and the physical address of the MMIO range must be mapped into the page tables at some virtual memory location determined by the kernel.

These systems must maintain storage for the MMIO range within RAM and establish the mapping within the driver's init function. Other systems do not care about this and can use MMIO physical addresses directly from DTS and do not need any RAM-based storage for it.

For drivers that may need to deal with this situation, a set of APIs under the DEVICE_MMIO scope are defined, along with a mapping function device_map().

Device Model Drivers with one MMIO region

The simplest case is for drivers which need to maintain one MMIO region. These drivers will need to use the DEVICE_MMIO_ROM and DEVICE_MMIO_RAM macros in the definitions for their config_info and driver_data structures, with initialization of the config_info from DTS using DEVICE_MMIO_ROM_INIT. A call to DEVICE_MMIO_MAP() is made within the init function:

```c
struct my_driver_config {
    DEVICE_MMIO_ROM; /* Must be first */
    ...
}

struct my_driver_dev_data {
    DEVICE_MMIO_RAM; /* Must be first */
    ...
}

const static struct my_driver_config my_driver_config_0 = {
    DEVICE_MMIO_ROM_INIT(DT_DRV_INST(...)),
    ...
};

int my_driver_init(const struct device *dev) {
    ...
    DEVICE_MMIO_MAP(dev, K_MEM_CACHE_NONE);
    ...
}

int my_driver_some_function(const struct device *dev) {
    ...
    /* Write some data to the MMIO region */
    sys_write32(0xDEADBEEF, DEVICE_MMIO_GET(dev));
    ...
}
```

The particular expansion of these macros depends on configuration. On a device with no MMU or PCI-e, DEVICE_MMIO_MAP and DEVICE_MMIO_RAM expand to nothing.
Device Model Drivers with multiple MMIO regions

Some drivers may have multiple MMIO regions. In addition, some drivers may already be implementing a form of inheritance which requires some other data to be placed first in the config_info and driver_data structures.

This can be managed with the DEVICE_MMIO_NAMED variant macros. These require that DEV_CFG() and DEV_DATA() macros be defined to obtain a properly typed pointer to the driver’s config_info or dev_data structs. For example:

```c
struct my_driver_config {
    ...
    DEVICE_MMIO_NAMED_ROM(corge);
    DEVICE_MMIO_NAMED_ROM(grault);
    ...
}

struct my_driver_dev_data {
    ...
    DEVICE_MMIO_NAMED_RAM(corge);
    DEVICE_MMIO_NAMED_RAM(grault);
    ...
}

#define DEV_CFG(_dev) \
    ((const struct my_driver_config *)((_dev)->config))

#define DEV_DATA(_dev) \
    ((struct my_driver_dev_data *)((_dev)->data))

const static struct my_driver_config my_driver_config_0 = {
    ...
    DEVICE_MMIO_NAMED_ROM_INIT(corge, DT_DRV_INST(...)),
    DEVICE_MMIO_NAMED_ROM_INIT(grault, DT_DRV_INST(...)),
    ...
}

int my_driver_init(const struct device *dev)
{
    ...
    DEVICE_MMIO_NAMED_MAP(dev, corge, K_MEM_CACHE_NONE);
    DEVICE_MMIO_NAMED_MAP(dev, grault, K_MEM_CACHE_NONE);
    ...
}

int my_driver_some_function(const struct device *dev)
{
    /* Write some data to the MMIO regions */
    sys_write32(0xDEADBEEF, DEVICE_MMIO_GET(dev, grault));
    sys_write32(0xF0CCAC1A, DEVICE_MMIO_GET(dev, corge));
    ...
}
```

Device Model Drivers with multiple MMIO regions in the same DT node

Some drivers may have multiple MMIO regions defined into the same DT device node using the reg-names property to differentiate them, for example:
This can be managed as seen in the previous section but this time using the DEVICE_MMIO_NAMED_ROM_INIT_BY_NAME macro instead. So the only difference would be in the driver config struct:

```c
const static struct my_driver_config my_driver_config_0 = {
  ...
  DEVICE_MMIO_NAMED_ROM_INIT_BY_NAME(corge, DT_DRV_INST(...)),
  DEVICE_MMIO_NAMED_ROM_INIT_BY_NAME(grault, DT_DRV_INST(...)),
  ...
};
```

**Drivers that do not use Zephyr Device Model**

Some drivers or driver-like code may not use Zephyr’s device model, and alternative storage must be arranged for the MMIO data. An example of this are timer drivers, or interrupt controller code.

This can be managed with the DEVICE_MMIO_TOLEVEL set of macros, for example:

```c
DEVICE_MMIO_TOLEVEL_STATIC(my_regs, DT_DRV_INST(...));

void some_init_code(...) {
  ...
  DEVICE_MMIO_TOLEVEL_MAP(my_regs, K_MEM_CACHE_NONE);
  ...
}
void some_function(...) {
  ...
  sys_write32(DEVICE_MMIO_TOLEVEL_GET(my_regs), 0xDEADBEEF);
  ...
}
```

**Drivers that do not use DTS**

Some drivers may not obtain the MMIO physical address from DTS, such as is the case with PCI-E. In this case the device_map() function may be used directly:

```c
void some_init_code(...) {
  ...
  struct pcie_bar mbar;
  bool bar_found = pcie_get_mbar(bdf, index, &mbar);
  device_map(DEVICE_MMIO_RAM_PTR(dev), mbar.phys_addr, mbar.size, K_MEM_CACHE_NONE);
  ...
}
For these cases, DEVICE_MMIO_ROM directives may be omitted.

### 3.2.14 API Reference

#### group device_model

Device Model.

**Defines**

DEVICE_HANDLE_NULL

Flag value used to identify an unknown device.

DEVICE_NAME_GET(dev_id)

Expands to the name of a global device object.

Return the full name of a device object symbol created by DEVICE_DEFINE(), using the dev_id provided to DEVICE_DEFINE(). This is the name of the global variable storing the device structure, not a pointer to the string in the device::name field.

It is meant to be used for declaring extern symbols pointing to device objects before using the DEVICE_GET macro to get the device object.

This macro is normally only useful within device driver source code. In other situations, you are probably looking for device_get_binding().

**Parameters**

- dev_id – Device identifier.

**Returns**

The full name of the device object defined by device definition macros.

DEVICE_DEFINE(dev_id, name, init_fn, pm, data, config, level, prio, api)

Create a device object and set it up for boot time initialization.

This macro defines a device that is automatically configured by the kernel during system initialization. This macro should only be used when the device is not being allocated from a devicetree node. If you are allocating a device from a devicetree node, use DEVICE_DT_DEFINE() or DEVICE_DT_INST_DEFINE() instead.

**Parameters**

- dev_id – A unique token which is used in the name of the global device structure as a C identifier.
- name – A string name for the device, which will be stored in device::name. This name can be used to look up the device with device_get_binding(). This must be less than Z_DEVICE_MAX_NAME_LEN characters (including terminating NULL) in order to be looked up from user mode.
- init_fn – Pointer to the device’s initialization function, which will be run by the kernel during system initialization. Can be NULL.
- pm – Pointer to the device’s power management resources, a pm_device, which will be stored in device::pm field. Use NULL if the device does not use PM.
- data – Pointer to the device’s private mutable data, which will be stored in device::data.
- **config** – Pointer to the device's private constant data, which will be stored in `device::config`.
- **level** – The device's initialization level (PRE_KERNEL_1, PRE_KERNEL_2 or POST_KERNEL).
- **prio** – The device's priority within its initialization level. See SYS_INIT() for details.
- **api** – Pointer to the device's API structure. Can be NULL.

**DEVICE_DT_NAME(node_id)**

Return a string name for a devicetree node.

This macro returns a string literal usable as a device's name from a devicetree node identifier.

**Parameters**

- **node_id** – The devicetree node identifier.

**Returns**

The value of the node's label property, if it has one. Otherwise, the node's full name in node-name@unit-address form.

**DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, level, prio, api, ...)**

Create a device object from a devicetree node identifier and set it up for boot time initialization.

This macro defines a *device* that is automatically configured by the kernel during system initialization. The global device object's name as a C identifier is derived from the node's dependency ordinal. `device::name` is set to `DEVICE_DT_NAME(node_id)`.

The device is declared with extern visibility, so a pointer to a global device object can be obtained with `DEVICE_DT_GET(node_id)` from any source file that includes `<zephyr/device.h>`. Before using the pointer, the referenced object should be checked using `device_is_ready()`.

**Parameters**

- **node_id** – The devicetree node identifier.
- **init_fn** – Pointer to the device's initialization function, which will be run by the kernel during system initialization. Can be NULL.
- **pm** – Pointer to the device's power management resources, a `pm_device`, which will be stored in `device::pm`. Use NULL if the device does not use PM.
- **data** – Pointer to the device's private mutable data, which will be stored in `device::data`.
- **config** – Pointer to the device's private constant data, which will be stored in `device::config` field.
- **level** – The device's initialization level (PRE_KERNEL_1, PRE_KERNEL_2 or POST KERNEL).
- **prio** – The device's priority within its initialization level. See SYS_INIT() for details.
- **api** – Pointer to the device's API structure. Can be NULL.

**DEVICE_DT_INST_DEFINE(inst, ...)**

Like `DEVICE_DT_DEFINE()`, but uses an instance of a `DT_DRV_COMPAT` compatible instead of a node identifier.

**Parameters**
• inst – Instance number. The node_id argument to `DEVICE_DT_DEFINE()` is set to `DT_DRV_INST(inst)`.
• ... – Other parameters as expected by `DEVICE_DT_DEFINE()`.

`DEVICE_DT_NAME_GET(node_id)`
The name of the global device object for node_id.

Returns the name of the global device structure as a C identifier. The device must be allocated using `DEVICE_DT_DEFINE()` or `DEVICE_DT_INST_DEFINE()` for this to work.

This macro is normally only useful within device driver source code. In other situations, you are probably looking for `DEVICE_DT_GET()`.

Parameters
• node_id – Devicetree node identifier

Returns
The name of the device object as a C identifier

`DEVICE_DT_GET(node_id)`
Get a device reference from a devicetree node identifier.

Returns a pointer to a device object created from a devicetree node, if any device was allocated by a driver.

If no such device was allocated, this will fail at linker time. If you get an error that looks like `undefined reference to __device_dts_ord_<N>`, that is what happened. Check to make sure your device driver is being compiled, usually by enabling the Kconfig options it requires.

Parameters
• node_id – A devicetree node identifier

Returns
A pointer to the device object created for that node

`DEVICE_DT_INST_GET(inst)`
Get a device reference for an instance of a `DT_DRV_COMPAT` compatible.

This is equivalent to `DEVICE_DT_GET(DT_DRV_INST(inst))`.

Parameters
• inst – `DT_DRV_COMPAT` instance number

Returns
A pointer to the device object created for that instance

`DEVICE_DT_GET_ANY(compat)`
Get a device reference from a devicetree compatible.

If an enabled devicetree node has the given compatible and a device object was created from it, this returns a pointer to that device.

If there no such devices, this returns NULL.

If there are multiple, this returns an arbitrary one.

If this returns non-NULL, the device must be checked for readiness before use, e.g. with `device_is_ready()`.

Parameters
• compat – lowercase-and-underscores devicetree compatible

Returns
a pointer to a device, or NULL
DEVICE_DT_GET_ONE(compat)
Get a device reference from a devicetree compatible.

If an enabled devicetree node has the given compatible and a device object was created from it, this returns a pointer to that device.
If there are no such devices, this will fail at compile time.
If there are multiple, this returns an arbitrary one.
If this returns non-NULL, the device must be checked for readiness before use, e.g. with `device_is_ready()`.

Parameters
- compat – lowercase-and-underscores devicetree compatible

Returns
a pointer to a device

DEVICE_DT_GET_OR_NULL(node_id)
Utility macro to obtain an optional reference to a device.

If the node identifier refers to a node with status okay, this returns `DEVICE_DT_GET(node_id)`. Otherwise, it returns NULL.

Parameters
- node_id – devicetree node identifier

Returns
a device reference for the node identifier, which may be NULL.

DEVICE_GET(dev_id)
Obtain a pointer to a device object by name.

Return the address of a device object created by `DEVICE_DEFINE()`, using the dev_id provided to `DEVICE_DEFINE()`.

Parameters
- dev_id – Device identifier.

Returns
A pointer to the device object created by `DEVICE_DEFINE()`

DEVICE_DECLARE(dev_id)
Declare a static device object.

This macro can be used at the top-level to declare a device, such that `DEVICE_GET()` may be used before the full declaration in `DEVICE_DEFINE()`.

This is often useful when configuring interrupts statically in a device’s init or per-instance config function, as the init function itself is required by `DEVICE_DEFINE()` and use of `DEVICE_GET()` inside it creates a circular dependency.

Parameters
- dev_id – Device identifier.

DEVICE_INIT_DT_GET(node_id)
Get a init_entry reference from a devicetree node.

Parameters
- node_id – A devicetree node identifier

Returns
A pointer to the init_entry object created for that node
DEVICE_INIT_GET(dev_id)
Get a init_entry reference from a device identifier.

**Parameters**
- dev_id – Device identifier.

**Returns**
A pointer to the init_entry object created for that device

**TypeDefs**

typedef int16_t device_handle_t
Type used to represent a “handle” for a device.

Every device has an associated handle. You can get a pointer to a device from its handle and vice versa, but the handle uses less space than a pointer. The device.h API mainly uses handles to store lists of multiple devices in a compact way.

The extreme values and zero have special significance. Negative values identify functionality that does not correspond to a Zephyr device, such as the system clock or a SYS_INIT() function.

**See also:**
device_handle_get()

**See also:**
device_from_handle()

typedef int (*device_visitor_callback_t)(const struct device *dev, void *context)
Prototype for functions used when iterating over a set of devices.

Such a function may be used in API that identifies a set of devices and provides a visitor API supporting caller-specific interaction with each device in the set.

The visit is said to succeed if the visitor returns a non-negative value.

**See also:**
device_required_foreach()

**See also:**
device_supported_foreach()

**Param dev**
a device in the set being iterated

**Param context**
state used to support the visitor function

**Return**
A non-negative number to allow walking to continue, and a negative error code to case the iteration to stop.
**Functions**

static inline `device_handle_t device_handle_get(const struct device *dev)`

Get the handle for a given device.

**Parameters**
- `dev` – the device for which a handle is desired.

**Returns**
- the handle for the device, or DEVICE_HANDLE_NULL if the device does not have an associated handle.

static inline const struct device* `device_from_handle(device_handle_t dev_handle)`

Get the device corresponding to a handle.

**Parameters**
- `dev_handle` – the device handle

**Returns**
- the device that has that handle, or a null pointer if `dev_handle` does not identify a device.

static inline const `device_handle_t* device_required_handles_get(const struct device *dev, size_t *count)`

Get the device handles for devicetree dependencies of this device.

This function returns a pointer to an array of device handles. The length of the array is stored in the `count` parameter.

The array contains a handle for each device that `dev` requires directly, as determined from the devicetree. This does not include transitive dependencies; you must recursively determine those.

**Parameters**
- `dev` – the device for which dependencies are desired.
- `count` – pointer to where this function should store the length of the returned array. No value is stored if the call returns a null pointer. The value may be set to zero if the device has no devicetree dependencies.

**Returns**
- a pointer to a sequence of `count` device handles, or a null pointer if `dev` does not have any dependency data.

static inline const `device_handle_t* device_injected_handles_get(const struct device *dev, size_t *count)`

Get the device handles for injected dependencies of this device.

This function returns a pointer to an array of device handles. The length of the array is stored in the `count` parameter.

The array contains a handle for each device that `dev` manually injected as a dependency, via providing extra arguments to Z_DEVICE_DEFINE. This does not include transitive dependencies; you must recursively determine those.

**Parameters**
- `dev` – the device for which injected dependencies are desired.
- `count` – pointer to where this function should store the length of the returned array. No value is stored if the call returns a null pointer. The value may be set to zero if the device has no devicetree dependencies.
Returns

a pointer to a sequence of *count device handles, or a null pointer if dev does not have any dependency data.

static inline const device_handle_t* device_supported_handles_get(const struct device *dev, size_t *count)

Get the set of handles that this device supports.

This function returns a pointer to an array of device handles. The length of the array is stored in the count parameter.

The array contains a handle for each device that dev “supports” — that is, devices that require dev directly — as determined from the devicetree. This does not include transitive dependencies; you must recursively determine those.

Parameters

- dev – the device for which supports are desired.
- count – pointer to where this function should store the length of the returned array. No value is stored if the call returns a null pointer. The value may be set to zero if nothing in the devicetree depends on dev.

Returns

a pointer to a sequence of *count device handles, or a null pointer if dev does not have any dependency data.

int device_required_foreach(const struct device *dev, device_visitor_callback_t visitor_cb, void *context)

Visit every device that dev directly requires.

Zephyr maintains information about which devices are directly required by another device; for example an I2C-based sensor driver will require an I2C controller for communication. Required devices can derive from statically-defined devicetree relationships or dependencies registered at runtime.

This API supports operating on the set of required devices. Example uses include making sure required devices are ready before the requiring device is used, and releasing them when the requiring device is no longer needed.

There is no guarantee on the order in which required devices are visited.

If the visitor_cb function returns a negative value iteration is halted, and the returned value from the visitor is returned from this function.

Note: This API is not available to unprivileged threads.

Parameters

- dev – a device of interest. The devices that this device depends on will be used as the set of devices to visit. This parameter must not be null.
- visitor_cb – the function that should be invoked on each device in the dependency set. This parameter must not be null.
- context – state that is passed through to the visitor function. This parameter may be null if visitor_cb tolerates a null context.

Returns

The number of devices that were visited if all visits succeed, or the negative value returned from the first visit that did not succeed.

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int device_supported_foreach(const struct device *dev, device_visitor_callback_t visitor_cb, void *context)

Visit every device that dev directly supports.

Zephyr maintains information about which devices are directly supported by another device; for example, an I2C controller will support an I2C-based sensor driver. Supported devices can derive from statically-defined devicetree relationships.

This API supports operating on the set of supported devices. Example uses include iterating over the devices connected to a regulator when it is powered on.

There is no guarantee on the order in which required devices are visited.

If the visitor_cb function returns a negative value iteration is halted, and the returned value from the visitor is returned from this function.

---

Note: This API is not available to unprivileged threads.

**Parameters**

- **dev** – a device of interest. The devices that this device supports will be used as the set of devices to visit. This parameter must not be null.
- **visitor_cb** – the function that should be invoked on each device in the support set. This parameter must not be null.
- **context** – state that is passed through to the visitor function. This parameter may be null if visitor_cb tolerates a null context.

**Returns**

The number of devices that were visited if all visits succeed, or the negative value returned from the first visit that did not succeed.

---

const struct device *device_get_binding(const char *name)

Get a device reference from its device::name field.

This function iterates through the devices on the system. If a device with the given name field is found, and that device initialized successfully at boot time, this function returns a pointer to the device.

If no device has the given name, this function returns NULL.

This function also returns NULL when a device is found, but it failed to initialize successfully at boot time. (To troubleshoot this case, set a breakpoint on your device driver's initialization function.)

**Parameters**

- **name** – device name to search for. A null pointer, or a pointer to an empty string, will cause NULL to be returned.

**Returns**

pointer to device structure with the given name; NULL if the device is not found or if the device with that name's initialization function failed.

---

bool device_is_ready(const struct device *dev)

Verify that a device is ready for use.

Indicates whether the provided device pointer is for a device known to be in a state where it can be used with its standard API.

This can be used with device pointers captured from DEVICE_DT_GET(), which does not include the readiness checks of device_get_binding(). At minimum this means that the device has been successfully initialized.
Parameters

• dev – pointer to the device in question.

Return values

• true – If the device is ready for use.
• false – If the device is not ready for use or if a NULL device pointer is passed as argument.

struct device_state

#include <device.h> Runtime device dynamic structure (in RAM) per driver instance.

Fields in this are expected to be default-initialized to zero. The kernel driver infrastructure and driver access functions are responsible for ensuring that any non-zero initialization is done before they are accessed.

Public Members

uint8_t init_res

Device initialization return code (positive errno value).

Device initialization functions return a negative errno code if they fail. In Zephyr, errno values do not exceed 255, so we can store the positive result value in a uint8_t type.

bool initialized

Indicates the device initialization function has been invoked.

struct device

#include <device.h> Runtime device structure (in ROM) per driver instance.

Public Members

const char *name

Name of the device instance.

const void *config

Address of device instance config information.

const void *api

Address of the API structure exposed by the device instance.

struct device_state *state

Address of the common device state.

void *data

Address of the device instance private data.
const device_handle_t *deps

Optional pointer to dependencies associated with the device.

This encodes a sequence of sets of device handles that have some relationship to this node. The individual sets are extracted with dedicated API, such as device_required_handles_get(). Only available if CONFIG_DEVICE_DEPS is enabled.

union device

Reference to the device PM resources (only available if CONFIG_PM_DEVICE is enabled).

## 3.3 User Mode

Zephyr offers the capability to run threads at a reduced privilege level which we call user mode. The current implementation is designed for devices with MPU hardware.

For details on creating threads that run in user mode, please see Lifecycle.

### 3.3.1 Overview

**Threat Model**

User mode threads are considered to be untrusted by Zephyr and are therefore isolated from other user mode threads and from the kernel. A flawed or malicious user mode thread cannot leak or modify the private data/resources of another thread or the kernel, and cannot interfere with or control another user mode thread or the kernel.

Example use-cases of Zephyr's user mode features:

- The kernel can protect against many unintentional programming errors which could otherwise silently or spectacularly corrupt the system.
- The kernel can sandbox complex data parsers such as interpreters, network protocols, and filesystems such that malicious third-party code or data cannot compromise the kernel or other threads.
- The kernel can support the notion of multiple logical “applications”, each with their own group of threads and private data structures, which are isolated from each other if one crashes or is otherwise compromised.

**Design Goals**  For threads running in a non-privileged CPU state (hereafter referred to as ‘user mode’) we aim to protect against the following:

- We prevent access to memory not specifically granted, or incorrect access to memory that has an incompatible policy, such as attempting to write to a read-only area.
  - Access to thread stack buffers will be controlled with a policy which partially depends on the underlying memory protection hardware.
    - A user thread will by default have read/write access to its own stack buffer.
    - A user thread will never by default have access to user thread stacks that are not members of the same memory domain.
    - A user thread will never by default have access to thread stacks owned by a supervisor thread, or thread stacks used to handle system call privilege elevations, interrupts, or CPU exceptions.
A user thread may have read/write access to the stacks of other user threads in the same memory domain, depending on hardware.

- On MPU systems, threads may only access their own stack buffer.
- On MMU systems, threads may access any user thread stack in the same memory domain. Portable code should not assume this.

- By default, program text and read-only data are accessible to all threads on read-only basis, kernel-wide. This policy may be adjusted.
- User threads by default are not granted default access to any memory except what is noted above.

- We prevent use of device drivers or kernel objects not specifically granted, with the permission granularity on a per object or per driver instance basis.
- We validate kernel or driver API calls with incorrect parameters that would otherwise cause a crash or corruption of data structures private to the kernel. This includes:
  - Using the wrong kernel object type.
  - Using parameters outside of proper bounds or with nonsensical values.
  - Passing memory buffers that the calling thread does not have sufficient access to read or write, depending on the semantics of the API.
  - Use of kernel objects that are not in a proper initialization state.
- We ensure the detection and safe handling of user mode stack overflows.
- We prevent invoking system calls to functions excluded by the kernel configuration.
- We prevent disabling of or tampering with kernel-defined and hardware-enforced memory protections.
- We prevent re-entry from user to supervisor mode except through the kernel-defined system calls and interrupt handlers.
- We prevent the introduction of new executable code by user mode threads, except to the extent to which this is supported by kernel system calls.

We are specifically not protecting against the following attacks:

- The kernel itself, and any threads that are executing in supervisor mode, are assumed to be trusted.
- The toolchain and any supplemental programs used by the build system are assumed to be trusted.
- The kernel build is assumed to be trusted. There is considerable build-time logic for creating the tables of valid kernel objects, defining system calls, and configuring interrupts. The .elf binary files that are worked with during this process are all assumed to be trusted code.
- We can’t protect against mistakes made in memory domain configuration done in kernel mode that exposes private kernel data structures to a user thread. RAM for kernel objects should always be configured as supervisor-only.
- It is possible to make top-level declarations of user mode threads and assign them permissions to kernel objects. In general, all C and header files that are part of the kernel build producing zephyr.elf are assumed to be trusted.
- We do not protect against denial of service attacks through thread CPU starvation. Zephyr has no thread priority aging and a user thread of a particular priority can starve all threads of lower priority, and also other threads of the same priority if time-slicing is not enabled.
- There are build-time defined limits on how many threads can be active simultaneously, after which creation of new user threads will fail.
• Stack overflows for threads running in supervisor mode may be caught, but the integrity of the system cannot be guaranteed.

High-level Policy Details

Broadly speaking, we accomplish these thread-level memory protection goals through the following mechanisms:

• Any user thread will only have access to a subset of memory: typically its stack, program text, read-only data, and any partitions configured in the Memory Protection Design it belongs to. Access to any other RAM must be done on the thread's behalf through system calls, or specifically granted by a supervisor thread using the memory domain APIs. Newly created threads inherit the memory domain configuration of the parent. Threads may communicate with each other by having shared membership of the same memory domains, or via kernel objects such as semaphores and pipes.

• User threads cannot directly access memory belonging to kernel objects. Although pointers to kernel objects are used to reference them, actual manipulation of kernel objects is done through system call interfaces. Device drivers and threads stacks are also considered kernel objects. This ensures that any data inside a kernel object that is private to the kernel cannot be tampered with.

• User threads by default have no permission to access any kernel object or driver other than their own thread object. Such access must be granted by another thread that is either in supervisor mode or has permission on both the receiving thread object and the kernel object being granted access to. The creation of new threads has an option to automatically inherit permissions of all kernel objects granted to the parent, except the parent thread itself.

• For performance and footprint reasons Zephyr normally does little or no parameter error checking for kernel object or device driver APIs. Access from user mode through system calls involves an extra layer of handler functions, which are expected to rigorously validate access permissions and type of the object, check the validity of other parameters through bounds checking or other means, and verify proper read/write access to any memory buffers involved.

• Thread stacks are defined in such a way that exceeding the specified stack space will generate a hardware fault. The way this is done specifically varies per architecture.

Constraints

All kernel objects, thread stacks, and device driver instances must be defined at build time if they are to be used from user mode. Dynamic use-cases for kernel objects will need to go through predefined pools of available objects.

There are some constraints if additional application binary data is loaded for execution after the kernel starts:

• Loaded object code will not be able to define any kernel objects that will be recognized by the kernel. This code will instead need to use APIs for requesting kernel objects from pools.

• Similarly, since the loaded object code will not be part of the kernel build process, this code will not be able to install interrupt handlers, instantiate device drivers, or define system calls, regardless of what mode it runs in.

• Loaded object code that does not come from a verified source should always be entered with the CPU already in user mode.
3.3.2 Memory Protection Design

Zephyr's memory protection design is geared towards microcontrollers with MPU (Memory Protection Unit) hardware. We do support some architectures, such as x86, which have a paged MMU (Memory Management Unit), but in that case the MMU is used like an MPU with an identity page table.

All of the discussion below will be using MPU terminology; systems with MMUs can be considered to have an MPU with an unlimited number of programmable regions.

There are a few different levels on how memory access is configured when Zephyr memory protection features are enabled, which we will describe here:

Boot Time Memory Configuration

This is the configuration of the MPU after the kernel has started up. It should contain the following:

- Any configuration of memory regions which need to have special caching or write-back policies for basic hardware and driver function. Note that most MPUs have the concept of a default memory access policy map, which can be enabled as a “background” mapping for any area of memory that doesn't have an MPU region configuring it. It is strongly recommended to use this to maximize the number of available MPU regions for the end user. On ARMv7-M/ARMv8-M this is called the System Address Map, other CPUs may have similar capabilities.

- A read-only, executable region or regions for program text and ro-data, that is accessible to user mode. This could be further sub-divided into a read-only region for ro-data, and a read-only, executable region for text, but this will require an additional MPU region. This is required so that threads running in user mode can read ro-data and fetch instructions.

- Depending on configuration, user-accessible read-write regions to support extra features like GCOV, HEP, etc.

Assuming there is a background map which allows supervisor mode to access any memory it needs, and regions are defined which grant user mode access to text/ro-data, this is sufficient for the boot time configuration.

Hardware Stack Overflow

CONFIG_HW_STACK_PROTECTION is an optional feature which detects stack buffer overflows when the system is running in supervisor mode. This catches issues when the entire stack buffer has overflowed, and not individual stack frames, use compiler-assisted CONFIG_STACK_CANARIES for that.

Like any crash in supervisor mode, no guarantees can be made about the overall health of the system after a supervisor mode stack overflow, and any instances of this should be treated as a serious error. However it's still very useful to know when these overflows happen, as without robust detection logic the system will either crash in mysterious ways or behave in an undefined manner when the stack buffer overflows.

Some systems implement this feature by creating at runtime a 'guard' MPU region which is set to be read-only and is at either the beginning or immediately preceding the supervisor mode stack buffer. If the stack overflows an exception will be generated.

This feature is optional and is not required to catch stack overflows in user mode; disabling this may free 1-2 MPU regions depending on the MPU design.

Other systems may have dedicated CPU support for catching stack overflows and no extra MPU regions will be required.
Thread Stack

Any thread running in user mode will need access to its own stack buffer. On context switch into a user mode thread, a dedicated MPU region will be programmed with the bounds of the stack buffer. A thread exceeding its stack buffer will start pushing data onto memory it doesn’t have access to and a memory access violation exception will be generated.

Thread Resource Pools

A small subset of kernel APIs, invoked as system calls, require heap memory allocations. This memory is used only by the kernel and is not accessible directly by user mode. In order to use these system calls, invoking threads must assign themselves to a resource pool, which is a `k_heap` object. Memory is drawn from a thread’s resource pool using `z_thread_malloc()` and freed with `k_free()`.

The APIs which use resource pools are as follows, with any alternatives noted for users who do not want heap allocations within their application:

- `k_stack_alloc_init()` sets up a `k_stack` with its storage buffer allocated out of a resource pool instead of a buffer provided by the user. An alternative is to declare `k_stacks` that are automatically initialized at boot with `K_STACK_DEFINE()`, or to initialize the `k_stack` in supervisor mode with `k_stack_init()`.
- `k_pipe_alloc_init()` sets up a `k_pipe` object with its storage buffer allocated out of a resource pool instead of a buffer provided by the user. An alternative is to declare `k_pipes` that are automatically initialized at boot with `K_PIPE_DEFINE()`, or to initialize the `k_pipe` in supervisor mode with `k_pipe_init()`.
- `k_msgq_alloc_init()` sets up a `k_msgq` object with its storage buffer allocated out of a resource pool instead of a buffer provided by the user. An alternative is to declare a `k_msgq` that is automatically initialized at boot with `K_MSGQ_DEFINE()`, or to initialize the `k_msgq` in supervisor mode with `k_msgq_init()`.
- `k_poll()` when invoked from user mode, needs to make a kernel-side copy of the provided events array while waiting for an event. This copy is freed when `k_poll()` returns for any reason.
- `k_queue_alloc_prepend()` and `k_queue_alloc_append()` allocate a container structure to place the data in, since the internal bookkeeping information that defines the queue cannot be placed in the memory provided by the user.
- `k_object_alloc()` allows for entire kernel objects to be dynamically allocated at runtime and a usable pointer to them returned to the caller.

The relevant API is `k_thread_heap_assign()` which assigns a `k_heap` to draw these allocations from for the target thread.

If the system heap is enabled, then the system heap may be used with `k_thread_system_pool_assign()`, but it is preferable for different logical applications running on the system to have their own pools.

Memory Domains

The kernel ensures that any user thread will have access to its own stack buffer, plus program text and read-only data. The memory domain APIs are the way to grant access to additional blocks of memory to a user thread.

Conceptually, a memory domain is a collection of some number of memory partitions. The maximum number of memory partitions in a domain is limited by the number of available MPU regions. This is why it is important to minimize the number of boot-time MPU regions.
Memory domains are not intended to control access to memory from supervisor mode. In some cases this may be unavoidable; for example some architectures do not allow for the definition of regions which are read-only to user mode but read-write to supervisor mode. A great deal of care must be taken when working with such regions to not unintentionally cause the kernel to crash when accessing such a region. Any attempt to use memory domain APIs to control supervisor mode access is at best undefined behavior; supervisor mode access policy is only intended to be controlled by boot-time memory regions.

Memory domain APIs are only available to supervisor mode. The only control user mode has over memory domains is that any user thread's child threads will automatically become members of the parent's domain.

All threads are members of a memory domain, including supervisor threads (even though this has no implications on their memory access). There is a default domain k_mem_domain_default which will be assigned to threads if they have not been specifically assigned to a domain, or inherited a memory domain membership from their parent thread. The main thread starts as a member of the default domain.

**Memory Partitions** Each memory partition consists of a memory address, a size, and access attributes. It is intended that memory partitions are used to control access to system memory. Defining memory partitions are subject to the following constraints:

- The partition must represent a memory region that can be programmed by the underlying memory management hardware, and needs to conform to any underlying hardware constraints. For example, many MPU-based systems require that partitions be sized to some power of two, and aligned to their own size. For MMU-based systems, the partition must be aligned to a page and the size some multiple of the page size.

- Partitions within the same memory domain may not overlap each other. There is no notion of precedence among partitions within a memory domain. Partitions within a memory domain are assumed to have a higher precedence than any boot-time memory regions, however whether a memory domain partition can overlap a boot-time memory region is architecture specific.

- The same partition may be specified in multiple memory domains. For example there may be a shared memory area that multiple domains grant access to.

- Care must be taken in determining what memory to expose in a partition. It is not appropriate to provide direct user mode access to any memory containing private kernel data.

- Memory domain partitions are intended to control access to system RAM. Configuration of memory partitions which do not correspond to RAM may not be supported by the architecture; this is true for MMU-based systems.

There are two ways to define memory partitions: either manually or automatically.

**Manual Memory Partitions** The following code declares a global array buf, and then declares a read-write partition for it which may be added to a domain:

```c
uint8_t __aligned(32) buf[32];
K_MEM_PARTITION_DEFINE(my_partition, buf, sizeof(buf), K_MEM_PARTITION_P_RW_U_RW);
```

This does not scale particularly well when we are trying to contain multiple objects spread out across several C files into a single partition.

**Automatic Memory Partitions** Automatic memory partitions are created by the build system. All globals which need to be placed inside a partition are tagged with their destination partition. The build system will then coalesce all of these into a single contiguous block of memory, zero
any BSS variables at boot, and define a memory partition of appropriate base address and size which contains all the tagged data.

Automatic memory partitions are only configured as read-write regions. They are defined with `K_APPMEM_PARTITION_DEFINE()`. Global variables are then routed to this partition using `K_APP_DMEM()` for initialized data and `K_APP_BMEM()` for BSS.

```c
#include <zephyr/app_memory/app_memdomain.h>

/* Declare a k_mem_partition "my_partition" that is read-write to user mode. Note that we do not specify a base address or size. */
K_APPMEM_PARTITION_DEFINE(my_partition);

/* The global variable var1 will be inside the bounds of my_partition and be initialized with 37 at boot. */
K_APP_DMEM(my_partition) int var1 = 37;

/* The global variable var2 will be inside the bounds of my_partition and be zeroed at boot size K_APP_BMEM() was used, indicating a BSS variable. */
K_APP_BMEM(my_partition) int var2;
```

The build system will ensure that the base address of `my_partition` will be properly aligned, and the total size of the region conforms to the memory management hardware requirements, adding padding if necessary.

If multiple partitions are being created, a variadic preprocessor macro can be used as provided in `app_macro_support.h`:

```c
FOR_EACH(K_APPMEM_PARTITION_DEFINE, part0, part1, part2);
```

**Automatic Partitions for Static Library Globals**

The build-time logic for setting up automatic memory partitions is in `scripts/build/gen_app_partitions.py`. If a static library is linked into Zephyr, it is possible to route all the globals in that library to a specific memory partition with the --library argument.

![Fig. 2: Automatic Memory Domain build flow](image)
For example, if the Newlib C library is enabled, the Newlib globals all need to be placed in `z_libc_partition`. The invocation of the script in the top-level `CMakeLists.txt` adds the following:

```python
gen_app_partitions.py ... --library libc.a z_libc_partition ..
```

For pre-compiled libraries there is no support for expressing this in the project-level configuration or build files; the toplevel `CMakeLists.txt` must be edited.

For Zephyr libraries created using `zephyr_library` or `zephyr_library_named` the `zephyr_library_app_memory` function can be used to specify the memory partition where all globals in the library should be placed.

Pre-defined Memory Partitions There are a few memory partitions which are pre-defined by the system:

- `z_malloc_partition` - This partition contains the system-wide pool of memory used by libc malloc(). Due to possible starvation issues, it is not recommended to draw heap memory from a global pool, instead it is better to define various `sys_heap` objects and assign them to specific memory domains.
- `z_libc_partition` - Contains globals required by the C library and runtime. Required when using either the Minimal C library or the Newlib C Library. Required when `CONFIG_STACK_CANARIES` is enabled.

Library-specific partitions are listed in `include/app_memory/partitions.h`. For example, to use the MBEDTLS library from user mode, the `k_mbedtls_partition` must be added to the domain.

Memory Domain Usage

Create a Memory Domain A memory domain is defined using a variable of type `k_mem_domain`. It must then be initialized by calling `k_mem_domain_init()`.

The following code defines and initializes an empty memory domain.

```c
struct k_mem_domain app0_domain;
k_mem_domain_init(&app0_domain, 0, NULL);
```

Add Memory Partitions into a Memory Domain There are two ways to add memory partitions into a memory domain.

This first code sample shows how to add memory partitions while creating a memory domain.

```c
/* the start address of the MPU region needs to align with its size */
uint8_t __aligned(32) app0_buf[32];
uint8_t __aligned(32) app1_buf[32];

K_MEM_PARTITION_DEFINE(app0_part0, app0_buf, sizeof(app0_buf),
                        K_MEM_PARTITION_P_RW_U_RW);

K_MEM_PARTITION_DEFINE(app0_part1, app1_buf, sizeof(app1_buf),
                        K_MEM_PARTITION_P_RW_U_RW);

struct k_mem_partition *app0_parts[] = {
    app0_part0,
    app0_part1
};
```

(continues on next page)
This second code sample shows how to add memory partitions into an initialized memory domain one by one.

```c
/* the start address of the MPU region needs to align with its size */
uint8_t __aligned(32) app0_buf[32];
uint8_t __aligned(32) app1_buf[32];

K_MEM_PARTITION_DEFINE(app0_part0, app0_buf, sizeof(app0_buf), K_MEM_PARTITION_P_RW_U_RW);  
K_MEM_PARTITION_DEFINE(app0_part1, app1_buf, sizeof(app1_buf), K_MEM_PARTITION_P_RW_U_RO);  

k_mem_domain_add_partition(&app0_domain, &app0_part0);

k_mem_domain_add_partition(&app0_domain, &app0_part1);
```

**Note:** The maximum number of memory partitions is limited by the maximum number of MPU regions or the maximum number of MMU tables.

---

**Memory Domain Assignment**  Any thread may join a memory domain, and any memory domain may have multiple threads assigned to it. Threads are assigned to memory domains with an API call:

```c
k_mem_domain_add_thread(&app0_domain, app_thread_id);
```

If the thread was already a member of some other domain (including the default domain), it will be removed from it in favor of the new one.

In addition, if a thread is a member of a memory domain, and it creates a child thread, that thread will belong to the domain as well.

**Remove a Memory Partition from a Memory Domain**  The following code shows how to remove a memory partition from a memory domain.

```c
k_mem_domain_remove_partition(&app0_domain, &app0_part1);
```

The `k_mem_domain_remove_partition()` API finds the memory partition that matches the given parameter and removes that partition from the memory domain.

**Available Partition Attributes**  When defining a partition, we need to set access permission attributes to the partition. Since the access control of memory partitions relies on either an MPU or MMU, the available partition attributes would be architecture dependent.

The complete list of available partition attributes for a specific architecture is found in the architecture-specific include file `include/zephyr/arch/<arch name>/arch.h`, (for example, `include/zephyr/arch/arm/arm/arch.h`). Some examples of partition attributes are:

```c
/* Denote partition is privileged read/write, unprivileged read/write */
K_MEM_PARTITION_P_RW_U_RW

/* Denote partition is privileged read/write, unprivileged read-only */
K_MEM_PARTITION_P_RW_U_RO
```

In almost all cases `K_MEM_PARTITION_P_RW_U_RW` is the right choice.
**Configuration Options**

Related configuration options:
- `CONFIG_MAX_DOMAIN_PARTITIONS`

**API Reference**

The following memory domain APIs are provided by `include/zephyr/kernel.h`:

*group mem_domain_apis*

**Defines**

`K_MEM_PARTITION_DEFINE`(name, start, size, attr)

Statically declare a memory partition.

**Functions**

`int k_mem_domain_init(struct k_mem_domain *domain, uint8_t num_parts, struct k_mem_partition *parts[])`

Initialize a memory domain.

Initialize a memory domain with given name and memory partitions.

See documentation for `k_mem_domain_add_partition()` for details about partition constraints.

Do not call `k_mem_domain_init()` on the same memory domain more than once, doing so is undefined behavior.

**Parameters**

- `domain` – The memory domain to be initialized.
- `num_parts` – The number of array items of "parts" parameter.
- `parts` – An array of pointers to the memory partitions. Can be NULL if `num_parts` is zero.

**Return values**

- `0` – if successful
- `-EINVAL` – if invalid parameters supplied
- `-ENOMEM` – if insufficient memory

`int k_mem_domain_add_partition(struct k_mem_domain *domain, struct k_mem_partition *part)`

Add a memory partition into a memory domain.

Add a memory partition into a memory domain. Partitions must conform to the following constraints:

- Partitions in the same memory domain may not overlap each other.
- Partitions must not be defined which expose private kernel data structures or kernel objects.
• The starting address alignment, and the partition size must conform to the con-
straints of the underlying memory management hardware, which varies per ar-
chitecture.

• Memory domain partitions are only intended to control access to memory from
user mode threads.

• If CONFIG_EXECUTE_XOR_WRITE is enabled, the partition must not allow both
writes and execution.

Violating these constraints may lead to CPU exceptions or undefined behavior.

Parameters

- domain – The memory domain to be added a memory partition.
- part – The memory partition to be added

Return values

- 0 – if successful
- EINVAL – if invalid parameters supplied
- ENOSPC – if no free partition slots available

int k_mem_domain_remove_partition(struct k_mem_domain *domain, struct
k_mem_partition *part)

Remove a memory partition from a memory domain.

Parameters

- domain – The memory domain to be removed a memory partition.
- part – The memory partition to be removed

Return values

- 0 – if successful
- EINVAL – if invalid parameters supplied
- ENOENT – if no matching partition found

int k_mem_domain_add_thread(struct k_mem_domain *domain, k_tid_t thread)

Add a thread into a memory domain.

Add a thread into a memory domain. It will be removed from whatever memory do-
main it previously belonged to.

Parameters

- domain – The memory domain that the thread is going to be added into.
- thread – ID of thread going to be added into the memory domain.

Returns

0 if successful, fails otherwise.

Variables

struct k_mem_domain k_mem_domain_default

Default memory domain.

All threads are a member of some memory domain, even if running in supervisor
mode. Threads belong to this default memory domain if they haven't been added to
or inherited membership from some other domain.
This memory domain has the z_libc_partition partition for the C library added to it if exists.

```
struct k_mem_partition
#include <mem_domain.h> Memory Partition.
A memory partition is a region of memory in the linear address space with a specific access policy.
The alignment of the starting address, and the alignment of the size value may have varying requirements based on the capabilities of the underlying memory management hardware; arbitrary values are unlikely to work.

Public Members

uintptr_t start  
start address of memory partition

size_t size      
size of memory partition

k_mem_partition_attr_t attr  
attribute of memory partition
```

```
struct k_mem_domain
#include <mem_domain.h> Memory Domain.
A memory domain is a collection of memory partitions, used to represent a user thread's access policy for the linear address space. A thread may be a member of only one memory domain, but any memory domain may have multiple threads that are members.
Supervisor threads may also be a member of a memory domain; this has no implications on their memory access but can be useful as any child threads inherit the memory domain membership of the parent.
A user thread belonging to a memory domain with no active partitions will have guaranteed access to its own stack buffer, program text, and read-only data.

Public Members

struct k_mem_partition partitions[CONFIG_MAX_DOMAIN_PARTITIONS]  
partitions in the domain

sys_dlist_t mem_domain_q  
Doubly linked list of member threads.

uint8_t num_partitions  
number of active partitions in the domain
3.3.3 Kernel Objects

A kernel object can be one of three classes of data:

- A core kernel object, such as a semaphore, thread, pipe, etc.
- A thread stack, which is an array of z_thread_stack_element and declared with
  \texttt{K_THREAD_STACK_DEFINE()}.
- A device driver instance (const struct device) that belongs to one of a defined set of subsystems.

The set of known kernel objects and driver subsystems is defined in include/kernel.h as \texttt{k_objects}.

Kernel objects are completely opaque to user threads. User threads work with addresses to kernel objects when making API calls, but may never dereference these addresses, doing so will cause a memory protection fault. All kernel objects must be placed in memory that is not accessible by user threads.

Since user threads may not directly manipulate kernel objects, all use of them must go through system calls. In order to perform a system call on a kernel object, checks are performed by system call handler functions that the kernel object address is valid and that the calling thread has sufficient permissions to work with it.

Permission on an object also has the semantics of a reference to an object. This is significant for certain object APIs which do temporary allocations, or objects which themselves have been allocated from a runtime memory pool.

If an object loses all references, two events may happen:

- If the object has an associated cleanup function, the cleanup function may be called to release any runtime-allocated buffers the object was using.
- If the object itself was dynamically allocated, the memory for the object will be freed.

Object Placement

Kernel objects that are only used by supervisor threads have no restrictions and can be located anywhere in the binary, or even declared on stacks. However, to prevent accidental or intentional corruption by user threads, they must not be located in any memory that user threads have direct access to.

In order for a static kernel object to be usable by a user thread via system call APIs, several conditions must be met on how the kernel object is declared:

- The object must be declared as a top-level global at build time, such that it appears in the ELF symbol table. It is permitted to declare kernel objects with static scope. The post-build script \texttt{scripts/build/gen_kobject_list.py} scans the generated ELF file to find kernel objects and places their memory addresses in a special table of kernel object metadata. Kernel objects may be members of arrays or embedded within other data structures.
- Kernel objects must be located in memory reserved for the kernel. They must not be located in any memory partitions that are user-accessible.
- Any memory reserved for a kernel object must be used exclusively for that object. Kernel objects may not be members of a union data type.

Kernel objects that are found but do not meet the above conditions will not be included in the generated table that is used to validate kernel object pointers passed in from user mode.

The debug output of the \texttt{scripts/build/gen_kobject_list.py} script may be useful when debugging why some object was unexpectedly not being tracked. This information will be printed if the script is run with the \texttt{--verbose} flag, or if the build system is invoked with verbose output.
Dynamic Objects

Kernel objects may also be allocated at runtime if CONFIG_DYNAMIC_OBJECTS is enabled. In this case, the \texttt{k\_object\_alloc()} API may be used to instantiate an object from the calling thread's resource pool. Such allocations may be freed in two ways:

- Supervisor threads may call \texttt{k\_object\_free()} to force a dynamic object to be released.
- If an object's references drop to zero (which happens when no threads have permissions on it) the object will be automatically freed. User threads may drop their own permission on an object with \texttt{k\_object\_release()}, and their permissions are automatically cleared when a thread terminates. Supervisor threads may additionally revoke references for another thread using \texttt{k\_object\_access\_revoke()}.

Because permissions are also used for reference counting, it is important for supervisor threads to acquire permissions on objects they are using even though the access control aspects of the permission system are not enforced.

Implementation Details

The \texttt{scripts/build/gen_kobject_list.py} script is a post-build step which finds all the valid kernel object instances in the binary. It accomplishes this by parsing the DWARF debug information present in the generated ELF file for the kernel.

Any instances of structs or arrays corresponding to kernel objects that meet the object placement criteria will have their memory addresses placed in a special perfect hash table of kernel objects generated by the ‘gperf’ tool. When a system call is made and the kernel is presented with a memory address of what may or may not be a valid kernel object, the address can be validated with a constant-time lookup in this table.

Drivers are a special case. All drivers are instances of \texttt{device}, but it is important to know what subsystem a driver belongs to so that incorrect operations, such as calling a UART API on a sensor driver object, can be prevented. When a device struct is found, its API pointer is examined to determine what subsystem the driver belongs to.

The table itself maps kernel object memory addresses to instances of \texttt{z\_object}, which has all the metadata for that object. This includes:

- A bitfield indicating permissions on that object. All threads have a numerical ID assigned to them at build time, used to index the permission bitfield for an object to see if that thread has permission on it. The size of this bitfield is controlled by the \texttt{CONFIG\_MAX\_THREAD\_BYTES} option and the build system will generate an error if this value is too low.
- A type field indicating what kind of object this is, which is some instance of \texttt{k\_objects}.
- A set of flags for that object. This is currently used to track initialization state and whether an object is public or not.
- An extra data field. The semantics of this field vary by object type, see the definition of \texttt{z\_object\_data}.

Dynamic objects allocated at runtime are tracked in a runtime red/black tree which is used in parallel to the gperf table when validating object pointers.

Supervisor Thread Access Permission

Supervisor threads can access any kernel object. However, permissions for supervisor threads are still tracked for two reasons:

- If a supervisor thread calls \texttt{k\_thread\_user\_mode\_enter()}, the thread will then run in user mode with any permissions it had been granted (in many cases, by itself) when it was a supervisor thread.
• If a supervisor thread creates a user thread with the \texttt{K\_INHERIT\_PERMS} option, the child thread will be granted the same permissions as the parent thread, except the parent thread object.

\textbf{User Thread Access Permission}

By default, when a user thread is created, it will only have access permissions on its own thread object. Other kernel objects by default are not usable. Access to them needs to be explicitly or implicitly granted. There are several ways to do this.

• If a thread is created with the \texttt{K\_INHERIT\_PERMS}, that thread will inherit all the permissions of the parent thread, except the parent thread object.

• A thread that has permission on an object, or is running in supervisor mode, may grant permission on that object to another thread via the \texttt{k\_object\_access\_grant()} API. The convenience pseudo-function \texttt{k\_thread\_access\_grant()} may also be used, which accepts an arbitrary number of pointers to kernel objects and calls \texttt{k\_object\_access\_grant()} on each of them. The thread being granted permission, or the object whose access is being granted, do not need to be in an initialized state. If the caller is from user mode, the caller must have permissions on both the kernel object and the target thread object.

• Supervisor threads may declare a particular kernel object to be a public object, usable by all current and future threads with the \texttt{k\_object\_access\_all\_grant()} API. You must assume that any untrusted or exploited code will then be able to access the object. Use this API with caution!

• If a thread was declared statically with \texttt{K\_THREAD\_DEFINE()}, then the \texttt{K\_THREAD\_ACCESS\_GRANT()} may be used to grant that thread access to a set of kernel objects at boot time.

Once a thread has been granted access to an object, such access may be removed with the \texttt{k\_object\_access\_revoke()} API. This API is not available to user threads, however user threads may use \texttt{k\_object\_release()} to relinquish their own permissions on an object.

API calls from supervisor mode to set permissions on kernel objects that are not being tracked by the kernel will be no-ops. Doing the same from user mode will result in a fatal error for the calling thread.

Objects allocated with \texttt{k\_object\_alloc()} implicitly grant permission on the allocated object to the calling thread.

\textbf{Initialization State}

Most operations on kernel objects will fail if the object is considered to be in an uninitialized state. The appropriate init function for the object must be performed first.

Some objects will be implicitly initialized at boot:

• Kernel objects that were declared with static initialization macros (such as \texttt{K\_SEM\_DEFINE} for semaphores) will be in an initialized state at build time.

• Device driver objects are considered initialized after their init function is run by the kernel early in the boot process.

If a kernel object is initialized with a private static initializer, the object must have \texttt{k\_object\_init()} called on it at some point by a supervisor thread, otherwise the kernel will consider the object uninitialized if accessed by a user thread. This is very uncommon, typically only for kernel objects that are embedded within some larger struct and initialized statically.
Creating New Kernel Object Types

When implementing new kernel features or driver subsystems, it may be necessary to define some new kernel object types. There are different steps needed for creating core kernel objects and new driver subsystems.

Creating New Core Kernel Objects

- In `scripts/build/gen_kobject_list.py`, add the name of the struct to the kobjects list. Instances of the new struct should now be tracked.

Creating New Driver Subsystem Kernel Objects

All driver instances are `device`. They are differentiated by what API struct they are set to.

- In `scripts/build/gen_kobject_list.py`, add the name of the API struct for the new subsystem to the subsystems list.

Driver instances of the new subsystem should now be tracked.

Configuration Options

Related configuration options:

- `CONFIG_USERSPACE`
- `CONFIG_MAX_THREAD_BYTES`

API Reference

`group usermode_apis`

**Defines**

`K_THREAD_ACCESS_GRANT(name_, ...)`

Grant a static thread access to a list of kernel objects.

For threads declared with `K_THREAD_DEFINE()`, grant the thread access to a set of kernel objects. These objects do not need to be in an initialized state. The permissions will be granted when the threads are initialized in the early boot sequence.
All arguments beyond the first must be pointers to kernel objects.

**Parameters**

- **name_** – Name of the thread, as passed to `K_THREAD_DEFINE()`

**K_OBJ_FLAG_INITIALIZED**
Object initialized.

**K_OBJ_FLAG_PUBLIC**
Object is Public.

**K_OBJ_FLAG_ALLOC**
Object allocated.

**K_OBJ_FLAG_DRIVER**
Driver Object.

**Functions**

```c
void k_object_access_grant(const void *object, struct k_thread *thread)
Grant a thread access to a kernel object.

The thread will be granted access to the object if the caller is from supervisor mode, or the caller is from user mode AND has permissions on both the object and the thread whose access is being granted.

**Parameters**
- **object** – Address of kernel object
- **thread** – Thread to grant access to the object
```

```c
void k_object_access_revoke(const void *object, struct k_thread *thread)
Revoke a thread's access to a kernel object.

The thread will lose access to the object if the caller is from supervisor mode, or the caller is from user mode AND has permissions on both the object and the thread whose access is being revoked.

**Parameters**
- **object** – Address of kernel object
- **thread** – Thread to remove access to the object
```

```c
void k_object_release(const void *object)
Release an object.

Allows user threads to drop their own permission on an object. Their permissions are automatically cleared when a thread terminates.

**Parameters**
- **object** – The object to be released
```

```c
void k_object_access_all_grant(const void *object)
Grant all present and future threads access to an object.

If the caller is from supervisor mode, or the caller is from user mode and have sufficient permissions on the object, then that object will have permissions granted to it for all current and future threads running in the system, effectively becoming a public kernel object.
```
Use of this API should be avoided on systems that are running untrusted code as it is possible for such code to derive the addresses of kernel objects and perform unwanted operations on them.

It is not possible to revoke permissions on public objects; once public, any thread may use it.

### Parameters

- **object** – Address of kernel object

```c
bool k_object_is_valid(const void *obj, enum k_objects otype)
```

Check if a kernel object is of certain type and is valid.

This checks if the kernel object exists, of certain type, and has been initialized.

#### Parameters

- **obj** – Address of the kernel object
- **otype** – Object type (use K_OBJ_ANY for ignoring type checking)

#### Returns

- True if kernel object (obj) exists, of certain type, and has been initialized.
- False otherwise.

```c
void *k_object_alloc(enum k_objects otype)
```

Allocate a kernel object of a designated type.

This will instantiate at runtime a kernel object of the specified type, returning a pointer to it. The object will be returned in an uninitialized state, with the calling thread being granted permission on it. The memory for the object will be allocated out of the calling thread's resource pool.

**Note:** This function is available only if CONFIG_DYNAMIC_OBJECTS is selected.

**Note:** Thread stack object has to use `k_object_alloc_size()` since stacks may have different sizes.

#### Parameters

- **otype** – Requested kernel object type

#### Returns

- A pointer to the allocated kernel object, or NULL if memory wasn't available

```c
void *k_object_alloc_size(enum k_objects otype, size_t size)
```

Allocate a kernel object of a designated type and a given size.

This will instantiate at runtime a kernel object of the specified type, returning a pointer to it. The object will be returned in an uninitialized state, with the calling thread being granted permission on it. The memory for the object will be allocated out of the calling thread's resource pool.

This function is specially helpful for thread stack objects because their sizes can vary. Other objects should probably look `k_object_alloc()`.

**Note:** This function is available only if CONFIG_DYNAMIC_OBJECTS is selected.
Parameters

- otype – Requested kernel object type
- size – Requested kernel object size

Returns
A pointer to the allocated kernel object, or NULL if memory wasn’t available

```c
void k_object_free(void *obj)
```

Free a kernel object previously allocated with `k_object_alloc()`.

This will return memory for a kernel object back to resource pool it was allocated from. Care must be exercised that the object will not be used during or after when this call is made.

**Note:** This function is available only if `CONFIG_DYNAMIC_OBJECTS` is selected.

Parameters

- obj – Pointer to the kernel object memory address.

### 3.3.4 System Calls

User threads run with a reduced set of privileges than supervisor threads: certain CPU instructions may not be used, and they have access to only a limited part of the memory map. System calls (may) allow user threads to perform operations not directly available to them.

When defining system calls, it is very important to ensure that access to the API’s private data is done exclusively through system call interfaces. Private kernel data should never be made available to user mode threads directly. For example, the `k_queue` APIs were intentionally not made available as they store bookkeeping information about the queue directly in the queue buffers which are visible from user mode.

APIs that allow the user to register callback functions that run in supervisor mode should never be exposed as system calls. Reserve these for supervisor-mode access only.

This section describes how to declare new system calls and discusses a few implementation details relevant to them.

**Components**

All system calls have the following components:

- A **C prototype** prefixed with `__syscall` for the API. It will be declared in some header under `include/` or in another `SYSCALL_INCLUDE_DIRS` directory. This prototype is never implemented manually, instead it gets created by the `scripts/build/gen_syscalls.py` script. What gets generated is an inline function which either calls the implementation function directly (if called from supervisor mode) or goes through privilege elevation and validation steps (if called from user mode).

- An **implementation function**, which is the real implementation of the system call. The implementation function may assume that all parameters passed in have been validated if it was invoked from user mode.

- A **verification function**, which wraps the implementation function and does validation of all the arguments passed in.
• An **unmarshalling function**, which is an automatically generated handler that must be included by user source code.

### C Prototype

The C prototype represents how the API is invoked from either user or supervisor mode. For example, to initialize a semaphore:

```c
__syscall void k_sem_init(struct k_sem *sem, unsigned int initial_count, unsigned int limit);
```

The `__syscall` attribute is very special. To the C compiler, it simply expands to ‘static inline’. However, to the post-build `scripts/build/parse_syscalls.py` script, it indicates that this API is a system call. The `scripts/build/parse_syscalls.py` script does some parsing of the function prototype, to determine the data types of its return value and arguments, and has some limitations:

- Array arguments must be passed in as pointers, not arrays. For example, `int foo[]` or `int foo[12]` is not allowed, but should instead be expressed as `int *foo`.
- Function pointers horribly confuse the limited parser. The workaround is to typedef them first, and then express in the argument list in terms of that typedef.
- `__syscall` must be the first thing in the prototype.

The preprocessor is intentionally not used when determining the set of system calls to generate. However, any generated system calls that don’t actually have a verification function defined (because the related feature is not enabled in the kernel configuration) will instead point to a special verification for unimplemented system calls. Data type definitions for APIs should not have conditional visibility to the compiler.

Any header file that declares system calls must include a special generated header at the very bottom of the header file. This header follows the naming convention `syscalls/<name of header file>`. For example, at the bottom of `include/sensor.h`:

```c
#include <syscalls/sensor.h>
```

C prototype functions must be declared in one of the directories listed in the CMake variable `SYSCALL_INCLUDE_DIRS`. This list always contains `APPLICATION_SOURCE_DIR` when `CONFIG_APPLICATION_DEFINED_SYSCALL` is set, or `${ZEPHYR_BASE}/subsys/testsuite/ztest/include` when `CONFIG_ZTEST` is set. Additional paths can be added to the list through the CMake command line or in CMake code that is run before `find_package(Zephyr ...) is run. `${ZEPHYR_BASE}/include` is always scanned for potential syscall prototypes.

Note that not all syscalls will be included in the final binaries. CMake functions `zephyr_syscall_header` and `zephyr_syscall_header_ifdef` are used to specify which header files contain syscall prototypes where those syscalls must be present in the final binaries. Note that header files inside directories listed in CMake variable `SYSCALL_INCLUDE_DIRS` will always have their syscalls present in final binaries. To force all syscalls to be included in the final binaries, turn on `CONFIG_EMIT_ALL_SYSCALLS`.

### Invocation Context

Source code that uses system call APIs can be made more efficient if it is known that all the code inside a particular C file runs exclusively in user mode, or exclusively in supervisor mode. The system will look for the definition of macros `__ZEPHYR_SUPERVISOR__` or `__ZEPHYR_USER__`, typically these will be added to the compiler flags in the build system for the related files.

- If `CONFIG_USERSPACE` is not enabled, all APIs just directly call the implementation function.
- Otherwise, the default case is to make a runtime check to see if the processor is currently running in user mode, and either make the system call or directly call the implementation function as appropriate.

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• If \texttt{\_\_ZEPHYR\_SUPERVISOR\_} is defined, then it is assumed that all the code runs in supervisor mode and all APIs just directly call the implementation function. If the code was actually running in user mode, there will be a CPU exception as soon as it tries to do something it isn’t allowed to do.

• If \texttt{\_\_ZEPHYR\_USER\_} is defined, then it is assumed that all the code runs in user mode and system calls are unconditionally made.

\textbf{Implementation Details}  
Declaring an API with \texttt{\_syscall} causes some code to be generated in C and header files by the \texttt{scripts/build/gen_syscalls.py} script, all of which can be found in the project out directory under include/generated/:

• The system call is added to the enumerated type of system call IDs, which is expressed in include/generated/syscall_list.h. It is the name of the API in uppercase, prefixed with \texttt{K\_SYSCALL\_}.

• An entry for the system call is created in the dispatch table \texttt{\_\_k\_syscall\_table}, expressed in include/generated/syscall_dispatch.c
  
  – This table only contains syscalls where their corresponding prototypes are declared in header files when \texttt{CONFIG\_EMIT\_ALL\_SYSCALLS} is enabled:
    
    * Indicated by CMake functions \texttt{zephyr\_syscall\_header} and \texttt{zephyr\_syscall\_header\_ifdef}, or

  * Under directories specified in CMake variable \texttt{SYSCALL\_INCLUDE\_DIRS}.

• A weak verification function is declared, which is just an alias of the ‘unimplemented system call’ verifier. This is necessary since the real verification function may or may not be built depending on the kernel configuration. For example, if a user thread makes a sensor subsystem API call, but the sensor subsystem is not enabled, the weak verifier will be invoked instead.

• An unmarshalling function is defined in include/generated/<name>_mrsh.c

The body of the API is created in the generated system header. Using the example of \texttt{k\_sem\_init()}, this API is declared in include/kernel.h. At the bottom of include/kernel.h is:

```c
#include <syscalls/kernel.h>
Inside this header is the body of \texttt{k\_sem\_init()}:

```
static inline void k_sem_init(struct k_sem * sem, unsigned int initial_count, unsigned int
  \_\_limit)
{
  #ifdef CONFIG\_USERSPACE
    if (zsyscall\_trap()) {
      arch\_syscall\_invoke3((uintptr\_t *)sem, *(uintptr\_t *)\&initial\_count,
       *(uintptr\_t *)\&limit, K\_SYSCALL\_K\_SEM\_INIT);
      return;
    }
  compiler\_barrier();
  #endif
  z\_impl\_k\_sem\_init(sem, initial\_count, limit);
}
```

This generates an inline function that takes three arguments with void return value. Depending on context it will either directly call the implementation function or go through a system call elevation. A prototype for the implementation function is also automatically generated.

The final layer is the invocation of the system call itself. All architectures implementing system calls must implement the seven inline functions \texttt{\_arch\_syscall\_invoke0()} through \texttt{\_arch\_syscall\_invoke6()}. These functions marshal arguments into designated CPU registers.
and perform the necessary privilege elevation. Parameters of API inline function, before being passed as arguments to system call, are C casted to `uintptr_t` which matches size of register. Exception to above is passing 64-bit parameters on 32-bit systems, in which case 64-bit parameters are split into lower and higher part and passed as two consecutive arguments. There is always a `uintptr_t` type return value, which may be neglected if not needed.

**Fig. 3: System Call execution flow**

Some system calls may have more than six arguments, but number of arguments passed via registers is limited to six for all architectures. Additional arguments will need to be passed in an array in the source memory space, which needs to be treated as untrusted memory in the verification function. This code (packing, unpacking and validation) is generated automatically as needed in the stub above and in the unmarshalling function.

System calls return `uintptr_t` type value that is C casted, by wrapper, to a return type of API prototype declaration. This means that 64-bit value may not be directly returned, from a system call to its wrapper, on 32-bit systems. To solve the problem the automatically generated wrapper function defines 64-bit intermediate variable, which is considered untrusted buffer, on its stack and passes pointer to that variable to the system call, as a final argument. Upon return from the system call the value written to that buffer will be returned by the wrapper function. The problem does not exist on 64-bit systems which are able to return 64-bit values directly.

**Implementation Function**

The implementation function is what actually does the work for the API. Zephyr normally does little to no error checking of arguments, or does this kind of checking with assertions. When writing the implementation function, validation of any parameters is optional and should be done with assertions.

All implementation functions must follow the naming convention, which is the name of the API prefixed with `z_impl_`. Implementation functions may be declared in the same header as the API as a static inline function or declared in some C file. There is no prototype needed for implementation functions, these are automatically generated.

**Verification Function**

The verification function runs on the kernel side when a user thread makes a system call. When the user thread makes a software interrupt to elevate to supervisor mode, the common system call entry point uses the system call ID provided by the user to look up the appropriate unmarshalling function for that system call and jump into it. This in turn calls the verification function.
Verification and unmarshalling functions only run when system call APIs are invoked from user mode. If an API is invoked from supervisor mode, the implementation is simply called and there is no software trap.

The purpose of the verification function is to validate all the arguments passed in. This includes:

- Any kernel object pointers provided. For example, the semaphore APIs must ensure that the semaphore object passed in is a valid semaphore and that the calling thread has permission on it.
- Any memory buffers passed in from user mode. Checks must be made that the calling thread has read or write permissions on the provided buffer.
- Any other arguments that have a limited range of valid values.

Verification functions involve a great deal of boilerplate code which has been made simpler by some macros in `include/zephyr/internal/syscall_handler.h`. Verification functions should be declared using these macros.

**Argument Validation** Several macros exist to validate arguments:

- `K_SYSCALL_OBJ()` Checks a memory address to assert that it is a valid kernel object of the expected type, that the calling thread has permissions on it, and that the object is initialized.
- `K_SYSCALL_OBJ_INIT()` is the same as `K_SYSCALL_OBJ()`, except that the provided object may be uninitialized. This is useful for verifiers of object init functions.
- `K_SYSCALL_OBJ_NEVER_INIT()` is the same as `K_SYSCALL_OBJ()`, except that the provided object must be uninitialized. This is not used very often, currently only for `k_thread_create()`.
- `K_SYSCALL_MEMORY_READ()` validates a memory buffer of a particular size. The calling thread must have read permissions on the entire buffer.
- `K_SYSCALL_MEMORY_WRITE()` is the same as `K_SYSCALL_MEMORY_READ()` but the calling thread must additionally have write permissions.
- `K_SYSCALL_MEMORY_ARRAY_READ()` validates an array whose total size is expressed as separate arguments for the number of elements and the element size. This macro correctly accounts for multiplication overflow when computing the total size. The calling thread must have read permissions on the total size.
- `K_SYSCALL_MEMORY_ARRAY_WRITE()` is the same as `K_SYSCALL_MEMORY_ARRAY_READ()` but the calling thread must additionally have write permissions.
- `K_SYSCALL_VERIFY_MSG()` does a runtime check of some boolean expression which must evaluate to true otherwise the check will fail. A variant `K_SYSCALL_VERIFY` exists which does not take a message parameter, instead printing the expression tested if it fails. The latter should only be used for the most obvious of tests.
- `K_SYSCALL_DRIVER_OP()` checks at runtime if a driver instance is capable of performing a particular operation. While this macro can be used by itself, it’s mostly a building block for macros that are automatically generated for every driver subsystem. For instance, to validate the GPIO driver, one could use the `K_SYSCALL_DRIVER_GPIO()` macro.
- `K_SYSCALL_SPECIFIC_DRIVER()` is a runtime check to verify that a provided pointer is a valid instance of a specific device driver, that the calling thread has permissions on it, and that the driver has been initialized. It does this by checking the API structure pointer that is stored within the driver instance and ensuring that it matches the provided value, which should be the address of the specific driver’s API structure.

If any check fails, the macros will return a nonzero value. The macro `K_OOPS()` can be used to induce a kernel oops which will kill the calling thread. This is done instead of returning some error condition to keep the APIs the same when calling from supervisor mode.
Verifier Definition  All system calls are dispatched to a verifier function with a prefixed `z_vrfy_` name based on the system call. They have exactly the same return type and argument types as the wrapped system call. Their job is to execute the system call (generally by calling the implementation function) after having validated all arguments.

The verifier is itself invoked by an automatically generated unmarshaller function which takes care of unpacking the register arguments from the architecture layer and casting them to the correct type. This is defined in a header file that must be included from user code, generally somewhere after the definition of the verifier in a translation unit (so that it can be inlined).

For example:

```c
static int z_vrfy_k_sem_take(struct k_sem *sem, int32_t timeout) {
    K_OOPS(K_SYSCALL_OBJ(sem, K_OBJ_SEM));
    return z_impl_k_sem_take(sem, timeout);
}
#include <syscalls/k_sem_take_mrsh.c>
```

Verification Memory Access Policies  Parameters passed to system calls by reference require special handling, because the value of these parameters can be changed at any time by any user thread that has access to the memory that parameter points to. If the kernel makes any logical decisions based on the contents of this memory, this can open up the kernel to attacks even if checking is done. This is a class of exploits known as TOCTOU (Time Of Check to Time Of Use).

The proper procedure to mitigate these attacks is to make a copies in the verification function, and only perform parameter checks on the copies, which user threads will never have access to. The implementation functions get passed the copy and not the original data sent by the user. The `k_usermode_to_copy()` and `k_usermode_from_copy()` APIs exist for this purpose.

There is one exception in place, with respect to large data buffers which are only used to provide a memory area that is either only written to, or whose contents are never used for any validation or control flow. Further discussion of this later in this section.

As a first example, consider a parameter which is used as an output parameter for some integral value:

```c
int z_vrfy_some_syscall(int *out_param) {
    int local_out_param;
    int ret;
    ret = z_impl_some_syscall(&local_out_param);
    K_OOPS(k_usermode_to_copy(out_param, &local_out_param, sizeof(*out_param)));
    return ret;
}
```

Here we have allocated `local_out_param` on the stack, passed its address to the implementation function, and then used `k_usermode_to_copy()` to fill in the memory passed in by the caller.

It might be tempting to do something more concise:

```c
int z_vrfy_some_syscall(int *out_param) {
    K_OOPS(K_SYSCALL_MEMORY_WRITE(out_param, sizeof(*out_param)));
    return z_impl_some_syscall(out_param);
}
```

However, this is unsafe if the implementation ever does any reads to this memory as part of its logic. For example, it could be used to store some counter value, and this could be meddled with by user threads that have access to its memory. It is by far safest for small integral values to do the copying as shown in the first example.
Some parameters may be input/output. For instance, it’s not uncommon to see APIs which pass in a pointer to some `size_t` which is a maximum allowable size, which is then updated by the implementation to reflect the actual number of bytes processed. This too should use a stack copy:

```c
int z_vrfy_in_out_syscall(size_t *size_ptr)
{
    size_t size;
    int ret;

    K_OOPS(k_usermode_from_copy(&size, size_ptr, sizeof(size));
    ret = z_impl_in_out_syscall(&size);
    K_OOPS(k_usermode_to_copy(size_ptr, &size, sizeof(size));
    return ret;
}
```

Many system calls pass in structures or even linked data structures. All should be copied. Typically this is done by allocating copies on the stack:

```c
struct bar {
    ...
};

struct foo {
    ...
    struct bar *bar_left;
    struct bar *bar_right;
};

int z_vrfy_must_alloc(struct foo *foo)
{
    int ret;
    struct foo foo_copy;
    struct bar bar_right_copy;
    struct bar bar_left_copy;

    K_OOPS(k_usermode_from_copy(&foo_copy, foo, sizeof(*foo));
    K_OOPS(k_usermode_from_copy(&bar_right_copy, foo_copy.bar_right,
                                  sizeof(struct bar));
    foo_copy.bar_right = &bar_right_copy;
    K_OOPS(k_usermode_from_copy(&bar_left_copy, foo_copy.bar_left,
                                sizeof(struct bar));
    foo_copy.bar_left = &bar_left_copy;

    return z_impl_must_alloc(&foo_copy);
}
```

In some cases the amount of data isn’t known at compile time or may be too large to allocate on the stack. In this scenario, it may be necessary to draw memory from the caller’s resource pool via `z_thread_malloc()`. This should always be considered last resort. Functional safety programming guidelines heavily discourage usage of heap and the fact that a resource pool is used must be clearly documented. Any issues with allocation must be reported, to a caller, with returning the `-ENOMEM`. The `K_OOPS()` should never be used to verify if resource allocation has been successful.

```c
struct bar {
    ...
};

struct foo {
    size_t count;
    struct bar *bar_list; /* array of struct bar of size count */
};
```

(continues on next page)
int z_vrfy_must_alloc(struct foo *foo)
{
    int ret;
    struct foo foo_copy;
    struct bar *bar_list_copy;
    size_t bar_list_bytes;

    /* Safely copy foo into foo_copy */
    K_OOPS(k_usermode_from_copy(&foo_copy, foo, sizeof(foo)));

    /* Bounds check the count member, in the copy we made */
    if (foo_copy.count > 32) {
        return -EINVAL;
    }

    /* Allocate RAM for the bar_list, replace the pointer in
     * foo_copy */
    bar_list_bytes = foo_copy.count * sizeof(struct_bar);
    bar_list_copy = z_thread_malloc(bar_list_bytes);
    if (bar_list_copy == NULL) {
        return -ENOMEM;
    }
    K_OOPS(k_usermode_from_copy(bar_list_copy, foo_copy.bar_list, bar_list_bytes));
    foo_copy.bar_list = bar_list_copy;
    ret = z_impl_must_alloc(&foo_copy);

    /* All done with the memory, free it and return */
    k_free(foo_copy.bar_list_copy);
    return ret;
}

Finally, we must consider large data buffers. These represent areas of user memory which either have data copied out of, or copied into. It is permitted to pass these pointers to the implementation function directly. The caller's access to the buffer still must be validated with K_SYSCALL_MEMORY APIs. The following constraints need to be met:

- If the buffer is used by the implementation function to write data, such as data captured from some MMIO region, the implementation function must only write this data, and never read it.
- If the buffer is used by the implementation function to read data, such as a block of memory to write to some hardware destination, this data must be read without any processing. No conditional logic can be implemented due to the data buffer's contents. If such logic is required a copy must be made.
- The buffer must only be used synchronously with the call. The implementation must not ever save the buffer address and use it asynchronously, such as when an interrupt fires.

int z_vrfy_get_data_from_kernel(void *buf, size_t size)
{
    K_OOPS(K_SYSCALL_MEMORY_WRITE(buf, size));
    return z_impl_get_data_from_kernel(buf, size);
}

Verification Return Value Policies When verifying system calls, it's important to note which kinds of verification failures should propagate a return value to the caller, and which should simply invoke K_OOPS() which kills the calling thread. The current conventions are as follows:

3.3. User Mode 505
1. For system calls that are defined but not compiled, invocations of these missing system calls are routed to `handler_no_syscall()` which invokes `K_OOPS()`.

2. Any invalid access to memory found by the set of `K_SYSCALL_MEMORY` APIs, `k_usermode_from_copy()`, `k_usermode_to_copy()` should trigger a `K_OOPS`. This happens when the caller doesn’t have appropriate permissions on the memory buffer or some size calculation overflowed.

3. Most system calls take kernel object pointers as an argument, checked either with one of the `K_SYSCALL_OBJ` functions, `K_SYSCALL_DRIVER_nnnnn`, or manually using `k_object_validate()`. These can fail for a variety of reasons: missing driver API, bad kernel object pointer, wrong kernel object type, or improper initialization state. These issues should always invoke `K_OOPS()`.

4. Any error resulting from a failed memory heap allocation, often from invoking `z_thread_malloc()`, should propagate `-ENOMEM` to the caller.

5. General parameter checks should be done in the implementation function, in most cases using `CHECKIF()`.
   - The behavior of `CHECKIF()` depends on the kernel configuration, but if user mode is enabled, `CONFIG_RUNTIME_ERROR_CHECKS` is enforced, which guarantees that these checks will be made and a return value propagated.

6. It is totally forbidden for any kind of kernel mode callback function to be registered from user mode. APIs which simply install callbacks shall not be exposed as system calls. Some driver subsystem APIs may take optional function callback pointers. User mode verification functions for these APIs must enforce that these are NULL and should invoke `K_OOPS()` if not.

7. Some parameter checks are enforced only from user mode. These should be checked in the verification function and propagate a return value to the caller if possible.

There are some known exceptions to these policies currently in Zephyr:

- `k_thread_join()` and `k_thread_abort()` are no-ops if the thread object isn’t initialized. This is because for threads, the initialization bit pulls double-duty to indicate whether a thread is running, cleared upon exit. See #23030.
- `k_thread_create()` invokes `K_OOPS()` for parameter checks, due to a great deal of existing code ignoring the return value. This will also be addressed by #23030.
- `k_thread_abort()` invokes `K_OOPS()` if an essential thread is aborted, as the function has no return value.
- Various system calls related to logging invoke `K_OOPS()` when bad parameters are passed in as they do not propagate errors.

### Configuration Options

Related configuration options:

- `CONFIG_USERSPACE`
- `CONFIG_EMIT_ALL_SYSCALLS`

### APIs

Helper macros for creating system call verification functions are provided in `include/zephyr/internal/syscall_handler.h`:

- `K_SYSCALL_OBJ()`
- `K_SYSCALL_OBJ_INIT()`
• K_SYSCALL_OBJ_NEVER_INIT()
• K_OOPS()
• K_SYSCALL_MEMORY_READ()
• K_SYSCALL_MEMORY_WRITE()
• K_SYSCALL_MEMORY_ARRAY_READ()
• K_SYSCALL_MEMORY_ARRAY_WRITE()
• K_SYSCALL_VERIFY_MSG()
• K_SYSCALL_VERIFY

Functions for invoking system calls are defined in include/zephyr/syscall.h:
• _arch_syscall_invoke0()
• _arch_syscall_invoke1()
• _arch_syscall_invoke2()
• _arch_syscall_invoke3()
• _arch_syscall_invoke4()
• _arch_syscall_invoke5()
• _arch_syscall_invoke6()

### 3.3.5 MPU Stack Objects

#### Thread Stack Creation

Thread stacks are declared statically with K_THREAD_STACK_DEFINE().

For architectures which utilize memory protection unit (MPU) hardware, stacks are physically contiguous allocations. This contiguous allocation has implications for the placement of stacks in memory, as well as the implementation of other features such as stack protection and userspace. The implications for placement are directly attributed to the alignment requirements for MPU regions. This is discussed in the memory placement section below.

#### Stack Guards

Stack protection mechanisms require hardware support that can restrict access to memory. Memory protection units can provide this kind of support. The MPU provides a fixed number of regions. Each region contains information about the start, end, size, and access attributes to be enforced on that particular region.

Stack guards are implemented by using a single MPU region and setting the attributes for that region to not allow write access. If invalid accesses occur, a fault ensues. The stack guard is defined at the bottom (the lowest address) of the stack.

#### Memory Placement

During stack creation, a set of constraints are enforced on the allocation of memory. These constraints include determining the alignment of the stack and the correct sizing of the stack. During linking of the binary, these constraints are used to place the stacks properly.
The main source of the memory constraints is the MPU design for the SoC. The MPU design may require specific constraints on the region definition. These can include alignment of beginning and end addresses, sizes of allocations, or even interactions between overlapping regions.

Some MPUs require that each region be aligned to a power of two. These SoCs will have `CONFIG_MPU_REQUIRES_POWER_OF_TWO_ALIGNMENT` defined. This means that a 1500 byte stack should be aligned to a 2kB boundary and the stack size should also be adjusted to 2kB to ensure that nothing else is placed in the remainder of the region. SoCs which include the unmodified ARM v7m MPU will have these constraints.

Some ARM MPUs use start and end addresses to define MPU regions and both the start and end addresses require 32 byte alignment. An example of this kind of MPU is found in the NXP FRDM K64F.

MPUs may have a region priority mechanisms that use the highest priority region that covers the memory access to determine the enforcement policy. Others may logically OR regions to determine enforcement policy.

Size and alignment constraints may result in stack allocations being larger than the requested size. Region priority mechanisms may result in some added complexity when implementing stack guards.

### 3.3.6 MPU Backed Userspace

The MPU backed userspace implementation requires the creation of a secondary set of stacks. These stacks exist in a 1:1 relationship with each thread stack defined in the system. The privileged stacks are created as a part of the build process.

A post-build script `scripts/build/gen_kobject_list.py` scans the generated ELF file and finds all of the thread stack objects. A set of privileged stacks, a lookup table, and a set of helper functions are created and added to the image.

During the process of dropping a thread to user mode, the privileged stack information is filled in and later used by the swap and system call infrastructure to configure the MPU regions properly for the thread stack and guard (if applicable).

During system calls, the user mode thread's access to the system call and the passed-in parameters are all validated. The user mode thread is then elevated to privileged mode, the stack is switched to use the privileged stack, and the call is made to the specified kernel API. On return from the kernel API, the thread is set back to user mode and the stack is restored to the user stack.

### 3.4 Memory Management

The following contains various topics regarding memory management.

#### 3.4.1 Memory Heaps

Zephyr provides a collection of utilities that allow threads to dynamically allocate memory.

**Synchronized Heap Allocator**

**Creating a Heap** The simplest way to define a heap is statically, with the `K_HEAP_DEFINE` macro. This creates a static `k_heap` variable with a given name that manages a memory region of the specified size.
Heaps can also be created to manage arbitrary regions of application-controlled memory using \texttt{k_heap_init()}. 

**Allocating Memory** Memory can be allocated from a heap using \texttt{k_heap_alloc()}, passing it the address of the heap object and the number of bytes desired. This functions similarly to standard C \texttt{malloc()}, returning a NULL pointer on an allocation failure.

The heap supports blocking operation, allowing threads to go to sleep until memory is available. The final argument is a \texttt{k_timeout_t} timeout value indicating how long the thread may sleep before returning, or else one of the constant timeout values \texttt{K\_NO\_WAIT} or \texttt{K\_FOREVER}.

**Releasing Memory** Memory allocated with \texttt{k_heap_alloc()} must be released using \texttt{k_heap_free()}. Similar to standard C \texttt{free()}, the pointer provided must be either a NULL value or a pointer previously returned by \texttt{k_heap_alloc()} for the same heap. Freeing a NULL value is defined to have no effect.

**Low Level Heap Allocator**

The underlying implementation of the \texttt{k_heap} abstraction is provided a data structure named \texttt{sys_heap}. This implements exactly the same allocation semantics, but provides no kernel synchronization tools. It is available for applications that want to manage their own blocks of memory in contexts (for example, userspace) where synchronization is unavailable or more complicated. Unlike \texttt{k_heap}, all calls to any \texttt{sys_heap} functions on a single heap must be serialized by the caller. Simultaneous use from separate threads is disallowed.

**Implementation** Internally, the \texttt{sys_heap} memory block is partitioned into “chunks” of 8 bytes. All allocations are made out of a contiguous region of chunks. The first chunk of every allocation or unused block is prefixed by a chunk header that stores the length of the chunk, the length of the next lower (“left”) chunk in physical memory, a bit indicating whether the chunk is in use, and chunk-indexed link pointers to the previous and next chunk in a “free list” to which unused chunks are added.

The heap code takes reasonable care to avoid fragmentation. Free block lists are stored in “buckets” by their size, each bucket storing blocks within one power of two (i.e. a bucket for blocks of 3-4 chunks, another for 5-8, 9-16, etc...) this allows new allocations to be made from the smallest/most-fragmented blocks available. Also, as allocations are freed and added to the heap, they are automatically combined with adjacent free blocks to prevent fragmentation.

All metadata is stored at the beginning of the contiguous block of heap memory, including the variable-length list of bucket list heads (which depend on heap size). The only external memory required is the \texttt{sys_heap} structure itself.

The \texttt{sys_heap} functions are unsynchronized. Care must be taken by any users to prevent concurrent access. Only one context may be inside one of the API functions at a time.

The heap code takes care to present high performance and reliable latency. All \texttt{sys_heap} API functions are guaranteed to complete within constant time. On typical architectures, they will all complete within 1-200 cycles. One complexity is that the search of the minimum bucket size for an allocation (the set of free blocks that “might fit”) has a compile-time upper bound of iterations to prevent unbounded list searches, at the expense of some fragmentation resistance. This \texttt{CONFIG\_SYS\_HEAP\_ALLOC\_LOOPS} value may be chosen by the user at build time, and defaults to a value of 3.
Multi-Heap Wrapper Utility

The `sys_heap` utility requires that all managed memory be in a single contiguous block. It is common for complicated microcontroller applications to have more complicated memory setups that they still want to manage dynamically as a “heap”. For example, the memory might exist as separate discontiguous regions, different areas may have different cache, performance or power behavior, peripheral devices may only be able to perform DMA to certain regions, etc...

For those situations, Zephyr provides a `sys_multi_heap` utility. Effectively this is a simple wrapper around a set of one or more `sys_heap` objects. It should be initialized after its child heaps via `sys_multi_heap_init()`, after which each heap can be added to the managed set via `sys_multi_heap_add_heap()`. No destruction utility is provided; just as for `sys_heap`, applications that want to destroy a multi heap should simply ensure all allocated blocks are freed (or at least will never be used again) and repurpose the underlying memory for another usage.

It has a single pair of allocation entry points, `sys_multi_heap_alloc()` and `sys_multi_heap_aligned_alloc()`. These behave identically to the `sys_heap` functions with similar names, except that they also accept an opaque “configuration” parameter. This pointer is uninspected by the multi heap code itself; instead it is passed to a callback function provided at initialization time. This application-provided callback is responsible for doing the underlying allocation from one of the managed heaps, and may use the configuration parameter in any way it likes to make that decision.

When unused, a multi heap may be freed via `sys_multi_heap_free()`. The application does not need to pass a configuration parameter. Memory allocated from any of the managed `sys_heap` objects may be freed with in the same way.

System Heap

The `system heap` is a predefined memory allocator that allows threads to dynamically allocate memory from a common memory region in a `malloc()`-like manner.

Only a single system heap is defined. Unlike other heaps or memory pools, the system heap cannot be directly referenced using its memory address.

The size of the system heap is configurable to arbitrary sizes, subject to space availability.

A thread can dynamically allocate a chunk of heap memory by calling `k_malloc()`. The address of the allocated chunk is guaranteed to be aligned on a multiple of pointer sizes. If a suitable chunk of heap memory cannot be found `NULL` is returned.

When the thread is finished with a chunk of heap memory it can release the chunk back to the system heap by calling `k_free()`.

Defining the Heap Memory Pool

The size of the heap memory pool is specified using the `CONFIG_HEAP_MEM_POOL_SIZE` configuration option.

By default, the heap memory pool size is zero bytes. This value instructs the kernel not to define the heap memory pool object. The maximum size is limited by the amount of available memory in the system. The project build will fail in the link stage if the size specified can not be supported.

In addition, each subsystem (board, driver, library, etc) can set a custom requirement by defining a Kconfig option with the prefix `HEAP_MEM_POOL_ADD_SIZE_` (this value is in bytes). If multiple subsystems specify custom values, the sum of these will be used as the minimum requirement. If the application tries to set a value that’s less than the minimum value, this will be ignored and the minimum value will be used instead.

To force a smaller than minimum value to be used, the application may enable the `CONFIG_HEAP_MEM_POOL_IGNORE_MIN` option. This can be useful when optimizing the heap size and the minimum requirement can be more accurately determined for a specific application.
Allocating Memory  A chunk of heap memory is allocated by calling `k_malloc()`.
The following code allocates a 200 byte chunk of heap memory, then fills it with zeros. A warning
is issued if a suitable chunk is not obtained.

```c
char *mem_ptr;
mem_ptr = k_malloc(200);
if (mem_ptr != NULL) {
    memset(mem_ptr, 0, 200);
    ...
} else {
    printf("Memory not allocated");
}
```

Releasing Memory  A chunk of heap memory is released by calling `k_free()`.
The following code allocates a 75 byte chunk of memory, then releases it once it is no longer
needed.

```c
char *mem_ptr;
mem_ptr = k_malloc(75);
/* use memory block */
k_free(mem_ptr);
```

Suggested Uses  Use the heap memory pool to dynamically allocate memory in a `malloc()`-like
manner.

Configuration Options  Related configuration options:

- `CONFIG_HEAP_MEM_POOL_SIZE`

API Reference

`group heap_apis`

Defines

`K_HEAP_DEFINE(name, bytes)`
Define a static `k_heap`.

This macro defines and initializes a static memory region and `k_heap` of the requested
size. After kernel start, &name can be used as if `k_heap_init()` had been called.

Note that this macro enforces a minimum size on the memory region to accommodate
metadata requirements. Very small heaps will be padded to fit.

Parameters

- `name` – Symbol name for the struct `k_heap` object
- `bytes` – Size of memory region, in bytes
**K_HEAP_DEFINE_NOCACHE**(name, bytes)

Define a static k_heap in uncached memory.

This macro defines and initializes a static memory region and k_heap of the requested size in uncached memory. After kernel start, &name can be used as if k_heap_init() had been called.

Note that this macro enforces a minimum size on the memory region to accommodate metadata requirements. Very small heaps will be padded to fit.

**Parameters**

- **name** – Symbol name for the struct k_heap object
- **bytes** – Size of memory region, in bytes

**Functions**

**void k_heap_init**(struct k_heap *h, void *mem, size_t bytes)

Initialize a k_heap.

This constructs a synchronized k_heap object over a memory region specified by the user. Note that while any alignment and size can be passed as valid parameters, internal alignment restrictions inside the inner sys_heap mean that not all bytes may be usable as allocated memory.

**Parameters**

- **h** – Heap struct to initialize
- **mem** – Pointer to memory.
- **bytes** – Size of memory region, in bytes

**void *k_heap_aligned_alloc**(struct k_heap *h, size_t align, size_t bytes, k_timeout_t timeout)

Allocate aligned memory from a k_heap.

Behaves in all ways like k_heap_alloc(), except that the returned memory (if available) will have a starting address in memory which is a multiple of the specified power-of-two alignment value in bytes. The resulting memory can be returned to the heap using k_heap_free().

**Function properties (list may not be complete)**

- **isr-ok**

**Note:** timeout must be set to K_NO_WAIT if called from ISR.

**Note:** When CONFIG_MULTITHREADING=n any timeout is treated as K_NO_WAIT.

**Parameters**

- **h** – Heap from which to allocate
- **align** – Alignment in bytes, must be a power of two
- **bytes** – Number of bytes requested
- **timeout** – How long to wait, or K_NO_WAIT
Returns

Pointer to memory the caller can now use

```c
void *k_heap_alloc(struct k_heap *h, size_t bytes, k_timeout_t timeout)
```
Allocate memory from a `k_heap`.

Allocates and returns a memory buffer from the memory region owned by the heap. If no memory is available immediately, the call will block for the specified timeout (constructed via the standard timeout API, or K_NO_WAIT or K_FOREVER) waiting for memory to be freed. If the allocation cannot be performed by the expiration of the timeout, NULL will be returned. Allocated memory is aligned on a multiple of pointer sizes.

Function properties (list may not be complete)

`isr-ok`

Note: `timeout` must be set to K_NO_WAIT if called from ISR.

Note: When CONFIG_MULTITHREADING=n any `timeout` is treated as K_NO_WAIT.

Parameters

- **h** – Heap from which to allocate
- **bytes** – Desired size of block to allocate
- **timeout** – How long to wait, or K_NO_WAIT

Returns

A pointer to valid heap memory, or NULL

```c
void k_heap_free(struct k_heap *h, void *mem)
```
Free memory allocated by `k_heap_alloc()`

Returns the specified memory block, which must have been returned from `k_heap_alloc()`, to the heap for use by other callers. Passing a NULL block is legal, and has no effect.

Parameters

- **h** – Heap to which to return the memory
- **mem** – A valid memory block, or NULL

```c
void *k_aligned_alloc(size_t align, size_t size)
```
Allocate memory from the heap with a specified alignment.

This routine provides semantics similar to aligned_alloc(); memory is allocated from the heap with a specified alignment. However, one minor difference is that `k_aligned_alloc()` accepts any non-zero `size`, whereas aligned_alloc() only accepts a size that is an integral multiple of `align`.

Above, aligned_alloc() refers to: C11 standard (ISO/IEC 9899:2011): 7.22.3.1 The aligned_alloc function (p: 347-348)

Parameters

- **align** – Alignment of memory requested (in bytes).
- **size** – Amount of memory requested (in bytes).
Returns
Address of the allocated memory if successful; otherwise NULL.

void *k_malloc(size_t size)
Allocate memory from the heap.

This routine provides traditional malloc() semantics. Memory is allocated from the heap memory pool. Allocated memory is aligned on a multiple of pointer sizes.

Parameters
• size – Amount of memory requested (in bytes).

Returns
Address of the allocated memory if successful; otherwise NULL.

void k_free(void *ptr)
Free memory allocated from heap.

This routine provides traditional free() semantics. The memory being returned must have been allocated from the heap memory pool.

If ptr is NULL, no operation is performed.

Parameters
• ptr – Pointer to previously allocated memory.

void *k_calloc(size_t nmemb, size_t size)
Allocate memory from heap, array style.

This routine provides traditional calloc() semantics. Memory is allocated from the heap memory pool and zeroed.

Parameters
• nmemb – Number of elements in the requested array
• size – Size of each array element (in bytes).

Returns
Address of the allocated memory if successful; otherwise NULL.

struct k_heap

#include <kernel.h>

Heap listener

group heap_listener_apis

Defines

HEAP_ID_FROM_POINTER(heap_pointer)
Construct heap identifier from heap pointer.

Construct a heap identifier from a pointer to the heap object, such as sys_heap.

Parameters
• heap_pointer – Pointer to the heap object
HEAP_ID_LIBC
Libc heap identifier.
Identifier of the global libc heap.

HEAP_LISTENER_ALLOC_DEFINE(name, _heap_id, _alloc_cb)
Define heap event listener node for allocation event.
Sample usage:

```c
void on_heap_alloc(uintptr_t heap_id, void *mem, size_t bytes)
{
    LOG_INF("Memory allocated at %p, size %ld", mem, bytes);
}

HEAP_LISTENER_ALLOC_DEFINE(my_listener, HEAP_ID_LIBC, on_heap_alloc);
```

Parameters
- name – Name of the heap event listener object
- _heap_id – Identifier of the heap to be listened
- _alloc_cb – Function to be called for allocation event

HEAP_LISTENER_FREE_DEFINE(name, _heap_id, _free_cb)
Define heap event listener node for free event.
Sample usage:

```c
void on_heap_free(uintptr_t heap_id, void *mem, size_t bytes)
{
    LOG_INF("Memory freed at %p, size %ld", mem, bytes);
}

HEAP_LISTENER_FREE_DEFINE(my_listener, HEAP_ID_LIBC, on_heap_free);
```

Parameters
- name – Name of the heap event listener object
- _heap_id – Identifier of the heap to be listened
- _free_cb – Function to be called for free event

HEAP_LISTENER_RESIZE_DEFINE(name, _heap_id, _resize_cb)
Define heap event listener node for resize event.
Sample usage:

```c
void on_heap_resized(uintptr_t heap_id, void *old_heap_end, void *new_heap_end)
{
    LOG_INF("Libc heap end moved from %p to %p", old_heap_end, new_heap_end);
}

HEAP_LISTENER_RESIZE_DEFINE(my_listener, HEAP_ID_LIBC, on_heap_resized);
```

Parameters
- name – Name of the heap event listener object
- _heap_id – Identifier of the heap to be listened
- _resize_cb – Function to be called when the listened heap is resized
**Typedefs**

`typedef void (*heap_listener_resize_cb_t)(uintptr_t heap_id, void *old_heap_end, void *new_heap_end)`

Callback used when heap is resized.

**Note:** Minimal C library does not emit this event.

**Param heap_id**
Identifier of heap being resized

**Param old_heap_end**
Pointer to end of heap before resize

**Param new_heap_end**
Pointer to end of heap after resize

`typedef void (*heap_listener_alloc_cb_t)(uintptr_t heap_id, void *mem, size_t bytes)`

Callback used when there is heap allocation.

**Note:** Heaps managed by libraries outside of code in Zephyr main code repository may not emit this event.

**Note:** The number of bytes allocated may not match exactly to the request to the allocation function. Internal mechanism of the heap may allocate more than requested.

**Param heap_id**
Heap identifier

**Param mem**
Pointer to the allocated memory

**Param bytes**
Size of allocated memory

`typedef void (*heap_listener_free_cb_t)(uintptr_t heap_id, void *mem, size_t bytes)`

Callback used when memory is freed from heap.

**Note:** Heaps managed by libraries outside of code in Zephyr main code repository may not emit this event.

**Note:** The number of bytes freed may not match exactly to the request to the allocation function. Internal mechanism of the heap dictates how memory is allocated or freed.

**Param heap_id**
Heap identifier

**Param mem**
Pointer to the freed memory
**Param bytes**  
Size of freed memory

** Enums**

```c
enum heap_event_types  
Values:
  enumerator HEAP_EVT_UNKNOWN = 0
  enumerator HEAP_RESIZE
  enumerator HEAP_ALLOC
  enumerator HEAP_FREE
  enumerator HEAP_REALLOC
  enumerator HEAP_MAX_EVENTS
```

**Functions**

```c
void heap_listener_register(struct heap_listener *listener)  
Register heap event listener.
Add the listener to the global list of heap listeners that can be notified by different heap implementations upon certain events related to the heap usage.

Parameters
• listener – Pointer to the heap_listener object

void heap_listener_unregister(struct heap_listener *listener)  
Unregister heap event listener.
Remove the listener from the global list of heap listeners that can be notified by different heap implementations upon certain events related to the heap usage.

Parameters
• listener – Pointer to the heap_listener object

void heap_listener_notify_alloc(uintptr_t heap_id, void *mem, size_t bytes)  
Notify listeners of heap allocation event.
Notify registered heap event listeners with matching heap identifier that an allocation has been done on heap

Parameters
• heap_id – Heap identifier
• mem – Pointer to the allocated memory
• bytes – Size of allocated memory
```
void heap_listener_notify_free(uintptr_t heap_id, void *mem, size_t bytes)
Notify listeners of heap free event.
Notify registered heap event listeners with matching heap identifier that memory is freed on heap

Parameters
• heap_id – Heap identifier
• mem – Pointer to the freed memory
• bytes – Size of freed memory

void heap_listener_notify_resize(uintptr_t heap_id, void *old_heap_end, void *new_heap_end)

Notify listeners of heap resize event.
Notify registered heap event listeners with matching heap identifier that the heap has been resized.

Parameters
• heap_id – Heap identifier
• old_heap_end – Address of the heap end before the change
• new_heap_end – Address of the heap end after the change

struct heap_listener

#include <heap_listener.h>

Public Members

sys_snode_t node
Singly linked list node.

uintptr_t heap_id
Identifier of the heap whose events are listened.
It can be a heap pointer, if the heap is represented as an object, or 0 in the case of the global libc heap.

enum heap_event_types event
The heap event to be notified.

3.4.2 Shared Multi Heap

The shared multi-heap memory pool manager uses the multi-heap allocator to manage a set of reserved memory regions with different capabilities / attributes (cacheable, non-cacheable, etc...).
All the different regions can be added at run-time to the shared multi-heap pool providing an opaque “attribute” value (an integer or enum value) that can be used by drivers or applications to request memory with certain capabilities.
This framework is commonly used as follow:
1. At boot time some platform code initialize the shared multi-heap framework using `shared_multi_heap_pool_init()` and add the memory regions to the pool with `shared_multi_heap_add()`, possibly gathering the needed information for the regions from the DT.

2. Each memory region encoded in a `shared_multi_heap_region` structure. This structure is also carrying an opaque and user-defined integer value that is used to define the region capabilities (for example: cacheability, cpu affinity, etc...)

```c
// Init the shared multi-heap pool
shared_multi_heap_pool_init()

// Fill the struct with the data for cacheable memory
struct shared_multi_heap_region cacheable_r0 = {
  .addr = addr_r0,
  .size = size_r0,
  .attr = SMH_REG_ATTR_CACHEABLE,
};

// Add the region to the pool
shared_multi_heap_add(&cacheable_r0, NULL);

// Add another cacheable region
struct shared_multi_heap_region cacheable_r1 = {
  .addr = addr_r1,
  .size = size_r1,
  .attr = SMH_REG_ATTR_CACHEABLE,
};

shared_multi_heap_add(&cacheable_r0, NULL);

// Add a non-cacheable region
struct shared_multi_heap_region non_cacheable_r2 = {
  .addr = addr_r2,
  .size = size_r2,
  .attr = SMH_REG_ATTR_NON_CACHEABLE,
};

shared_multi_heap_add(&non_cacheable_r2, NULL);
```

3. When a driver or application needs some dynamic memory with a certain capability, it can use `shared_multi_heap_alloc()` (or the aligned version) to request the memory by using the opaque parameter to select the correct set of attributes for the needed memory. The framework will take care of selecting the correct heap (thus memory region) to carve memory from, based on the opaque parameter and the runtime state of the heaps (available memory, heap state, etc...)

```c
// Allocate 4K from cacheable memory
shared_multi_heap_alloc(SMH_REG_ATTR_CACHEABLE, 0x1000);

// Allocate 4K from non-cacheable memory
shared_multi_heap_alloc(SMH_REG_ATTR_NON_CACHEABLE, 0x1000);
```

**Adding new attributes**

The API does not enforce any attributes, but at least it defines the two most common ones: `SMH_REG_ATTR_CACHEABLE` and `SMH_REG_ATTR_NON_CACHEABLE`

**group shared_multi_heap**

Shared Multi-Heap (SMH) interface.
The shared multi-heap manager uses the multi-heap allocator to manage a set of memory regions with different capabilities / attributes (cacheable, non-cacheable, etc...).

All the different regions can be added at run-time to the shared multi-heap pool providing an opaque “attribute” value (an integer or enum value) that can be used by drivers or applications to request memory with certain capabilities.

This framework is commonly used as follow:

- At boot time some platform code initialize the shared multi-heap framework using `shared_multi_heap_pool_init` and add the memory regions to the pool with `shared_multi_heap_add`, possibly gathering the needed information for the regions from the DT.
- Each memory region encoded in a `shared_multi_heap_region` structure. This structure is also carrying an opaque and user-defined integer value that is used to define the region capabilities (for example: cacheability, cpu affinity, etc...)
- When a driver or application needs some dynamic memory with a certain capability, it can use `shared_multi_heap_alloc` (or the aligned version) to request the memory by using the opaque parameter to select the correct set of attributes for the needed memory. The framework will take care of selecting the correct heap (thus memory region) to carve memory from, based on the opaque parameter and the runtime state of the heaps (available memory, heap state, etc...)

**Defines**

MAX_SHARED_MULTI_HEAP_ATTR

   Maximum number of standard attributes.

**Enums**

enum shared_multi_heap_attr

   SMH region attributes enumeration type.

   Enumeration type for some common memory region attributes.

   Values:

   enumerator SMH_REG_ATTR_CACHEABLE
            cacheable

   enumerator SMH_REG_ATTR_NON_CACHEABLE
            non-cacheable

   enumerator SMH_REG_ATTR_NUM
            must be the last item

**Functions**
int shared_multi_heap_pool_init(void)
  Init the pool.

  This must be the first function to be called to initialize the shared multi-heap pool. All
  the individual heaps must be added later with shared_multi_heap_add.

  Note: As for the generic multi-heap allocator the expectation is that this function will
  be called at soc- or board-level.

Return values
  • 0 – on success.
  • -EALREADY – when the pool was already inited.
  • other – errno codes

void *shared_multi_heap_alloc(enum shared_multi_heap_attr attr, size_t bytes)
  Allocate memory from the memory shared multi-heap pool.
  Allocates a block of memory of the specified size in bytes and with a specified capability
  / attribute. The opaque attribute parameter is used by the backend to select the correct
  heap to allocate memory from.

  Parameters
  • attr – capability / attribute requested for the memory block.
  • bytes – requested size of the allocation in bytes.

Return values
  • ptr – a valid pointer to heap memory.
  • err – NULL if no memory is available.

void *shared_multi_heap_aligned_alloc(enum shared_multi_heap_attr attr, size_t align,
  size_t bytes)
  Allocate aligned memory from the memory shared multi-heap pool.
  Allocates a block of memory of the specified size in bytes and with a specified capability
  / attribute. Takes an additional parameter specifying a power of two alignment in
  bytes.

  Parameters
  • attr – capability / attribute requested for the memory block.
  • align – power of two alignment for the returned pointer, in bytes.
  • bytes – requested size of the allocation in bytes.

Return values
  • ptr – a valid pointer to heap memory.
  • err – NULL if no memory is available.

void shared_multi_heap_free(void *block)
  Free memory from the shared multi-heap pool.
  Used to free the passed block of memory that must be the return value of a previously
  call to shared_multi_heap_alloc or shared_multi_heap_aligned_alloc.

  Parameters
  • block – block to free, must be a pointer to a block allocated by
    shared_multi_heap_alloc or shared_multi_heap_aligned_alloc.
int shared_multi_heap_add(struct shared_multi_heap_region *region, void *user_data)
Add an heap region to the shared multi-heap pool.
This adds a shared multi-heap region to the multi-heap pool.

**Parameters**
- **user_data** – pointer to any data for the heap.
- **region** – pointer to the memory region to be added.

**Return values**
- 0 – on success.
- -EINVAL – when the region attribute is out-of-bound.
- -ENOMEM – when there are no more heaps available.
- other – errno codes

struct shared_multi_heap_region
#include <shared_multi_heap.h> SMH region struct.
This struct is carrying information about the memory region to be added in the multi-heap pool.

**Public Members**

uint32_t attr
Memory heap attribute.

uintptr_t addr
Memory heap starting virtual address.

size_t size
Memory heap size in bytes.

### 3.4.3 Memory Slabs

A *memory slab* is a kernel object that allows memory blocks to be dynamically allocated from a designated memory region. All memory blocks in a memory slab have a single fixed size, allowing them to be allocated and released efficiently and avoiding memory fragmentation concerns.

- **Concepts**
  - Internal Operation
- **Implementation**
  - Defining a Memory Slab
  - Allocating a Memory Block
  - Releasing a Memory Block
- **Suggested Uses**
- **Configuration Options**
- **API Reference**
Concepts

Any number of memory slabs can be defined (limited only by available RAM). Each memory slab is referenced by its memory address.

A memory slab has the following key properties:

• The **block size** of each block, measured in bytes. It must be at least 4N bytes long, where N is greater than 0.
• The **number of blocks** available for allocation. It must be greater than zero.
• A **buffer** that provides the memory for the memory slab’s blocks. It must be at least “block size” times “number of blocks” bytes long.

The memory slab's buffer must be aligned to an N-byte boundary, where N is a power of 2 larger than 2 (i.e. 4, 8, 16, ...). To ensure that all memory blocks in the buffer are similarly aligned to this boundary, the block size must also be a multiple of N.

A memory slab must be initialized before it can be used. This marks all of its blocks as unused.

A thread that needs to use a memory block simply allocates it from a memory slab. When the thread finishes with a memory block, it must release the block back to the memory slab so the block can be reused.

If all the blocks are currently in use, a thread can optionally wait for one to become available. Any number of threads may wait on an empty memory slab simultaneously; when a memory block becomes available, it is given to the highest-priority thread that has waited the longest.

Unlike a heap, more than one memory slab can be defined, if needed. This allows for a memory slab with smaller blocks and others with larger-sized blocks. Alternatively, a memory pool object may be used.

Internal Operation  A memory slab's buffer is an array of fixed-size blocks, with no wasted space between the blocks.

The memory slab keeps track of unallocated blocks using a linked list; the first 4 bytes of each unused block provide the necessary linkage.

Implementation

Defining a Memory Slab  A memory slab is defined using a variable of type `k_mem_slab`. It must then be initialized by calling `k_mem_slab_init()`.

The following code defines and initializes a memory slab that has 6 blocks that are 400 bytes long, each of which is aligned to a 4-byte boundary.

```c
struct k_mem_slab my_slab;
char __aligned(4) my_slab_buffer[6 * 400];
k_mem_slab_init(&my_slab, my_slab_buffer, 400, 6);
```

Alternatively, a memory slab can be defined and initialized at compile time by calling `K_MEM_SLAB_DEFINE`.

The following code has the same effect as the code segment above. Observe that the macro defines both the memory slab and its buffer:

```c
K_MEM_SLAB_DEFINE(my_slab, 400, 6, 4);
```

Similarly, you can define a memory slab in private scope:
Allocating a Memory Block

A memory block is allocated by calling `k_mem_slab_alloc()`. The following code builds on the example above, and waits up to 100 milliseconds for a memory block to become available, then fills it with zeroes. A warning is printed if a suitable block is not obtained.

```c
char *block_ptr;
if (k_mem_slab_alloc(&my_slab, (void **)&block_ptr, K_MSEC(100)) == 0) {
    memset(block_ptr, 0, 400);
    ...}
else {
    printf("Memory allocation time-out");
}
```

Releasing a Memory Block

A memory block is released by calling `k_mem_slab_free()`. The following code builds on the example above, and allocates a memory block, then releases it once it is no longer needed.

```c
char *block_ptr;
k_mem_slab_alloc(&my_slab, (void **)&block_ptr, K_FOREVER);
... /* use memory block pointed at by block_ptr */
k_mem_slab_free(&my_slab, (void *)&block_ptr);
```

Suggested Uses

Use a memory slab to allocate and free memory in fixed-size blocks.

Use memory slab blocks when sending large amounts of data from one thread to another, to avoid unnecessary copying of the data.

Configuration Options

Related configuration options:

- CONFIG_MEM_SLAB_TRACE_MAX_UTILIZATION

API Reference

`group mem_slab_apis`

**Defines**

`K_MEM_SLAB_DEFINE(name, slab_block_size, slab_num_blocks, slab_align)`

Statically define and initialize a memory slab in a public (non-static) scope.

The memory slab's buffer contains `slab_num_blocks` memory blocks that are `slab_block_size` bytes long. The buffer is aligned to a `slab_align`-byte boundary. To
ensure that each memory block is similarly aligned to this boundary, `slab_block_size` must also be a multiple of `slab_align`.

The memory slab can be accessed outside the module where it is defined using:

```c
extern struct k_mem_slab <name>;
```

**Note:** This macro cannot be used together with a static keyword. If such a use-case is desired, use `K_MEM_SLAB_DEFINE_STATIC` instead.

### Parameters

- **name** – Name of the memory slab.
- **slab_block_size** – Size of each memory block (in bytes).
- **slab_num_blocks** – Number memory blocks.
- **slab_align** – Alignment of the memory slab's buffer (power of 2).

### Functions

```c
int k_mem_slab_init(struct k_mem_slab *slab, void *buffer, size_t block_size, uint32_t num_blocks)
```

Initializes a memory slab.

Initializes a memory slab, prior to its first use.

The memory slab's buffer contains `slab_num_blocks` memory blocks that are `slab_block_size` bytes long. The buffer must be aligned to a `slab_align`-byte boundary. To ensure that each memory block is similarly aligned to this boundary, `slab_block_size` must also be a multiple of `slab_align`.

### Parameters

- **slab** – Address of the memory slab.
- **buffer** – Pointer to buffer used for the memory blocks.
- **block_size** – Size of each memory block (in bytes).
- **num_blocks** – Number of memory blocks.

### Return values

- **0** – on success
int k_mem_slab_alloc(struct k_mem_slab *slab, void **mem, \textit{k_timeout_t} \textit{timeout})

Allocate memory from a memory slab.

This routine allocates a memory block from a memory slab.

\textbf{Function properties (list may not be complete)}

\textit{isr-ok}

\textbf{Note}: \textit{timeout} must be set to K_NO_WAIT if called from ISR.

\textbf{Note}: When CONFIG_MULTITHREADING=n any \textit{timeout} is treated as K_NO_WAIT.

\textbf{Parameters}

- \textit{slab} – Address of the memory slab.
- \textit{mem} – Pointer to block address area.
- \textit{timeout} – Non-negative waiting period to wait for operation to complete.
  Use K_NO_WAIT to return without waiting, or K_FOREVER to wait as long as necessary.

\textbf{Return values}

- 0 – Memory allocated. The block address area pointed at by \textit{mem} is set to the starting address of the memory block.
- -ENOMEM – Returned without waiting.
- -EAGAIN – Waiting period timed out.
- -EINVAL – Invalid data supplied

\textbf{void k_mem_slab_free(struct k_mem_slab *slab, void *mem)}

Free memory allocated from a memory slab.

This routine releases a previously allocated memory block back to its associated memory slab.

\textbf{Parameters}

- \textit{slab} – Address of the memory slab.
- \textit{mem} – Pointer to the memory block (as returned by \textit{k_mem_slab_alloc}).

\textbf{static inline uint32_t k_mem_slab_num_used_get(struct k_mem_slab *slab)}

Get the number of used blocks in a memory slab.

This routine gets the number of memory blocks that are currently allocated in \textit{slab}.

\textbf{Parameters}

- \textit{slab} – Address of the memory slab.

\textbf{static inline uint32_t k_mem_slab_max_used_get(struct k_mem_slab *slab)}

Get the number of maximum used blocks so far in a memory slab.

This routine gets the maximum number of memory blocks that were allocated in \textit{slab}.
Parameters

• slab – Address of the memory slab.

Returns

Maximum number of allocated memory blocks.

static inline uint32_t k_mem_slab_num_free_get(struct k_mem_slab *slab)

Get the number of unused blocks in a memory slab.

This routine gets the number of memory blocks that are currently unallocated in slab.

Parameters

• slab – Address of the memory slab.

Returns

Number of unallocated memory blocks.

int k_mem_slab_runtime_stats_get(struct k_mem_slab *slab, struct sys_memory_stats *stats)

Get the memory stats for a memory slab.

This routine gets the runtime memory usage stats for the slab slab.

Parameters

• slab – Address of the memory slab

Parameter values

• 0 – Success

• -EINVAL – Any parameter points to NULL

int k_mem_slab_runtime_stats_reset_max(struct k_mem_slab *slab)

Reset the maximum memory usage for a slab.

This routine resets the maximum memory usage for the slab slab to its current usage.

Parameters

• slab – Address of the memory slab

Return values

• 0 – Success

• -EINVAL – Memory slab is NULL

3.4.4 Memory Blocks Allocator

The Memory Blocks Allocator allows memory blocks to be dynamically allocated from a designated memory region, where:

• All memory blocks have a single fixed size.

• Multiple blocks can be allocated or freed at the same time.

• A group of blocks allocated together may not be contiguous. This is useful for operations such as scatter-gather DMA transfers.

• Bookkeeping of allocated blocks is done outside of the associated buffer (unlike memory slab). This allows the buffer to reside in memory regions where these can be powered down to conserve energy.
Concepts

Any number of Memory Blocks Allocator can be defined (limited only by available RAM). Each allocator is referenced by its memory address.

A memory blocks allocator has the following key properties:

- The block size of each block, measured in bytes. It must be at least 4N bytes long, where N is greater than 0.
- The number of blocks available for allocation. It must be greater than zero.
- A buffer that provides the memory for the memory slab's blocks. It must be at least “block size” times “number of blocks” bytes long.
- A blocks bitmap to keep track of which block has been allocated.

The buffer must be aligned to an N-byte boundary, where N is a power of 2 larger than 2 (i.e. 4, 8, 16, ...). To ensure that all memory blocks in the buffer are similarly aligned to this boundary, the block size must also be a multiple of N.

Due to the use of internal bookkeeping structures and their creation, each memory blocks allocator must be declared and defined at compile time.

Internal Operation  Each buffer associated with an allocator is an array of fixed-size blocks, with no wasted space between the blocks.

The memory blocks allocator keeps track of unallocated blocks using a bitmap.

Memory Blocks Allocator

Internally, the memory blocks allocator uses a bitmap to keep track of which blocks have been allocated. Each allocator, utilizing the sys_bitarray interface, gets memory blocks one by one from the backing buffer up to the requested number of blocks. All the metadata about an allocator is stored outside of the backing buffer. This allows the memory region of the backing buffer to be powered down to conserve energy, as the allocator code never touches the content of the buffer.
Multi Memory Blocks Allocator Group

The Multi Memory Blocks Allocator Group utility functions provide a convenient to manage a group of allocators. A custom allocator choosing function is used to choose which allocator to use among this group.

An allocator group should be initialized at runtime via `sys_multi_mem_blocks_init()`. Each allocator can then be added via `sys_multi_mem_blocks_add_allocator()`.

To allocate memory blocks from group, `sys_multi_mem_blocks_alloc()` is called with an opaque “configuration” parameter. This parameter is passed directly to the allocator choosing function so that an appropriate allocator can be chosen. After an allocator is chosen, memory blocks are allocated via `sys_mem_blocks_alloc()`.

Allocated memory blocks can be freed via `sys_multi_mem_blocks_free()`. The caller does not need to pass a configuration parameter. The allocator code matches the passed in memory addresses to find the correct allocator and then memory blocks are freed via `sys_mem_blocks_free()`.

Usage

Defining a Memory Blocks Allocator  A memory blocks allocator is defined using a variable of type `sys_mem_blocks_t`. It needs to be defined and initialized at compile time by calling `SYS_MEM_BLOCKS_DEFINE`.

The following code defines and initializes a memory blocks allocator which has 4 blocks that are 64 bytes long, each of which is aligned to a 4-byte boundary:

```c
SYS_MEM_BLOCKS_DEFINE(allocator, 64, 4, 4);
```

Similarly, you can define a memory blocks allocator in private scope:

```c
SYS_MEM_BLOCKS_DEFINE_STATIC(static_allocator, 64, 4, 4);
```

A pre-defined buffer can also be provided to the allocator where the buffer can be placed separately. Note that the alignment of the buffer needs to be done at its definition.

```c
uint8_t __aligned(4) backing_buffer[64 * 4];
SYS_MEM_BLOCKS_DEFINE_WITH_EXT_BUF(allocator, 64, 4, backing_buffer);
```

Allocating Memory Blocks  Memory blocks can be allocated by calling `sys_mem_blocks_alloc()`.

```c
int ret;
uintptr_t blocks[2];
ret = sys_mem_blocks_alloc(allocator, 2, blocks);
```

If `ret == 0`, the array `blocks` will contain an array of memory addresses pointing to the allocated blocks.

Releasing a Memory Block  Memory blocks are released by calling `sys_mem_blocks_free()`.

The following code builds on the example above which allocates 2 memory blocks, then releases them once they are no longer needed.
Using Multi Memory Blocks Allocator Group

The following code demonstrates how to initialize an allocator group:

```c
sys_mem_blocks_t *choice_fn(struct sys_multi_mem_blocks *group, void *cfg)
{
    ...
}
SYS_MEM_BLOCKS_DEFINE(allocator0, 64, 4, 4);
SYS_MEM_BLOCKS_DEFINE(allocator1, 64, 4, 4);
static sys_multi_mem_blocks_t alloc_group;
sys_multi_mem_blocks_init(&alloc_group, choice_fn);
sys_multi_mem_blocks_add_allocator(&alloc_group, &allocator0);
sys_multi_mem_blocks_add_allocator(&alloc_group, &allocator1);
```

To allocate and free memory blocks from the group:

```c
int ret;
uintptr_t blocks[1];
size_t blk_size;
ret = sys_multi_mem_blocks_alloc(&alloc_group, UINT_TO_POINTER(0),
                                1, blocks, &blk_size);
ret = sys_multi_mem_blocks_free(&alloc_group, 1, blocks);
```

API Reference

**group mem_blocks_apis**

**Defines**

SYS_MEM_BLOCKS_DEFINE(name, blk_sz, num_blks, buf_align)
Create a memory block object with a new backing buffer.

Parameters

- name – Name of the memory block object.
- blk_sz – Size of each memory block (in bytes).
- num_blks – Total number of memory blocks.
- buf_align – Alignment of the memory block buffer (power of 2).

SYS_MEM_BLOCKS_DEFINE_STATIC(name, blk_sz, num_blks, buf_align)
Create a static memory block object with a new backing buffer.

Parameters
---

**memory block object**

- **name** – Name of the memory block object.
- **blk_sz** – Size of each memory block (in bytes).
- **num_blks** – Total number of memory blocks.
- **buf_align** – Alignment of the memory block buffer (power of 2).

### SYS_MEM_BLOCKS_DEFINE_WITH_EXT_BUF

Create a memory block object with a providing backing buffer.

**Parameters**

- **name** – Name of the memory block object.
- **blk_sz** – Size of each memory block (in bytes).
- **num_blks** – Total number of memory blocks.
- **buf** – Backing buffer of type uint8_t.

### SYS_MEM_BLOCKS_DEFINE_STATIC_WITH_EXT_BUF

Create a static memory block object with a providing backing buffer.

**Parameters**

- **name** – Name of the memory block object.
- **blk_sz** – Size of each memory block (in bytes).
- **num_blks** – Total number of memory blocks.
- **buf** – Backing buffer of type uint8_t.

### Typedefs

- typedef struct sys_mem_blocks *sys_mem_blocks_t
  - Memory Blocks Allocator.

- typedef struct sys_multi_mem_blocks *sys_multi_mem_blocks_t
  - Multi Memory Blocks Allocator.

- typedef sys_mem_blocks_t *(*sys_multi_mem_blocks_choice_fn_t)(struct sys_multi_mem_blocks *group, void *cfg)
  - Multi memory blocks allocator choice function.

  This is a user-provided functions whose responsibility is selecting a specific memory blocks allocator based on the opaque cfg value, which is specified by the user as an argument to **sys_multi_mem_blocks_alloc()**. The callback returns a pointer to the chosen allocator where the allocation is performed.

  NULL may be returned, which will cause the allocation to fail and a -EINVAL reported to the calling code.

  **Param group**
  - Multi memory blocks allocator structure.

  **Param cfg**
  - An opaque user-provided value. It may be interpreted in any way by the application.

  **Return**
  - A pointer to the chosen allocator, or NULL if none is chosen.

---

**3.4. Memory Management**

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Functions

```c
int sys_mem_blocks_alloc(sys_mem_blocks_t *mem_block, size_t count, void **out_blocks)
```

Allocate multiple memory blocks. Allocate multiple memory blocks, and place their pointers into the output array.

**Parameters**
- `count` – [in] Number of blocks to allocate.
- `out_blocks` – [out] Output array to be populated by pointers to the memory blocks. It must have at least `count` elements.

**Return values**
- `0` – Successful
- `-EINVAL` – Invalid argument supplied.
- `-ENOMEM` – Not enough blocks for allocation.

```c
int sys_mem_blocks_alloc_contiguous(sys_mem_blocks_t *mem_block, size_t count, void **out_block)
```

Allocate a contiguous set of memory blocks. Allocate multiple memory blocks, and place their pointers into the output array.

**Parameters**
- `count` – [in] Number of blocks to allocate.
- `out_block` – [out] Output pointer to the start of the allocated block set

**Return values**
- `0` – Successful
- `-EINVAL` – Invalid argument supplied.
- `-ENOMEM` – Not enough contiguous blocks for allocation.

```c
int sys_mem_blocks_get(sys_mem_blocks_t *mem_block, void *in_block, size_t count)
```

Force allocation of a specified blocks in a memory block object. Note: use caution when mixing `sys_mem_blocks_get` and `sys_mem_blocks_alloc`, allocation may take any of the free memory space

**Parameters**
- `in_block` – [in] Address of the first required block to allocate
- `count` – [in] Number of blocks to allocate.

**Return values**
- `0` – Successful
- `-EINVAL` – Invalid argument supplied.
- `-ENOMEM` – Some of blocks are taken and cannot be allocated
int sys_mem_blocks_is_region_free(sys_mem_blocks_t *mem_block, void *in_block, size_t count)

check if the region is free

Parameters

• mem_block – [in] Pointer to memory block object.
• in_block – [in] Address of the first block to check
• count – [in] Number of blocks to check.

Return values

• 1 – All memory blocks are free
• 0 – At least one of the memory blocks is taken

int sys_mem_blocks_free(sys_mem_blocks_t *mem_block, size_t count, void **in_blocks)

Free multiple memory blocks according to the array of memory block pointers.

Parameters

• mem_block – [in] Pointer to memory block object.
• count – [in] Number of blocks to free.
• in_blocks – [in] Input array of pointers to the memory blocks.

Return values

• 0 – Successful
• -EINVAL – Invalid argument supplied.
• -EFAULT – Invalid pointers supplied.

int sys_mem_blocks_free_contiguous(sys_mem_blocks_t *mem_block, void *block, size_t count)

Free contiguous multiple memory blocks.

Parameters

• mem_block – [in] Pointer to memory block object.
• block – [in] Pointer to the first memory block
• count – [in] Number of blocks to free.

Return values

• 0 – Successful
• -EINVAL – Invalid argument supplied.
• -EFAULT – Invalid pointer supplied.

void sys_multi_mem_blocks_init(sys_multi_mem_blocks_t *group, 
sys_multi_mem_blocks_choice_fn_t choice_fn)

Initialize multi memory blocks allocator group.

Initialize a sys_multi_mem_block struct with the specified choice function. Note that individual allocator must be added later with sys_multi_mem_blocks_add_allocator.

Parameters

• group – Multi memory blocks allocator structure.
• **choice_fn** – A `sys_multi_mem_blocks_choice_fn_t` callback used to select
the allocator to be used at allocation time

```c
void sys_multi_mem_blocks_add_allocator (sys_multi_mem_blocks_t *group,
                                         sys_mem_blocks_t *alloc)
```

Add an allocator to an allocator group.
This adds a known allocator to an existing multi memory blocks allocator group.

**Parameters**
- `group` – Multi memory blocks allocator structure.
- `alloc` – Allocator to add

```c
int sys_multi_mem_blocks_alloc (sys_multi_mem_blocks_t *group, void *cfg, size_t count,
                                void **out_blocks, size_t *blk_size)
```

Allocate memory from multi memory blocks allocator group.
Just as for `sys_mem_blocks_alloc()`, allocates multiple blocks of memory. Takes an
opaque configuration pointer passed to the choice function, which is used by integra-
tion code to choose an allocator.

**Parameters**
- `cfg` – [in] Opaque configuration parameter, as for
  `sys_multi_mem_blocks_choice_fn_t`
- `count` – [in] Number of blocks to allocate
- `out_blocks` – [out] Output array to be populated by pointers to the mem-
  ory blocks. It must have at least `count` elements.
- `blk_size` – [out] If not NULL, output the block size of the chosen allocator.

**Return values**
- 0 – Successful
- -EINVAL – Invalid argument supplied, or no allocator chosen.
- -ENOMEM – Not enough blocks for allocation.

```c
int sys_multi_mem_blocks_free (sys_multi_mem_blocks_t *group, size_t count, void **in_blocks)
```

Free memory allocated from multi memory blocks allocator group.
Free previous allocated memory blocks from `sys_multi_mem_blocks_alloc()`.
Note that all blocks in `in_blocks` must be from the same allocator.

**Parameters**
- `count` – [in] Number of blocks to free.

**Return values**
- 0 – Successful
- -EINVAL – Invalid argument supplied, or no allocator chosen.
- -EFAULT – Invalid pointer(s) supplied.
3.4.5 Demand Paging

Demand paging provides a mechanism where data is only brought into physical memory as required by current execution context. The physical memory is conceptually divided in page-sized page frames as regions to hold data.

- When the processor tries to access data and the data page exists in one of the page frames, the execution continues without any interruptions.

- When the processor tries to access the data page that does not exist in any page frames, a page fault occurs. The paging code then brings in the corresponding data page from backing store into physical memory if there is a free page frame. If there is no more free page frames, the eviction algorithm is invoked to select a data page to be paged out, thus freeing up a page frame for new data to be paged in. If this data page has been modified after it is first paged in, the data will be written back into the backing store. If no modifications is done or after written back into backing store, the data page is now considered paged out and the corresponding page frame is now free. The paging code then invokes the backing store to page in the data page corresponding to the location of the requested data. The backing store copies that data page into the free page frame. Now the data page is in physical memory and execution can continue.

There are functions where paging in and out can be invoked manually using `k_mem_page_in()` and `k_mem_page_out()`. `k_mem_page_in()` can be used to page in data pages in anticipation that they are required in the near future. This is used to minimize number of page faults as these data pages are already in physical memory, and thus minimizing latency. `k_mem_page_out()` can be used to page out data pages where they are not going to be accessed for a considerable amount of time. This frees up page frames so that the next page in can be executed faster as the paging code does not need to invoke the eviction algorithm.

Terminology

Data Page
A data page is a page-sized region of data. It may exist in a page frame, or be paged out to some backing store. Its location can always be looked up in the CPU’s page tables (or equivalent) by virtual address. The data type will always be `void *` or in some cases `uint8_t *` when doing pointer arithmetic.

Page Frame
A page frame is a page-sized physical memory region in RAM. It is a container where a data page may be placed. It is always referred to by physical address. Zephyr has a convention of using `uintptr_t` for physical addresses. For every page frame, a struct `z_page_frame` is instantiated to store metadata. Flags for each page frame:

- `Z_PAGE_FRAME_Pinned` indicates a page frame is pinned in memory and should never be paged out.
- `Z_PAGE_FRAME_RESERVED` indicates a physical page reserved by hardware and should not be used at all.
- `Z_PAGE_FRAME_MAPPED` is set when a physical page is mapped to virtual memory address.
- `Z_PAGE_FRAME_BUSY` indicates a page frame is currently involved in a page-in/out operation.
- `Z_PAGE_FRAME_BACKED` indicates a page frame has a clean copy in the backing store.

Z_SCRATCH_PAGE
The virtual address of a special page provided to the backing store to: * Copy a data page from Z_SCRATCH_PAGE to the specified location; or, * Copy a data page from the provided location to Z_SCRATCH_PAGE. This is used as an intermediate page for page in/out operations. This scratch needs to be mapped read/write for backing store code to access. However the
data page itself may only be mapped as read-only in virtual address space. If this page is provided as-is to backing store, the data page must be re-mapped as read/write which has security implications as the data page is no longer read-only to other parts of the application.

### Paging Statistics

Paging statistics can be obtained via various function calls when `CONFIG_DEMAND_PAGING_TIMING_HISTOGRAM_NUM_BINS` is enabled:

- Overall statistics via `k_mem_paging_stats_get()`
- Per-thread statistics via `k_mem_paging_thread_stats_get()` if `CONFIG_DEMAND_PAGING_THREAD_STATS` is enabled
- Execution time histogram can be obtained when `CONFIG_DEMAND_PAGING_TIMING_HISTOGRAM` is enabled, and `CONFIG_DEMAND_PAGING_TIMING_HISTOGRAM_NUM_BINS` is defined. Note that the timing is highly dependent on the architecture, SoC or board. It is highly recommended that `k_mem_paging_eviction_histogram_bounds[]` and `k_mem_paging_backing_store_histogram_bounds[]` be defined for a particular application.
  - Execution time histogram of eviction algorithm via `k_mem_paging_histogram_eviction_get()`
  - Execution time histogram of backing store doing page-in via `k_mem_paging_histogram_backing_store_page_in_get()`
  - Execution time histogram of backing store doing page-out via `k_mem_paging_histogram_backing_store_page_out_get()`

### Eviction Algorithm

The eviction algorithm is used to determine which data page and its corresponding page frame can be paged out to free up a page frame for the next page in operation. There are two functions which are called from the kernel paging code:

- `k_mem_paging_eviction_init()` is called to initialize the eviction algorithm. This is called at `POST_KERNEL`.
- `k_mem_paging_eviction_select()` is called to select a data page to evict. A function argument `dirty` is written to signal the caller whether the selected data page has been modified since it is first paged in. If the `dirty` bit is returned as set, the paging code signals to the backing store to write the data page back into storage (thus updating its content). The function returns a pointer to the page frame corresponding to the selected data page.

Currently, a NRU (Not-Recently-Used) eviction algorithm has been implemented as a sample. This is a very simple algorithm which ranks each data page on whether they have been accessed and modified. The selection is based on this ranking.

To implement a new eviction algorithm, the two functions mentioned above must be implemented.

### Backing Store

Backing store is responsible for paging in/out data page between their corresponding page frames and storage. These are the functions which must be implemented:

- `k_mem_paging_backing_store_init()` is called to initialized the backing store at `POST_KERNEL`. 
• `k_mem_pagingBackingStoreLocationGet()` is called to reserve a backing store location so a data page can be paged out. This location token is passed to `k_mem_pagingBackingStorePageOut()` to perform actual page out operation.

• `k_mem_pagingBackingStoreLocationFree()` is called to free a backing store location (the location token) which can then be used for subsequent page out operation.

• `k_mem_pagingBackingStorePageIn()` copies a data page from the backing store location associated with the provided location token to the page pointed by `Z_SCRATCH_PAGE`.

• `k_mem_pagingBackingStorePageOut()` copies a data page from `Z_SCRATCH_PAGE` to the backing store location associated with the provided location token.

• `k_mem_pagingBackingStorePageFinalize()` is invoked after `k_mem_pagingBackingStorePageIn()` so that the page frame struct may be updated for internal accounting. This can be a no-op.

To implement a new backing store, the functions mentioned above must be implemented. `k_mem_pagingBackingStorePageFinalize()` can be an empty function if so desired.

API Reference

**group mem-demand-paging**

**Functions**

`int k_mem_page_out(void *addr, size_t size)`

Evict a page-aligned virtual memory region to the backing store.

Useful if it is known that a memory region will not be used for some time. All the data pages within the specified region will be evicted to the backing store if they weren't already, with their associated page frames marked as available for mappings or page-ins.

None of the associated page frames mapped to the provided region should be pinned.

Note that there are no guarantees how long these pages will be evicted, they could take page faults immediately.

If `CONFIG_DEMAND_PAGING_ALLOW_IRQ` is enabled, this function may not be called by ISRs as the backing store may be in-use.

**Parameters**

• `addr` – Base page-aligned virtual address

• `size` – Page-aligned data region size

**Return values**

• 0 – Success

• -ENOMEM – Insufficient space in backing store to satisfy request. The region may be partially paged out.

`void k_mem_page_in(void *addr, size_t size)`

Load a virtual data region into memory.

After the function completes, all the page frames associated with this function will be paged in. However, they are not guaranteed to stay there. This is useful if the region is known to be used soon.

If `CONFIG_DEMAND_PAGING_ALLOW_IRQ` is enabled, this function may not be called by ISRs as the backing store may be in-use.
Parameters
• **addr** – Base page-aligned virtual address
• **size** – Page-aligned data region size

```c
void k_mem_pin(void *addr, size_t size)
```

Pin an aligned virtual data region, paging in as necessary.
After the function completes, all the page frames associated with this region will be resident in memory and pinned such that they stay that way. This is a stronger version of `z_mem_page_in()`.

If `CONFIG_DEMAND_PAGING_ALLOW_IRQ` is enabled, this function may not be called by ISRs as the backing store may be in-use.

Parameters
• **addr** – Base page-aligned virtual address
• **size** – Page-aligned data region size

```c
void k_mem_unpin(void *addr, size_t size)
```

Un-pin an aligned virtual data region.
After the function completes, all the page frames associated with this region will be no longer marked as pinned. This does not evict the region, follow this with `z_mem_page_out()` if you need that.

Parameters
• **addr** – Base page-aligned virtual address
• **size** – Page-aligned data region size

```c
void k_mem_paging_stats_get(struct k_mem_paging_stats_t *stats)
```

Get the paging statistics since system startup.
This populates the paging statistics struct being passed in as argument.

Parameters
• **stats** – [inout] Paging statistics struct to be filled.

```c
void k_mem_paging_thread_stats_get(struct k_thread *thread, struct k_mem_paging_stats_t *stats)
```

Get the paging statistics since system startup for a thread.
This populates the paging statistics struct being passed in as argument for a particular thread.

Parameters
• **thread** – [in] Thread
• **stats** – [inout] Paging statistics struct to be filled.

```c
void k_mem_paging_histogram_eviction_get(struct k_mem_paging_histogram_t *hist)
```

Get the eviction timing histogram.
This populates the timing histogram struct being passed in as argument.

Parameters
• **hist** – [inout] Timing histogram struct to be filled.

```c
void k_mem_paging_histogram_backing_store_page_in_get(struct k_mem_paging_histogram_t *hist)
```
Get the backing store page-in timing histogram.
This populates the timing histogram struct being passed in as argument.

**Parameters**

- `hist` – `[inout]` Timing histogram struct to be filled.

```c
void k_mem_paging_histogram_backing_store_page_out_get(struct k_mem_paging_histogram_t *hist)
```

Get the backing store page-out timing histogram.
This populates the timing histogram struct being passed in as argument.

**Parameters**

- `hist` – `[inout]` Timing histogram struct to be filled.

```c
struct k_mem_paging_stats_t
#include <demand_paging.h> Paging Statistics.
```

### Public Members

- `cnt`  
  Number of page faults.

- `irq_locked`  
  Number of page faults with IRQ locked.

- `irq_unlocked`  
  Number of page faults with IRQ unlocked.

- `in_isr`  
  Number of page faults while in ISR.

- `clean`  
  Number of clean pages selected for eviction.

- `dirty`  
  Number of dirty pages selected for eviction.

```c
struct k_mem_paging_histogram_t
#include <demand_paging.h> Paging Statistics Histograms.
```

### Eviction Algorithm APIs

**group mem-demand-paging-eviction**

Eviction algorithm APIs.
Functions

struct z_page_frame *k_mem_paging_eviction_select(bool *dirty)
    Select a page frame for eviction.
    The kernel will invoke this to choose a page frame to evict if there are no free page frames.
    This function will never be called before the initial k_mem_paging_eviction_init().
    This function is invoked with interrupts locked.

Parameters

• dirty – [out] Whether the page to evict is dirty

Returns

The page frame to evict

void k_mem_paging_eviction_init(void)
    Initialization function.
    Called at POST_KERNEL to perform any necessary initialization tasks for the eviction algorithm. k_mem_paging_eviction_select() is guaranteed to never be called until this has returned, and this will only be called once.

Backing Store APIs

group mem-demand-paging-backing-store
    Backing store APIs.

Functions

int k_mem_paging_backing_store_location_get(struct z_page_frame *pf, uintptr_t *location, bool page_fault)
    Reserve or fetch a storage location for a data page loaded into a page frame.
    The returned location token must be unique to the mapped virtual address. This location will be used in the backing store to page out data page contents for later retrieval. The location value must be page-aligned.
    This function may be called multiple times on the same data page. If its page frame has its Z_PAGE_FRAME_BACKED bit set, it is expected to return the previous backing store location for the data page containing a cached clean copy. This clean copy may be updated on page-out, or used to discard clean pages without needing to write out their contents.
    If the backing store is full, some other backing store location which caches a loaded data page may be selected, in which case its associated page frame will have the Z_PAGE_FRAME_BACKED bit cleared (as it is no longer cached).
    pf->addr will indicate the virtual address the page is currently mapped to. Large, sparse backing stores which can contain the entire address space may simply generate location tokens purely as a function of pf->addr with no other management necessary.
    This function distinguishes whether it was called on behalf of a page fault. A free backing store location must always be reserved in order for page faults to succeed. If the page_fault parameter is not set, this function should return -ENOMEM even if one location is available.
    This function is invoked with interrupts locked.

Parameters
• pf – Virtual address to obtain a storage location
• location – [out] storage location token
• page_fault – Whether this request was for a page fault

Returns
0 Success

-ENOMEM Backing store is full

void k_mem_paging_backing_store_location_free(uintptr_t location)
Free a backing store location.

Any stored data may be discarded, and the location token associated with this address may be re-used for some other data page.

This function is invoked with interrupts locked.

Parameters
• location – Location token to free

void k_mem_paging_backing_store_page_out(uintptr_t location)
Copy a data page from Z_SCRATCH_PAGE to the specified location.

Immediately before this is called, Z_SCRATCH_PAGE will be mapped read-write to the intended source page frame for the calling context.

Calls to this and k_mem_paging_backing_store_page_in() will always be serialized, but interrupts may be enabled.

Parameters
• location – Location token for the data page, for later retrieval

void k_mem_paging_backing_store_page_in(uintptr_t location)
Copy a data page from the provided location to Z_SCRATCH_PAGE.

Immediately before this is called, Z_SCRATCH_PAGE will be mapped read-write to the intended destination page frame for the calling context.

Calls to this and k_mem_paging_backing_store_page_out() will always be serialized, but interrupts may be enabled.

Parameters
• location – Location token for the data page

void k_mem_paging_backing_store_page_finalize(struct z_page_frame *pf, uintptr_t location)
Update internal accounting after a page-in.

This is invoked after k_mem_paging_backing_store_page_in() and interrupts have been* re-locked, making it safe to access the z_page_frame data. The location value will be the same passed to k_mem_paging_backing_store_page_in().

The primary use-case for this is to update custom fields for the backing store in the page frame, to reflect where the data should be evicted to if it is paged out again. This may be a no-op in some implementations.

If the backing store caches paged-in data pages, this is the appropriate time to set the Z_PAGE_FRAME_BACKED bit. The kernel only skips paging out clean data pages if they are noted as clean in the page tables and the Z_PAGE_FRAME_BACKED bit is set in their associated page frame.

Parameters
• pf – Page frame that was loaded in
void k_mem_paging_backing_store_init(void)
  Backing store initialization function.
  The implementation may expect to receive page in/out calls as soon as this returns, but not before that. Called at POST_KERNEL.
  This function is expected to do two things:
  • Initialize any internal data structures and accounting for the backing store.
  • If the backing store already contains all or some loaded kernel data pages at boot time, Z_PAGE_FRAME_BACKED should be appropriately set for their associated page frames, and any internal accounting set up appropriately.

3.4.6 Virtual Memory

Virtual memory (VM) in Zephyr provides developers with the ability to fine tune access to memory. To utilize virtual memory, the platform must support Memory Management Unit (MMU) and it must be enabled in the build. Due to the target of Zephyr mainly being embedded systems, virtual memory support in Zephyr differs a bit from that in traditional operating systems:

Mapping of Kernel Image
  Default is to do 1:1 mapping for the kernel image (including code and data) between physical and virtual memory address spaces, if demand paging is not enabled. Deviation from this requires careful manipulation of linker script.

Secondary Storage
  Basic virtual memory support does not utilize secondary storage to extend usable memory. The maximum usable memory is the same as the physical memory.
  • Demand Paging enables utilizing secondary storage as a backing store for virtual memory, thus allowing larger usable memory than the available physical memory. Note that demand paging needs to be explicitly enabled.
  • Although the virtual memory space can be larger than physical memory space, without enabling demand paging, all virtually mapped memory must be backed by physical memory.

Kconfigs

Required  These are the Kconfigs that need to be enabled or defined for kernel to support virtual memory.
  • CONFIG_MMU: must be enabled for virtual memory support in kernel.
  • CONFIG_MMU_PAGE_SIZE: size of a memory page. Default is 4KB.
  • CONFIG_KERNEL_VM_BASE: base address of virtual address space.
  • CONFIG_KERNEL_VM_SIZE: size of virtual address space. Default is 8MB.
  • CONFIG_KERNEL_VM_OFFSET: kernel image starts at this offset from CONFIG_KERNEL_VM_BASE.

Optional
  • CONFIG_KERNEL_DIRECT_MAP: permits 1:1 mappings between virtual and physical addresses, instead of kernel choosing addresses within the virtual address space. This is useful for mapping device MMIO regions for more precise access control.
Memory Map Overview

This is an overview of the memory map of the virtual memory address space. Note that the \texttt{Z_*} macros, which are used in code, may have different meanings depending on architecture and Kconfigs, which will be explained below.

- \texttt{Z\_VIRT\_RAM\_START} is the beginning of the virtual memory address space. This needs to be page aligned. Currently, it is the same as \texttt{CONFIG\_KERNEL\_VM\_BASE}.

- \texttt{Z\_VIRT\_RAM\_SIZE} is the size of the virtual memory address space. This needs to be page aligned. Currently, it is the same as \texttt{CONFIG\_KERNEL\_VM\_SIZE}.

- \texttt{Z\_VIRT\_RAM\_END} is simply \texttt{(Z\_VIRT\_RAM\_START + Z\_VIRT\_RAM\_SIZE)}.

- \texttt{Z\_KERNEL\_VIRT\_START} is the same as \texttt{z\_mapped\_start} specified in the linker script. This is the virtual address of the beginning of the kernel image at boot time.

- \texttt{Z\_KERNEL\_VIRT\_END} is the same as \texttt{z\_mapped\_end} specified in the linker script. This is the virtual address of the end of the kernel image at boot time.

- \texttt{Z\_FREE\_VM\_START} is the beginning of the virtual address space where addresses can be allocated for memory mapping. This depends on whether \texttt{CONFIG\_ARCH\_MAPS\_ALL\_RAM} is enabled.
  - If it is enabled, which means all physical memory are mapped in virtual memory address space, and it is the same as \texttt{(CONFIG\_SRAM\_BASE\_ADDRESS + CONFIG\_SRAM\_SIZE)}.
  - If it is disabled, \texttt{Z\_FREE\_VM\_START} is the same \texttt{Z\_KERNEL\_VIRT\_END} which is the end of the kernel image.

- \texttt{Z\_VM\_RESERVED} is an area reserved to support kernel functions. For example, some addresses are reserved to support demand paging.

Virtual Memory Mappings

Setting up Mappings at Boot In general, most supported architectures set up the memory mappings at boot as following:

- \texttt{.text} section is read-only and executable. It is accessible in both kernel and user modes.
.rodata section is read-only and non-executable. It is accessible in both kernel and user modes.

Other kernel sections, such as .data, .bss and .noinit, are read-write and non-executable. They are only accessible in kernel mode.

- Stacks for user mode threads are automatically granted read-write access to their corresponding user mode threads during thread creation.
- Global variables, by default, are not accessible to user mode threads. Refer to Memory Domains and Partitions on how to use global variables in user mode threads, and on how to share data between user mode threads.

Caching modes for these mappings are architecture specific. They can be none, write-back, or write-through.

Note that SoCs have their own additional mappings required to boot where these mappings are defined under their own SoC configurations. These mappings usually include device MMIO regions needed to setup the hardware.

Mapping Anonymous Memory The unused physical memory can be mapped in virtual address space on demand. This is conceptually similar to memory allocation from heap, but these mappings must be aligned on page size and have finer access control.

- `k_mem_map()` can be used to map unused physical memory:
  - The requested size must be multiple of page size.
  - The address returned is inside the virtual address space between Z_FREE_VM_START and Z_VIRT_RAM_END.
  - The mapped region is not guaranteed to be physically contiguous in memory.
  - Guard pages immediately before and after the mapped virtual region are automatically allocated to catch access issue due to buffer underrun or overrun.

- The mapped region can be unmapped (i.e. freed) via `k_mem_unmap()`:
  - Caution must be exercised to give the pass the same region size to both `k_mem_map()` and `k_mem_unmap()`. The unmapping function does not check if it is a valid mapped region before unmapping.

API Reference

`group kernel_memory_management`
Kernel Memory Management.

Caching mode definitions.

These are mutually exclusive.

**K_MEM_CACHE_NONE**
No caching.
Most drivers want this.

**K_MEM_CACHE_WT**
Write-through caching.
Used by certain drivers.
K_MEM_CACHE_WB
    Full write-back caching.
    Any RAM mapped wants this.

K_MEM_CACHE_MASK
    Reserved bits for cache modes in k_map() flags argument.

Region permission attributes.

Default is read-only, no user, no exec

K_MEM_PERM_RW
    Region will have read/write access (and not read-only)

K_MEM_PERM_EXEC
    Region will be executable (normally forbidden)

K_MEM_PERM_USER
    Region will be accessible to user mode (normally supervisor-only)

Region mapping behaviour attributes

K_MEM_DIRECT_MAP
    Region will be mapped to 1:1 virtual and physical address.

k_mem_map() control flags

K_MEM_MAP_UNINIT
    The mapped region is not guaranteed to be zeroed.
    This may improve performance. The associated page frames may contain indeterminate data, zeroes, or even sensitive information.
    This may not be used with K_MEM_PERM_USER as there are no circumstances where this is safe.

K_MEM_MAP_LOCK
    Region will be pinned in memory and never paged.
    Such memory is guaranteed to never produce a page fault due to page-outs or copy-on-write once the mapping call has returned. Physical page frames will be pre-fetched as necessary and pinned.

Functions
size_t k_mem_free_get(void)
    Return the amount of free memory available.
    
The returned value will reflect how many free RAM page frames are available. If de-
mand paging is enabled, it may still be possible to allocate more.
    
The information reported by this function may go stale immediately if concurrent
memory mappings or page-ins take place.

    **Returns**
    Free physical RAM, in bytes

void *k_mem_map(size_t size, uint32_t flags)
    Map anonymous memory into Zephyr's address space.
    This function effectively increases the data space available to Zephyr. The kernel will
choose a base virtual address and return it to the caller. The memory will have access
permissions for all contexts set per the provided flags argument.
    
If user thread access control needs to be managed in any way, do not enable
K_MEM_PERM_USER flags here; instead manage the region's permissions with mem-
dory domain APIs after the mapping has been established. Setting K_MEM_PERM_USER
here will allow all user threads to access this memory which is usually undesirable.
    
Unless K_MEM_MAP_UNINIT is used, the returned memory will be zeroed.
    
The mapped region is not guaranteed to be physically contiguous in memory. Physi-
cally contiguous buffers should be allocated statically and pinned at build time.
    
Pages mapped in this way have write-back cache settings.
    
The returned virtual memory pointer will be page-aligned. The size parameter, and
any base address for re-mapping purposes must be page- aligned.
    
Note that the allocation includes two guard pages immediately before and after the
requested region. The total size of the allocation will be the requested size plus the
size of these two guard pages.

Many K_MEM_MAP_* flags have been implemented to alter the behavior of this func-
tion, with details in the documentation for these flags.

    **Parameters**
    
• **size** – Size of the memory mapping. This must be page-aligned.
• **flags** – K_MEM_PERM_*, K_MEM_MAP_ * control flags.

    **Returns**
    The mapped memory location, or NULL if insufficient virtual address
space, insufficient physical memory to establish the mapping, or insuffi-
cient memory for paging structures.

void k_mem_unmap(void *addr, size_t size)
    Un-map mapped memory.
    
This removes a memory mapping for the provided page-aligned region. Associated
page frames will be free and the kernel may re-use the associated virtual address re-
gion. Any paged out data pages may be discarded.
    
Calling this function on a region which was not mapped to begin with is undefined
behavior.

    **Parameters**
    
• **addr** – Page-aligned memory region base virtual address
• **size** – Page-aligned memory region size
size_t k_mem_region_align(uintptr_t *aligned_addr, size_t *aligned_size, uintptr_t addr, size_t size, size_t align)

Given an arbitrary region, provide a aligned region that covers it.

The returned region will have both its base address and size aligned to the provided alignment value.

Parameters
- aligned_addr – [out] Aligned address
- aligned_size – [out] Aligned region size
- addr – [in] Region base address
- size – [in] Region size
- align – [in] What to align the address and size to

Return values
offset – between aligned_addr and addr

3.5 Data Structures

Zephyr provides a library of common general purpose data structures used within the kernel, but useful by application code in general. These include list and balanced tree structures for storing ordered data, and a ring buffer for managing “byte stream” data in a clean way.

Note that in general, the collections are implemented as “intrusive” data structures. The “node” data is the only struct used by the library code, and it does not store a pointer or other metadata to indicate what user data is “owned” by that node. Instead, the expectation is that the node will be itself embedded within a user-defined struct. Macros are provided to retrieve a user struct address from the embedded node pointer in a clean way. The purpose behind this design is to allow the collections to be used in contexts where dynamic allocation is disallowed (i.e. there is no need to allocate node objects because the memory is provided by the user).

Note also that these libraries are uniformly unsynchronized; access to them is not threadsafe by default. These are data structures, not synchronization primitives. The expectation is that any locking needed will be provided by the user.

3.5.1 Single-linked List

Zephyr provides a `sys_slist_t` type for storing simple singly-linked list data (i.e. data where each list element stores a pointer to the next element, but not the previous one). This supports constant-time access to the first (head) and last (tail) elements of the list, insertion before the head and after the tail of the list and constant time removal of the head. Removal of subsequent nodes requires access to the “previous” pointer and thus can only be performed in linear time by searching the list.

The `sys_slist_t` struct may be instantiated by the user in any accessible memory. It should be initialized with either `sys_slist_init()` or by static assignment from SYS_SLIST_STATIC_INIT before use. Its interior fields are opaque and should not be accessed by user code.

The end nodes of a list may be retrieved with `sys_slist.peek_head()` and `sys_slist.peek_tail()`, which will return NULL if the list is empty, otherwise a pointer to a `sys_snore_t` struct.

The `sys_snore_t` struct represents the data to be inserted. In general, it is expected to be allocated/controlled by the user, usually embedded within a struct which is to be added to the list. The container struct pointer may be retrieved from a list node using `SYS_SLIST_CONTAINER`,
passing it the struct name of the containing struct and the field name of the node. Internally, the `sys_snnode_t` struct contains only a next pointer, which may be accessed with `sys_slist.peek.next()`.

Lists may be modified by adding a single node at the head or tail with `sys_slist.prepend()` and `sys_slist.append()`. They may also have a node added to an interior point with `sys_slist.insert()`, which inserts a new node after an existing one. Similarly `sys_slist.remove()` will remove a node given a pointer to its predecessor. These operations are all constant time.

Convenience routines exist for more complicated modifications to a list. `sys_slist.merge_slist()` will append an entire list to an existing one. `sys_slist.append_list()` will append a bounded subset of an existing list in constant time. And `sys_slist.find_and_remove()` will search a list (in linear time) for a given node and remove it if present.

Finally the slist implementation provides a set of “for each” macros that allows for iterating over a list in a natural way without needing to manually traverse the next pointers. `SYS_SLIST_FOR_EACH_NODE` will enumerate every node in a list given a local variable to store the node pointer. `SYS_SLIST_FOR_EACH_NODE_SAFE` behaves similarly, but has a more complicated implementation that requires an extra scratch variable for storage and allows the user to delete the iterated node during the iteration. Each of those macros also exists in a “container” variant (`SYS_SLIST_FOR_EACH_CONTAINER` and `SYS_SLIST_FOR_EACH_CONTAINER_SAFE`) which assigns a local variable of a type that matches the user’s container struct and not the node struct, performing the required offsets internally. And `SYS_SLIST_ITERATE_FROM_NODE` exists to allow for enumerating a node and all its successors only, without inspecting the earlier part of the list.

### Single-linked List Internals

The slist code is designed to be minimal and conventional. Internally, a `sys_slist_t` struct is nothing more than a pair of “head” and “tail” pointer fields. And a `sys_snnode_t` stores only a single “next” pointer.

![Fig. 4: An slist containing three elements.](image1)

![Fig. 5: An empty slist](image2)

The specific implementation of the list code, however, is done with an internal “Z_GENLIST” template API which allows for extracting those fields from arbitrary structures and emits an arbitrarily named set of functions. This allows for implementing more complicated single-linked list variants using the same basic primitives. The genlist implementor is responsible for a custom
implementation of the primitive operations only: an “init” step for each struct, and a “get” and “set” primitives for each of head, tail and next pointers on their relevant structs. These inline functions are passed as parameters to the genlist macro expansion.

Only one such variant, sflist, exists in Zephyr at the moment.

Flagged List

The sys_sflist_t is implemented using the described genlist template API. With the exception of symbol naming (“sflist” instead of “slist”) and the additional API described next, it operates in all ways identically to the slist API.

It adds the ability to associate exactly two bits of user defined “flags” with each list node. These can be accessed and modified with sys_sfnode_flags_get() and sys_sfnode_flags_set(). Internally, the flags are stored unioned with the bottom bits of the next pointer and incur no SRAM storage overhead when compared with the simpler slist code.

Single-linked List API Reference

group single-linked-list_apis

Single-linked list implementation.

Single-linked list implementation using inline macros/functions. This API is not thread safe, and thus if a list is used across threads, calls to functions must be protected with synchronization primitives.

Defines

SYS_SLIST_FOR_EACH_NODE(__sl, __sn)

Provide the primitive to iterate on a list Note: the loop is unsafe and thus __sn should not be removed.

User MUST add the loop statement curly braces enclosing its own code:

```
SYS_SLIST_FOR_EACH_NODE(l, n) {
    <user code>
}
```

This and other SYS_SLIST_*() macros are not thread safe.

Parameters

- __sl – A pointer on a sys_slist_t to iterate on
- __sn – A sys_snnode_t pointer to peek each node of the list

SYS_SLIST_ITERATE_FROM_NODE(__sl, __sn)

Provide the primitive to iterate on a list, from a node in the list Note: the loop is unsafe and thus __sn should not be removed.

User MUST add the loop statement curly braces enclosing its own code:

```
SYS_SLIST_ITERATE_FROM_NODE(l, n) {
    <user code>
}
```

Like SYS_SLIST_FOR_EACH_NODE(), but __sn already contains a node in the list where to start searching for the next entry from. If NULL, it starts from the head.

This and other SYS_SLIST_*() macros are not thread safe.
Parameters

- __sl – A pointer on a sys_slist_t to iterate on
- __sn – A sys_snnode_t pointer to peek each node of the list it contains the starting node, or NULL to start from the head

SYS_SLIST_FOR_EACH_NODE_SAFE(__sl, __sn, __sns)

Provide the primitive to safely iterate on a list Note: __sn can be removed, it will not break the loop.

User MUST add the loop statement curly braces enclosing its own code:

```c
SYS_SLIST_FOR_EACH_NODE_SAFE(l, n, s) {
    <user code>
}
```

This and other SYS_SLIST_*() macros are not thread safe.

Parameters

- __sl – A pointer on a sys_slist_t to iterate on
- __sn – A sys_snnode_t pointer to peek each node of the list
- __sns – A sys_snnode_t pointer for the loop to run safely

SYS_SLIST_CONTAINER(__ln, __cn, __n)

Provide the primitive to resolve the container of a list node Note: it is safe to use with NULL pointer nodes.

Parameters

- __ln – A pointer on a sys_node_t to get its container
- __cn – Container struct type pointer
- __n – The field name of sys_node_t within the container struct

SYS_SLIST_PEEK_HEAD_CONTAINER(__sl, __cn, __n)

Provide the primitive to peek container of the list head.

Parameters

- __sl – A pointer on a sys_slist_t to peek
- __cn – Container struct type pointer
- __n – The field name of sys_node_t within the container struct

SYS_SLIST_PEEK_TAIL_CONTAINER(__sl, __cn, __n)

Provide the primitive to peek container of the list tail.

Parameters

- __sl – A pointer on a sys_slist_t to peek
- __cn – Container struct type pointer
- __n – The field name of sys_node_t within the container struct

SYS_SLIST_PEEK_NEXT_CONTAINER(__cn, __n)

Provide the primitive to peek the next container.

Parameters

- __cn – Container struct type pointer
- __n – The field name of sys_node_t within the container struct
SYS_SLIST_FOR_EACH_CONTAINER((__sl, __cn, __n))
Provide the primitive to iterate on a list under a container Note: the loop is unsafe and thus __cn should not be detached.
User **MUST** add the loop statement curly braces enclosing its own code:

```c
SYS_SLIST_FOR_EACH_CONTAINER(l, c, n) {
    <user code>
}
```

**Parameters**
- __sl – A pointer on a sys_slist_t to iterate on
- __cn – A pointer to peek each entry of the list
- __n – The field name of sys_node_t within the container struct

SYS_SLIST_FOR_EACH_CONTAINER_SAFE((__sl, __cn, __cns, __n))
Provide the primitive to safely iterate on a list under a container Note: __cn can be detached, it will not break the loop.
User **MUST** add the loop statement curly braces enclosing its own code:

```c
SYS_SLIST_FOR_EACH_NODE_SAFE(l, c, cn, n) {
    <user code>
}
```

**Parameters**
- __sl – A pointer on a sys_slist_t to iterate on
- __cn – A pointer to peek each entry of the list
- __cns – A pointer for the loop to run safely
- __n – The field name of sys_node_t within the container struct

SYS_SLIST_STATIC_INIT(ptr_to_list)
Statically initialize a single-linked list.

**Parameters**
- ptr_to_list – A pointer on the list to initialize

**Typedefs**

typedef struct _snode sys_snodet
Single-linked list node structure.

typedef struct _slist sys_slist_t
Single-linked list structure.

**Functions**

static inline void sys_slist_init(sys_slist_t *list)
Initialize a list.

**Parameters**
• list – A pointer on the list to initialize

static inline sys_snode_t *sys_slist_peek_head(sys_slist_t *list)
Peek the first node from the list.

Parameters
• list – A pointer on the list to peek the first node from

Returns
A pointer on the first node of the list (or NULL if none)

static inline sys_snode_t *sys_slist_peek_tail(sys_slist_t *list)
Peek the last node from the list.

Parameters
• list – A pointer on the list to peek the last node from

Returns
A pointer on the last node of the list (or NULL if none)

static inline bool sys_slist_is_empty(sys_slist_t *list)
Test if the given list is empty.

Parameters
• list – A pointer on the list to test

Returns
a boolean, true if it's empty, false otherwise

static inline sys_snode_t *sys_slist_peek_next_no_check(sys_node_t *node)
Peek the next node from current node, node is not NULL.
Faster then sys_slist_peek_next() if node is known not to be NULL.

Parameters
• node – A pointer on the node where to peek the next node

Returns
a pointer on the next node (or NULL if none)

static inline void sys_slist_prepend(sys_slist_t *list, sys_snode_t *node)
Prepend a node to the given list.
This and other sys_slist_*() functions are not thread safe.

Parameters
• list – A pointer on the list to affect
• node – A pointer on the node to prepend

static inline void sys_slist_append(sys_slist_t *list, sys_snode_t *node)
Append a node to the given list.
This and other sys_slist_*() functions are not thread safe.

Parameters
static inline void sys_slist_append_list(sys_slist_t *list, void *head, void *tail)
    Append a list to the given list.
    Append a singly-linked, NULL-terminated list consisting of nodes containing the
    pointer to the next node as the first element of a node, to list. This and other sys_slist_*() functions are not thread safe.
    FIXME: Why are the element parameters void *?

    Parameters
    • list – A pointer on the list to affect
    • head – A pointer on the node to append
    • tail – A pointer on the node to append

static inline void sys_slist_merge_slist(sys_slist_t *list, sys_slist_t *list_to_append)
    merge two slists, appending the second one to the first
    When the operation is completed, the appending list is empty. This and other
    sys_slist_*() functions are not thread safe.

    Parameters
    • list – A pointer on the list to affect
    • list_to_append – A pointer to the list to append.

static inline void sys_slist_insert(sys_slist_t *list, sys_snode_t *prev, sys_snode_t *node)
    Insert a node to the given list.
    This and other sys_slist_*() functions are not thread safe.

    Parameters
    • list – A pointer on the list to affect
    • prev – A pointer on the previous node
    • node – A pointer on the node to insert

static inline sys_snode_t *sys_slist_get_not_empty(sys_slist_t *list)
    Fetch and remove the first node of the given list.
    List must be known to be non-empty. This and other sys_slist_*() functions are not
    thread safe.

    Parameters
    • list – A pointer on the list to affect

Returns
    A pointer to the first node of the list

static inline sys_snode_t *sys_slist_get(sys_slist_t *list)
    Fetch and remove the first node of the given list.
    This and other sys_slist_*() functions are not thread safe.

    Parameters
    • list – A pointer on the list to affect

Returns
    A pointer to the first node of the list (or NULL if empty)
static inline void sys_slist_remove(sys_slist_t *list, sys_snode_t *prev_node, sys_snode_t *node)

Remove a node.
This and other sys_slist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect
- prev_node – A pointer on the previous node (can be NULL, which means
  the node is the list's head)
- node – A pointer on the node to remove

static inline bool sys_slist_find_and_remove(sys_slist_t *list, sys_snode_t *node)

Find and remove a node from a list.
This and other sys_slist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect
- node – A pointer on the node to remove from the list

Returns
true if node was removed

static inline size_t sys_slist_len(sys_slist_t *list)

Compute the size of the given list in O(n) time.

Parameters
- list – A pointer on the list

Returns
an integer equal to the size of the list, or 0 if empty

Flagged List API Reference

Flagged single-linked list implementation.

Similar to Single-linked list with the added ability to define two bits of user “flags” for
each node. They can be accessed and modified using the sys_sfnode_flags_get() and
sys_sfnode_flags_set() APIs.

Flagged single-linked list implementation using inline macros/functions. This API is not
thread safe, and thus if a list is used across threads, calls to functions must be protected
with synchronization primitives.

Defines

SYS_SFLIST_FOR_EACH_NODE(__sl, __sn)

Provide the primitive to iterate on a list Note: the loop is unsafe and thus __sn should
not be removed.

User MUST add the loop statement curly braces enclosing its own code:

SYS_SFLIST_FOR_EACH_NODE(1, n) {
  <user code>
}
This and other SYS_SFLIST_*() macros are not thread safe.

**Parameters**
- __sl – A pointer on a sys_sflist_t to iterate on
- __sn – A sys_sfnode_t pointer to peek each node of the list

SYS_SFLIST_ITERATE_FROM_NODE(__sl, __sn)

Provide the primitive to iterate on a list, from a node in the list Note: the loop is unsafe and thus __sn should not be removed.

User *MUST* add the loop statement curly braces enclosing its own code:

```c
SYS_SFLIST_ITERATE_FROM_NODE(l, n) {
    <user code>
}
```

Like SYS_SFLIST_FOR_EACH_NODE(), but __dn already contains a node in the list where to start searching for the next entry from. If NULL, it starts from the head.

This and other SYS_SFLIST_*() macros are not thread safe.

**Parameters**
- __sl – A pointer on a sys_sflist_t to iterate on
- __sn – A sys_sfnode_t pointer to peek each node of the list it contains the starting node, or NULL to start from the head

SYS_SFLIST_FOR_EACH_NODE_SAFE(__sl, __sn, __sns)

Provide the primitive to safely iterate on a list Note: __sn can be removed, it will not break the loop.

User *MUST* add the loop statement curly braces enclosing its own code:

```c
SYS_SFLIST_FOR_EACH_NODE_SAFE(l, n, s) {
    <user code>
}
```

This and other SYS_SFLIST_*() macros are not thread safe.

**Parameters**
- __sl – A pointer on a sys_sflist_t to iterate on
- __sn – A sys_sfnode_t pointer to peek each node of the list
- __sns – A sys_sfnode_t pointer for the loop to run safely

SYS_SFLIST_CONTAINER(__ln, __cn, __n)

Provide the primitive to resolve the container of a list node Note: it is safe to use with NULL pointer nodes.

**Parameters**
- __ln – A pointer on a sys_sfnode_t to get its container
- __cn – Container struct type pointer
- __n – The field name of sys_sfnode_t within the container struct

SYS_SFLIST_PEEK_HEAD_CONTAINER(__sl, __cn, __n)

Provide the primitive to peek container of the list head.

**Parameters**
- __sl – A pointer on a sys_sflist_t to peek
- __cn – Container struct type pointer
• __n – The field name of sys_sfnode_t within the container struct

SYS_SFLIST_PEEK_TAIL_CONTAINER(__sl, __cn, __n)
Provide the primitive to peek container of the list tail.

**Parameters**

• __sl – A pointer on a sys_sflist_t to peek
• __cn – Container struct type pointer
• __n – The field name of sys_sfnode_t within the container struct

SYS_SFLIST_PEEK_NEXT_CONTAINER(__cn, __n)
Provide the primitive to peek the next container.

**Parameters**

• __cn – Container struct type pointer
• __n – The field name of sys_sfnode_t within the container struct

SYS_SFLIST_FOR_EACH_CONTAINER(__sl, __cn, __n)
Provide the primitive to iterate on a list under a container Note: the loop is unsafe and thus __cn should not be detached.

User **MUST** add the loop statement curly braces enclosing its own code:

```c
SYS_SFLIST_FOR_EACH_CONTAINER(l, c, n) {
    <user code>
}
```

**Parameters**

• __sl – A pointer on a sys_sflist_t to iterate on
• __cn – A pointer to peek each entry of the list
• __n – The field name of sys_sfnode_t within the container struct

SYS_SFLIST_FOR_EACH_CONTAINER_SAFE(__sl, __cn, __cns, __n)
Provide the primitive to safely iterate on a list under a container Note: __cn can be detached, it will not break the loop.

User **MUST** add the loop statement curly braces enclosing its own code:

```c
SYS_SFLIST_FOR_EACH_NODE_SAFE(l, c, cn, n) {
    <user code>
}
```

**Parameters**

• __sl – A pointer on a sys_sflist_t to iterate on
• __cn – A pointer to peek each entry of the list
• __cns – A pointer for the loop to run safely
• __n – The field name of sys_sfnode_t within the container struct

SYS_SFLIST_STATIC_INIT(ptr_to_list)
Statically initialize a flagged single-linked list.

**Parameters**

• ptr_to_list – A pointer on the list to initialize
typedef uint32_t unative_t

typedef struct _sfnode sys_sfnode_t
    Flagged single-linked list node structure.

typedef struct _sflist sys_sflist_t
    Flagged single-linked list structure.

Functions

static inline void sys_sflist_init(sys_sflist_t *list)
    Initialize a list.

    Parameters
    • list – A pointer on the list to initialize

static inline uint8_t sys_sfnode_flags_get(sys_sfnode_t *node)
    Fetch flags value for a particular sfnode.

    Parameters
    • node – A pointer to the node to fetch flags from

    Returns
    The value of flags, which will be between 0 and 3

static inline sys_sfnode_t *sys_sflist_peek_head(sys_sflist_t *list)
    Peek the first node from the list.

    Parameters
    • list – A point on the list to peek the first node from

    Returns
    A pointer on the first node of the list (or NULL if none)

static inline sys_sfnode_t *sys_sflist_peek_tail(sys_sflist_t *list)
    Peek the last node from the list.

    Parameters
    • list – A point on the list to peek the last node from

    Returns
    A pointer on the last node of the list (or NULL if none)

static inline void sys_sfnode_init(sys_sfnode_t *node, uint8_t flags)
    Initialize an sflist node.

    Set an initial flags value for this slist node, which can be a value between 0 and 3.
    These flags will persist even if the node is moved around within a list, removed, or
    transplanted to a different slist.

    This is ever so slightly faster than sys_sfnode_flags_set() and should only be used on a
    node that hasn't been added to any list.
**Parameters**

- **node** – A pointer to the node to set the flags on
- **flags** – A value between 0 and 3 to set the flags value

static inline void **sys_sfnode_flags_set**(*sys_sfnode_t* node, uint8_t flags)
Set flags value for an sfnode node.

Set a flags value for this slist node, which can be a value between 0 and 3. These flags will persist even if the node is moved around within a list, removed, or transplanted to a different slist.

**Parameters**

- **node** – A pointer to the node to set the flags on
- **flags** – A value between 0 and 3 to set the flags value

static inline bool **sys_sflist_is_empty**(*sys_sflist_t* list)
Test if the given list is empty.

**Parameters**

- **list** – A pointer on the list to test

**Returns**
a boolean, true if it's empty, false otherwise

static inline **sys_sfnode_t** * **sys_sflist_peek_next_no_check**(*sys_sfnode_t* node)
Peek the next node from current node, node is not NULL.

Faster then **sys_sflist_peek_next()** if node is known not to be NULL.

**Parameters**

- **node** – A pointer on the node where to peek the next node

**Returns**
a pointer on the next node (or NULL if none)

static inline **sys_sfnode_t** * **sys_sflist_peek_next**(*sys_sfnode_t* node)
Peek the next node from current node.

**Parameters**

- **node** – A pointer on the node where to peek the next node

**Returns**
a pointer on the next node (or NULL if none)

static inline void **sys_sflist_prepend**(*sys_sflist_t* list, **sys_sfnode_t** *node)
Prepend a node to the given list.

This and other sys_sflist_*() functions are not thread safe.

**Parameters**

- **list** – A pointer on the list to affect
- **node** – A pointer on the node to prepend

static inline void **sys_sflist_append**(*sys_sflist_t* list, **sys_sfnode_t** *node)
Append a node to the given list.

This and other sys_sflist_*() functions are not thread safe.

**Parameters**

- **list** – A pointer on the list to affect
- **node** – A pointer on the node to append
static inline void **sys_sflist_append_list**

Append a list to the given list.

Append a singly-linked, NULL-terminated list consisting of nodes containing the pointer to the next node as the first element of a node, to **list**. This and other sys_sflist_*() functions are not thread safe.

FIXME: Why are the element parameters void *?

**Parameters**

- **list** – A pointer on the list to affect
- **head** – A pointer to the first element of the list to append
- **tail** – A pointer to the last element of the list to append

static inline void **sys_sflist_merge_sflist**

merge two sflists, appending the second one to the first

When the operation is completed, the appending list is empty. This and other sys_sflist_*() functions are not thread safe.

**Parameters**

- **list** – A pointer on the list to affect
- **list_to_append** – A pointer to the list to append.

static inline void **sys_sflist_insert**

Insert a node to the given list.

This and other sys_sflist_*() functions are not thread safe.

**Parameters**

- **list** – A pointer on the list to affect
- **prev** – A pointer on the previous node
- **node** – A pointer on the node to insert

static inline **sys_sfnode_t** **sys_sflist_get_not_empty**

Fetch and remove the first node of the given list.

List must be known to be non-empty. This and other sys_sflist_*() functions are not thread safe.

**Parameters**

- **list** – A pointer on the list to affect

**Returns**

A pointer to the first node of the list

static inline **sys_sfnode_t** **sys_sflist_get**

Fetch and remove the first node of the given list.

This and other sys_sflist_*() functions are not thread safe.

**Parameters**

- **list** – A pointer on the list to affect

**Returns**

A pointer to the first node of the list (or NULL if empty)
static inline void sys_sflist_remove(sys_sflist_t *list, sys_sfnode_t *prev_node, sys_sfnode_t *node)

Remove a node.
This and other sys_sflist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect
- prev_node – A pointer on the previous node (can be NULL, which means
  the node is the list's head)
- node – A pointer on the node to remove

static inline bool sys_sflist_find_and_remove(sys_sflist_t *list, sys_sfnode_t *node)

Find and remove a node from a list.
This and other sys_sflist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect
- node – A pointer on the node to remove from the list

Returns
true if node was removed

static inline size_t sys_sflist_len(sys_sflist_t *list)

Compute the size of the given list in O(n) time.

Parameters
- list – A pointer on the list

Returns
an integer equal to the size of the list, or 0 if empty

3.5.2 Double-linked List

Similar to the single-linked list in many respects, Zephyr includes a double-linked implementa-
tion. This provides the same algorithmic behavior for all the existing slist operations, but also
allows for constant-time removal and insertion (at all points: before or after the head, tail or any
internal node). To do this, the list stores two pointers per node, and thus has somewhat higher
runtime code and memory space needs.

A sys_dlist_t struct may be instantiated by the user in any accessible memory. It must be ini-
tialized with sys_dlist_init() or SYS_DLIST_STATIC_INIT before use. The sys_dnode_t struct
is expected to be provided by the user for any nodes added to the list (typically embedded within
the struct to be tracked, as described above). It must be initialized in zeroed/bss memory or with
sys_dnode_init() before use.

Primitive operations may retrieve the head/tail of a list and the next/prev pointers of
a node with sys_dlist.peek_head(), sys_dlist.peek_tail(), sys_dlist.peek_next() and
sys_dlist.peek_prev(). These can all return NULL where appropriate (i.e. for empty lists, or
nodes at the endpoints of the list).

A dlist can be modified in constant time by removing a node with sys_dlist_remove(), by adding
a node to the head or tail of a list with sys_dlist.prepend() and sys_dlist.append(), or by
inserting a node before an existing node with sys_dlist_insert().

As for slist, each node in a dlist can be processed in a natural code block style using
SYS_DLIST_FOR_EACH_NODE. This macro also exists in a "FROM_NODE" form which allows for it-
erating from a known starting point, a “SAFE” variant that allows for removing the node being
inspected within the code block, a “CONTAINER” style that provides the pointer to a containing struct instead of the raw node, and a “CONTAINER_SAFE” variant that provides both properties.

Convenience utilities provided by dlist include `sys_dlist_insert_at()`, which inserts a node that linearly searches through a list to find the right insertion point, which is provided by the user as a C callback function pointer, and `sys_dnode_is_linked()`, which will affirmatively return whether or not a node is currently linked into a dlist or not (via an implementation that has zero overhead vs. the normal list processing).

**Double-linked List Internals**

Internally, the dlist implementation is minimal: the `sys_dlist_t` struct contains “head” and “tail” pointer fields, the `sys_dnode_t` contains “prev” and “next” pointers, and no other data is stored. But in practice the two structs are internally identical, and the list struct is inserted as a node into the list itself. This allows for a very clean symmetry of operations:

- An empty list has backpointers to itself in the list struct, which can be trivially detected.
- The head and tail of the list can be detected by comparing the prev/next pointers of a node vs. the list struct address.
- An insertion or deletion never needs to check for the special case of inserting at the head or tail. There are never any NULL pointers within the list to be avoided. Exactly the same operations are run, without tests or branches, for all list modification primitives.

Effectively, a dlist of N nodes can be thought of as a “ring” of “N+1” nodes, where one node represents the list tracking struct.

![Fig. 6: A dlist containing three elements. Note that the list struct appears as a fourth “element” in the list.](image)

![Fig. 7: An dlist containing just one element.](image)
Doubly-linked List API Reference

**group doubly-linked-list_apis**

Doubly-linked list implementation.

Doubly-linked list implementation using inline macros/functions. This API is not thread safe, and thus if a list is used across threads, calls to functions must be protected with synchronization primitives.

The lists are expected to be initialized such that both the head and tail pointers point to the list itself. Initializing the lists in such a fashion simplifies the adding and removing of nodes to/from the list.

**Defines**

SYS_DLIST_FOR_EACH_NODE(__dl, __dn)

Provide the primitive to iterate on a list Note: the loop is unsafe and thus __dn should not be removed.

User **MUST** add the loop statement curly braces enclosing its own code:

```
SYS_DLIST_FOR_EACH_NODE(l, n) {
  <user code>
}
```

This and other SYS_DLIST_*() macros are not thread safe.

**Parameters**

- **__dl** – A pointer on a sys_dlist_t to iterate on
• \texttt{__dn} – A \texttt{sys_dnode_t} pointer to peek each node of the list

\texttt{SYS_DLIST ITERATE FROM NODE(__dl, __dn)}

Provide the primitive to iterate on a list, from a node in the list Note: the loop is unsafe and thus \texttt{__dn} should not be removed.

User \textbf{MUST} add the loop statement curly braces enclosing its own code:

\begin{verbatim}
SYS_DLIST_ITERATE_FROM_NODE(l, n) {
    <user code>
}
\end{verbatim}

Like \texttt{SYS_DLIST FOR EACH NODE()}, but \texttt{__dn} already contains a node in the list where to start searching for the next entry from. If NULL, it starts from the head.

This and other \texttt{SYS_DLIST_\*()} macros are not thread safe.

\textbf{Parameters}

• \texttt{__dl} – A pointer on a \texttt{sys_dlist_t} to iterate on
• \texttt{__dn} – A \texttt{sys_dnode_t} pointer to peek each node of the list; it contains the starting node, or NULL to start from the head

\texttt{SYS_DLIST FOR EACH NODE SAFE(__dl, __dn, __dns)}

Provide the primitive to safely iterate on a list Note: \texttt{__dn} can be removed, it will not break the loop.

User \textbf{MUST} add the loop statement curly braces enclosing its own code:

\begin{verbatim}
SYS_DLIST_FOR_EACH_NODE_SAFE(l, n, s) {
    <user code>
}
\end{verbatim}

This and other \texttt{SYS_DLIST_\*()} macros are not thread safe.

\textbf{Parameters}

• \texttt{__dl} – A pointer on a \texttt{sys_dlist_t} to iterate on
• \texttt{__dn} – A \texttt{sys_dnode_t} pointer to peek each node of the list
• \texttt{__dns} – A \texttt{sys_dnode_t} pointer for the loop to run safely

\texttt{SYS_DLIST CONTAINER(__dn, __cn, __n)}

Provide the primitive to resolve the container of a list node Note: it is safe to use with NULL pointer nodes.

\textbf{Parameters}

• \texttt{__dn} – A pointer on a \texttt{sys_dnode_t} to get its container
• \texttt{__cn} – Container struct type pointer
• \texttt{__n} – The field name of \texttt{sys_dnode_t} within the container struct

\texttt{SYS_DLIST PEEK HEAD CONTAINER(__dl, __cn, __n)}

Provide the primitive to peek container of the list head.

\textbf{Parameters}

• \texttt{__dl} – A pointer on a \texttt{sys_dlist_t} to peek
• \texttt{__cn} – Container struct type pointer
• \texttt{__n} – The field name of \texttt{sys_dnode_t} within the container struct
SYS_DLIST_PEEK_NEXT_CONTAINER(__dl, __cn, __n)

Provide the primitive to peek the next container.

**Parameters**

- __dl – A pointer on a sys_dlist_t to peek
- __cn – Container struct type pointer
- __n – The field name of sys_dnode_t within the container struct

SYS_DLIST_FOR_EACH_CONTAINER(__dl, __cn, __n)

Provide the primitive to iterate on a list under a container Note: the loop is unsafe and thus __cn should not be detached.

User *MUST* add the loop statement curly braces enclosing its own code:

```c
SYS_DLIST_FOR_EACH_CONTAINER(l, c, n) {
    <user code>
}
```

**Parameters**

- __dl – A pointer on a sys_dlist_t to iterate on
- __cn – A container struct type pointer to peek each entry of the list
- __n – The field name of sys_dnode_t within the container struct

SYS_DLIST_FOR_EACH_CONTAINER_SAFE(__dl, __cn, __cns, __n)

Provide the primitive to safely iterate on a list under a container Note: __cn can be detached, it will not break the loop.

User *MUST* add the loop statement curly braces enclosing its own code:

```c
SYS_DLIST_FOR_EACH_CONTAINER_SAFE(l, c, cn, n) {
    <user code>
}
```

**Parameters**

- __dl – A pointer on a sys_dlist_t to iterate on
- __cn – A container struct type pointer to peek each entry of the list
- __cns – A container struct type pointer for the loop to run safely
- __n – The field name of sys_dnode_t within the container struct

SYS_DLIST_STATIC_INIT(ptr_to_list)

Static initializer for a doubly-linked list.

**Typedefs**

typedef struct_dnode sys_dlist_t

Doubly-linked list structure.

typedef struct_dnode sys_dnode_t

Doubly-linked list node structure.
Functions

static inline void sys_dlist_init(sys_dlist_t *list)
initialize list to its empty state

Parameters
• list – the doubly-linked list

static inline void sys_dnode_init(sys_dnode_t *node)
initialize node to its state when not in a list

Parameters
• node – the node

static inline bool sys_dnode_is_linked(const sys_dnode_t *node)
check if a node is a member of any list

Parameters
• node – the node

Returns
true if node is linked into a list, false if it is not

static inline bool sys_dlist_is_head(sys_dlist_t *list, sys_dnode_t *node)
check if a node is the list’s head

Parameters
• list – the doubly-linked list to operate on
• node – the node to check

Returns
true if node is the head, false otherwise

static inline bool sys_dlist_is_tail(sys_dlist_t *list, sys_dnode_t *node)
check if a node is the list’s tail

Parameters
• list – the doubly-linked list to operate on
• node – the node to check

Returns
true if node is the tail, false otherwise

static inline bool sys_dlist_is_empty(sys_dlist_t *list)
check if the list is empty

Parameters
• list – the doubly-linked list to operate on

Returns
true if empty, false otherwise

static inline bool sys_dlist_has_multiple_nodes(sys_dlist_t *list)
check if more than one node present

This and other sys_dlist_*() functions are not thread safe.

Parameters
• list – the doubly-linked list to operate on
Returns
true if multiple nodes, false otherwise

static inline sys_dnode_t *sys_dlist_peek_head(sys_dlist_t *list)
get a reference to the head item in the list

Parameters
• list – the doubly-linked list to operate on

Returns
a pointer to the head element, NULL if list is empty

static inline sys_dnode_t *sys_dlist_peek_head_not_empty(sys_dlist_t *list)
get a reference to the head item in the list
The list must be known to be non-empty.

Parameters
• list – the doubly-linked list to operate on

Returns
a pointer to the head element

static inline sys_dnode_t *sys_dlist_peek_next_no_check(sys_dlist_t *list, sys_dnode_t *node)
get a reference to the next item in the list, node is not NULL
Faster than sys_dlist_peek_next() if node is known not to be NULL.

Parameters
• list – the doubly-linked list to operate on
• node – the node from which to get the next element in the list

Returns
a pointer to the next element from a node, NULL if node is the tail

static inline sys_dnode_t *sys_dlist_peek_next(sys_dlist_t *list, sys_dnode_t *node)
get a reference to the next item in the list

Parameters
• list – the doubly-linked list to operate on
• node – the node from which to get the next element in the list

Returns
a pointer to the next element from a node, NULL if node is the tail or NULL
(when node comes from reading the head of an empty list).

static inline sys_dnode_t *sys_dlist_peek_prev_no_check(sys_dlist_t *list, sys_dnode_t *node)
get a reference to the previous item in the list, node is not NULL
Faster than sys_dlist_peek_prev() if node is known not to be NULL.

Parameters
• list – the doubly-linked list to operate on
• node – the node from which to get the previous element in the list

Returns
a pointer to the previous element from a node, NULL if node is the tail
static inline sys_dnode_t *sys_dlist_peek_prev(sys_dlist_t *list, sys_dnode_t *node)
get a reference to the previous item in the list

**Parameters**
- **list** – the doubly-linked list to operate on
- **node** – the node from which to get the previous element in the list

**Returns**
a pointer to the previous element from a node, NULL if node is the tail or
NULL (when node comes from reading the head of an empty list).

static inline sys_dnode_t *sys_dlist_peek_tail(sys_dlist_t *list)
get a reference to the tail item in the list

**Parameters**
- **list** – the doubly-linked list to operate on

**Returns**
a pointer to the tail element, NULL if list is empty

static inline void sys_dlist_append(sys_dlist_t *list, sys_dnode_t *node)
add node to tail of list

This and other sys_dlist_*() functions are not thread safe.

**Parameters**
- **list** – the doubly-linked list to operate on
- **node** – the element to append

static inline void sys_dlist_prepend(sys_dlist_t *list, sys_dnode_t *node)
add node to head of list

This and other sys_dlist_*() functions are not thread safe.

**Parameters**
- **list** – the doubly-linked list to operate on
- **node** – the element to append

static inline void sys_dlist_insert(sys_dnode_t *successor, sys_dnode_t *node)
Insert a node into a list.

Insert a node before a specified node in a dlist.

**Parameters**
- **successor** – the position before which “node” will be inserted
- **node** – the element to insert

static inline void sys_dlist_insert_at(sys_dlist_t *list, sys_dnode_t *node, int (*cond)(sys_dnode_t *node, void *data), void *data)
insert node at position

Insert a node in a location depending on an external condition. The cond() function
checks if the node is to be inserted before the current node against which it is checked.
This and other sys_dlist_*() functions are not thread safe.

**Parameters**
- **list** – the doubly-linked list to operate on
- **node** – the element to insert
• cond – a function that determines if the current node is the correct insert point
• data – parameter to cond()

static inline void sys_dlist_remove(sys_dnode_t *node)
remove a specific node from a list

The list is implicit from the node. The node must be part of a list. This and other sys_dlist_*() functions are not thread safe.

Parameters
• node – the node to remove

static inline sys_dnode_t *sys_dlist_get(sys_dlist_t *list)
get the first node in a list

This and other sys_dlist_*() functions are not thread safe.

Parameters
• list – the doubly-linked list to operate on

Returns
the first node in the list, NULL if list is empty

static inline size_t sys_dlist_len(sys_dlist_t *list)
Compute the size of the given list in O(n) time.

Parameters
• list – A pointer on the list

Returns
an integer equal to the size of the list, or 0 if empty

3.5.3 Multi Producer Single Consumer Packet Buffer

A Multi Producer Single Consumer Packet Buffer (MPSC_PBUF) is a circular buffer, whose contents are stored in first-in-first-out order. Variable size packets are stored in the buffer. Packet buffer works under assumption that there is a single context that consumes the data. However, it is possible that another context may interfere to flush the data and never come back (panic case). Packet is produced in two steps: first requested amount of data is allocated, producer fills the data and commits it. Consuming a packet is also performed in two steps: consumer claims the packet, gets pointer to it and length and later on packet is freed. This approach reduces memory copying.

A MPSC Packet Buffer has the following key properties:

• Allocate, commit scheme used for packet producing.
• Claim, free scheme used for packet consuming.
• Allocator ensures that contiguous memory of requested length is allocated.
• Following policies can be applied when requested space cannot be allocated:
  – Overwrite - oldest entries are dropped until requested amount of memory can be allocated. For each dropped packet user callback is called.
  – No overwrite - When requested amount of space cannot be allocated, allocation fails.
• Dedicated, optimized API for storing short packets.
• Allocation with timeout.
Internals

Each packet in the buffer contains MPSC_PBUF specific header which is used for internal management. Header consists of 2 bit flags. In order to optimize memory usage, header can be added on top of the user header using MPSC_PBUF_HDR and remaining bits in the first word can be application specific. Header consists of following flags:

- valid - bit set to one when packet contains valid user packet
- busy - bit set when packet is being consumed (claimed but not free)

Header state:

<table>
<thead>
<tr>
<th>valid</th>
<th>busy</th>
<th>description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>space is free</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>valid packet</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>claimed valid packet</td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>internal skip packet</td>
</tr>
</tbody>
</table>

Packet buffer space contains free space, valid user packets and internal skip packets. Internal skip packets indicates padding, e.g. at the end of the buffer.

Allocation  Using pairs for read and write indexes, available space is determined. If space can be allocated, temporary write index is moved and pointer to a space within buffer is returned. Packet header is reset. If allocation required wrapping of the write index, a skip packet is added to the end of buffer. If space cannot be allocated and overwrite is disabled then NULL pointer is returned or context blocks if allocation was with timeout.

Allocation with overwrite  If overwrite is enabled, oldest packets are dropped until requested amount of space can be allocated. When packets are dropped busy flag is checked in the header to ensure that currently consumed packet is not overwritten. In that case, skip packet is added before busy packet and packets following the busy packet are dropped. When busy packet is being freed, such situation is detected and packet is converted to skip packet to avoid double processing.

Usage

Packet header definition  Packet header details can be found in include/zephyr/sys/mpsc_packet.h. API functions can be found in include/zephyr/sys/mpsc_pbuf.h. Headers are split to avoid include spam when declaring the packet.

User header structure must start with internal header:

```c
#include <zephyr/sys/mpsc_packet.h>

struct foo_header {
    MPSC_PBUF_HDR;
    uint32_t length: 32 - MPSC_PBUF_HDR_BITS;
};
```

Packet buffer configuration  Configuration structure contains buffer details, configuration flags and callbacks. Following callbacks are used by the packet buffer:

- Drop notification - callback called whenever a packet is dropped due to overwrite.
- Get packet length - callback to determine packet length
Packet producing  Standard, two step method:

```c
foo_packet *packet = mpsc_pbuf_alloc(buffer, len, K_NO_WAIT);
fill_data(packet);
mpsc_pbuf_commit(buffer, packet);
```

Performance optimized storing of small packets:

- 32 bit word packet
- 32 bit word with pointer packet

Note that since packets are written by value, they should already contain valid bit set in the header.

```c
mpsc_pbuf_put_word(buffer, data);
mpsc_pbuf_put_word_ext(buffer, data, ptr);
```

Packet consuming  Two step method:

```c
foo_packet *packet = mpsc_pbuf_claim(buffer);
process(packet);
mpsc_pbuf_free(buffer, packet);
```

### 3.5.4 Single Producer Single Consumer Packet Buffer

A Single Producer Single Consumer Packet Buffer (SPSC_PBUF) is a circular buffer, whose contents are stored in first-in-first-out order. Variable size packets are stored in the buffer. Packet buffer works under assumption that there is a single context that produces packets and a single context that consumes the data.

Implementation is focused on performance and memory footprint.

Packets are added to the buffer using `spsc_pbuf_write()` which copies a data into the buffer. If the buffer is full error is returned.

Packets are copied out of the buffer using `spsc_pbuf_read()`.

### 3.5.5 Balanced Red/Black Tree

For circumstances where sorted containers may become large at runtime, a list becomes problematic due to algorithmic costs of searching it. For these situations, Zephyr provides a balanced tree implementation which has runtimes on search and removal operations bounded at $O(\log_2(N))$ for a tree of size $N$. This is implemented using a conventional red/black tree as described by multiple academic sources.

The `rbtree` tracking struct for a rbtree may be initialized anywhere in user accessible memory. It should contain only zero bits before first use. No specific initialization API is needed or required.

Unlike a list, where position is explicit, the ordering of nodes within an rbtree must be provided as a predicate function by the user. A function of type `rb_lessthan_t()` should be assigned to the `lessthan_fn` field of the `rbtree` struct before any tree operations are attempted. This function should, as its name suggests, return a boolean True value if the first node argument is “less than” the second in the ordering desired by the tree. Note that “equal” is not allowed, nodes within a tree must have a single fixed order for the algorithm to work correctly.
As with the slist and dlist containers, nodes within an rbtree are represented as a `rbnode` structure which exists in user-managed memory, typically embedded within the data structure being tracked in the tree. Unlike the list code, the data within an rbnode is entirely opaque. It is not possible for the user to extract the binary tree topology and “manually” traverse the tree as it is for a list.

Nodes can be inserted into a tree with `rb_insert()` and removed with `rb_remove()`. Access to the “first” and “last” nodes within a tree (in the sense of the order defined by the comparison function) is provided by `rb_get_min()` and `rb_get_max()`. There is also a predicate, `rb_contains()`, which returns a boolean True if the provided node pointer exists as an element within the tree. As described above, all of these routines are guaranteed to have at most log time complexity in the size of the tree.

There are two mechanisms provided for enumerating all elements in an rbtree. The first, `rb_walk()`, is a simple callback implementation where the caller specifies a C function pointer and an untyped argument to be passed to it, and the tree code calls that function for each node in order. This has the advantage of a very simple implementation, at the cost of a somewhat more cumbersome API for the user (not unlike ISO C’s `bsearch()` routine). It is a recursive implementation, however, and is thus not always available in environments that forbid the use of unbounded stack techniques like recursion.

There is also a `RB_FOR_EACH` iterator provided, which, like the similar APIs for the lists, works to iterate over a list in a more natural way, using a nested code block instead of a callback. It is also nonrecursive, though it requires log-sized space on the stack by default (however, this can be configured to use a fixed/maximally size buffer instead where needed to avoid the dynamic allocation). As with the lists, this is also available in a `RB_FOR_EACH_CONTAINER` variant which enumerates using a pointer to a container field and not the raw node pointer.

### Tree Internals

As described, the Zephyr rbtree implementation is a conventional red/black tree as described pervasively in academic sources. Low level details about the algorithm are out of scope for this document, as they match existing conventions. This discussion will be limited to details notable or specific to the Zephyr implementation.

The core invariant guaranteed by the tree is that the path from the root of the tree to any leaf is no more than twice as long as the path to any other leaf. This is achieved by associating one bit of “color” with each node, either red or black, and enforcing a rule that no red child can be a child of another red child (i.e. that the number of black nodes on any path to the root must be the same, and that no more than that number of “extra” red nodes may be present). This rule is enforced by a set of rotation rules used to “fix” trees following modification.

These rotations are conceptually implemented on top of a primitive that “swaps” the position of one node with another in the list. Typical implementations effect this by simply swapping the nodes internal “data” pointers, but because the Zephyr `rbnode` is intrusive, that cannot work. Zephyr must include somewhat more elaborate code to handle the edge cases (for example, one swapped node can be the root, or the two may already be parent/child).

The `rbnode` struct for a Zephyr rbtree contains only two pointers, representing the “left”, and “right” children of a node within the binary tree. Traversal of a tree for rebalancing following modification, however, routinely requires the ability to iterate “upwards” from a node as well. It is very common for red/black trees in the industry to store a third “parent” pointer for this purpose. Zephyr avoids this requirement by building a “stack” of node pointers locally as it traverses downward through the tree and updating it appropriately as modifications are made. So a Zephyr rbtree can be implemented with no more runtime storage overhead than a dlist.

These properties, of a balanced tree data structure that works with only two pointers of data per node and that works without any need for a memory allocation API, are quite rare in the industry and are somewhat unique to Zephyr.
Fig. 9: A maximally unbalanced rbtree with a black height of two. No more nodes can be added underneath the rightmost node without rebalancing.
Red/Black Tree API Reference

**group rbtree_apis**

Balanced Red/Black Tree implementation.

This implements an intrusive balanced tree that guarantees $O(\log_2(N))$ runtime for all operations and amortized $O(1)$ behavior for creation and destruction of whole trees. The algorithms and naming are conventional per existing academic and didactic implementations, c.f.:

https://en.wikipedia.org/wiki/Red%E2%80%93black_tree

The implementation is size-optimized to prioritize runtime memory usage. The data structure is intrusive, which is to say the `rbnode` handle is intended to be placed in a separate struct, in the same way as with other such structures (e.g. Zephyr's [Doubly-linked list](https://en.wikipedia.org/wiki/Linked_list)), and requires no data pointer to be stored in the node. The color bit is unioned with a pointer (fairly common for such libraries). Most notably, there is no “parent” pointer stored in the node, the upper structure of the tree being generated dynamically via a stack as the tree is recursed. So the overall memory overhead of a node is just two pointers, identical with a doubly-linked list.

**Defines**

**RB_FOR_EACH**(tree, node)

Walk a tree in-order without recursing.

While `rb_walk()` is very simple, recursing on the C stack can be clumsy for some purposes and on some architectures wastes significant memory in stack frames. This macro implements a non-recursive “foreach” loop that can iterate directly on the tree, at a moderate cost in code size.

Note that the resulting loop is not safe against modifications to the tree. Changes to the tree structure during the loop will produce incorrect results, as nodes may be skipped or duplicated. Unlike linked lists, no _SAFE variant exists.

Note also that the macro expands its arguments multiple times, so they should not be expressions with side effects.

**Parameters**

- `tree` – A pointer to a struct rbtree to walk
- `node` – The symbol name of a local struct rbnode* variable to use as the iterator

**RB_FOR_EACH_CONTAINER**(tree, node, field)

Loop over rbtree with implicit container field logic.

As for **RB_FOR_EACH()**, but “node” can have an arbitrary type containing a struct rbnode.

**Parameters**

- `tree` – A pointer to a struct rbtree to walk
- `node` – The symbol name of a local iterator
- `field` – The field name of a struct rbnode inside node

**Typedefs**
typedef bool (*rb_lessthan_t)(struct rbnode *a, struct rbnode *b)
  Red/black tree comparison predicate.
  Compares the two nodes and returns true if node A is strictly less than B according to
  the tree’s sorting criteria, false otherwise.
  Note that during insert, the new node being inserted will always be “A”, where “B” is
  the existing node within the tree against which it is being compared. This trait can be
  used (with care!) to implement “most/least recently added” semantics between nodes
  which would otherwise compare as equal.

typedef void (*rb_visit_t)(struct rbnode *node, void *cookie)
  Prototype for node visitor callback.

  **Param node**
  Node being visited

  **Param cookie**
  User-specified data

**Functions**

void rb_insert(struct rbtree *tree, struct rbnode *node)
  Insert node into tree.

void rb_remove(struct rbtree *tree, struct rbnode *node)
  Remove node from tree.

static inline struct rbnode *rb_get_min(struct rbtree *tree)
  Returns the lowest-sorted member of the tree.

static inline struct rbnode *rb_get_max(struct rbtree *tree)
  Returns the highest-sorted member of the tree.

bool rbContains(struct rbtree *tree, struct rbnode *node)
  Returns true if the given node is part of the tree.
  Note that this does not internally dereference the node pointer (though the tree’s
  lessthan callback might!), it just tests it for equality with items in the tree. So it’s feasible
  to use this to implement a “set” construct by simply testing the pointer value itself.

static inline void rb_walk(struct rbtree *tree, rb_visit_t visit_fn, void *cookie)
  Walk/enumerate a rbtree.
  Very simple recursive enumeration. Low code size, but requiring a separate function
  can be clumsy for the user and there is no way to break out of the loop early. See
  RB_FOR_EACH for an iterative implementation.

struct rbnode
  #include <rb.h> Balanced red/black tree node structure.

struct rbtree
  #include <rb.h> Balanced red/black tree structure.

**Public Members**
struct rbnode *root
    Root node of the tree.

rb_lessthan_t lessthan_fn
    Comparison function for nodes in the tree.

3.5.6 Ring Buffers

A ring buffer is a circular buffer, whose contents are stored in first-in-first-out order. For circumstances where an application needs to implement asynchronous “streaming” copying of data, Zephyr provides a struct ring_buf abstraction to manage copies of such data in and out of a shared buffer of memory.

Two content data modes are supported:

- **Byte mode**: raw bytes can be enqueued and dequeued.
- **Data item mode**: Multiple 32-bit word data items with metadata can be enqueued and dequeued from the ring buffer in chunks of up to 1020 bytes. Each data item also has two associated metadata values: a type identifier and a 16-bit integer value, both of which are application-specific.

While the underlying data structure is the same, it is not legal to mix these two modes on a single ring buffer instance. A ring buffer initialized with a byte count must be used only with the “bytes” API, one initialized with a word count must use the “items” calls.

- **Concepts**
  - Byte mode
  - Data item mode
  - Concurrency
  - Internal Operation
- **Implementation**
  - Defining a Ring Buffer
  - Enqueuing Data
  - Retrieving Data
- **Configuration Options**
- **API Reference**

Concepts

Any number of ring buffers can be defined (limited only by available RAM). Each ring buffer is referenced by its memory address.

A ring buffer has the following key properties:

- A **data buffer** of bytes or 32-bit words. The data buffer contains the raw bytes or 32-bit words that have been added to the ring buffer but not yet removed.
- A **data buffer size**, measured in bytes or 32-bit words. This governs the maximum amount of data (including possible metadata values) the ring buffer can hold.
A ring buffer must be initialized before it can be used. This sets its data buffer to empty.

A `struct` `ring_buf` may be placed anywhere in user-accessible memory, and must be initialized with `ring_buf_init()` or `ring_buf_item_init()` before use. This must be provided a region of user-controlled memory for use as the buffer itself. Note carefully that the units of the size of the buffer passed change (either bytes or words) depending on how the ring buffer will be used later. Macros for combining these steps in a single static declaration exist for convenience. `RING_BUF_DECLARE` will declare and statically initialize a ring buffer with a specified byte count, where `RING_BUF_ITEM_DECLARE` will declare and statically initialize a buffer with a given count of 32 bit words. `RING_BUF_ITEM_SIZEOF` will compute the size in 32-bit words corresponding to a type or an expression. Note: rounds up if the size is not a multiple of 32 bits.

“Bytes” data may be copied into the ring buffer using `ring_buf_put()`, passing a data pointer and byte count. These bytes will be copied into the buffer in order, as many as will fit in the allocated buffer. The total number of bytes copied (which may be fewer than provided) will be returned. Likewise `ring_buf_get()` will copy bytes out of the ring buffer in the order that they were written, into a user-provided buffer, returning the number of bytes that were transferred.

To avoid multiply-copied-data situations, a “claim” API exists for byte mode. `ring_buf_put_claim()` takes a byte size value from the user and returns a pointer to memory internal to the ring buffer that can be used to receive those bytes, along with a size of the contiguous internal region (which may be smaller than requested). The user can then copy data into that region at a later time without assembling all the bytes in a single region first. When complete, `ring_buf_put_finish()` can be used to signal the buffer that the transfer is complete, passing the number of bytes actually transferred. At this point a new transfer can be initiated. Similarly, `ring_buf_get_claim()` returns a pointer to internal ring buffer data from which the user can read without making a verbatim copy, and `ring_buf_get_finish()` signals the buffer with how many bytes have been consumed and allows for a new transfer to begin.

“Items” mode works similarly to bytes mode, except that all transfers are in units of 32 bit words and all memory is assumed to be aligned on 32 bit boundaries. The write and read operations are `ring_buf_item_put()` and `ring_buf_item_get()`, and work otherwise identically to the bytes mode APIs. There no “claim” API provided for items mode. One important difference is that unlike `ring_buf_put()`, `ring_buf_item_put()` will not do a partial transfer; it will return an error in the case where the provided data does not fit in its entirety.

The user can manage the capacity of a ring buffer without modifying it using either `ring_buf_space_get()` or `ring_buf_item_space_get()` which returns the number of free bytes or free 32-bit item words respectively, or by testing the `ring_buf_is_empty()` predicate.

Finally, a `ring_buf_reset()` call exists to immediately empty a ring buffer, discarding the tracking of any bytes or items already written to the buffer. It does not modify the memory contents of the buffer itself, however.

**Byte mode** A byte mode ring buffer instance is declared using `RING_BUF_DECLARE()` and accessed using: `ring_buf_put_claim()`, `ring_buf_put_finish()`, `ring_buf_get_claim()`, `ring_buf_get_finish()`, `ring_buf_put()` and `ring_buf_get()`.

Data can be copied into the ring buffer (see `ring_buf_put()`) or ring buffer memory can be used directly by the user. In the latter case, the operation is split into three stages:

1. allocating the buffer (`ring_buf_put_claim()`) when user requests the destination location where data can be written.
2. writing the data by the user (e.g. buffer written by DMA).
3. indicating the amount of data written to the provided buffer (`ring_buf_put_finish()`). The amount can be less than or equal to the allocated amount.

Data can be retrieved from a ring buffer through copying (see `ring_buf_get()`) or accessed directly by address. In the latter case, the operation is split into three stages:
1. retrieving source location with valid data written to a ring buffer (see `ring_buf_get_claim()`).

2. processing data

3. freeing processed data (see `ring_buf_get_finish()`). The amount freed can be less than or equal to the retrieved amount.

Data item mode A **data item mode** ring buffer instance is declared using `RING_BUF_ITEM_DECLARE()` and accessed using `ring_buf_item_put()` and `ring_buf_item_get()`.

A ring buffer **data item** is an array of 32-bit words from 0 to 1020 bytes in length. When a data item is **enqueued** (`ring_buf_item_put()`) its contents are copied to the data buffer, along with its associated metadata values (which occupy one additional 32-bit word). If the ring buffer has insufficient space to hold the new data item the enqueue operation fails.

A data item is **dequeued** (`ring_buf_item_get()`) from a ring buffer by removing the oldest enqueued item. The contents of the dequeued data item, as well as its two metadata values, are copied to areas supplied by the retriever. If the ring buffer is empty, or if the data array supplied by the retriever is not large enough to hold the data item’s data, the dequeue operation fails.

Concurrency The ring buffer APIs do not provide any concurrency control. Depending on usage (particularly with respect to number of concurrent readers/writers) applications may need to protect the ring buffer with mutexes and/or use semaphores to notify consumers that there is data to read.

For the trivial case of one producer and one consumer, concurrency control shouldn’t be needed.

Internal Operation Data streamed through a ring buffer is always written to the next byte within the buffer, wrapping around to the first element after reaching the end, thus the “ring” structure. Internally, the struct `ring_buf` contains its own buffer pointer and its size, and also a set of “head” and “tail” indices representing where the next read and write operations may occur.

This boundary is invisible to the user using the normal put/get APIs, but becomes a barrier to the “claim” API, because obviously no contiguous region can be returned that crosses the end of the buffer. This can be surprising to application code, and produce performance artifacts when transfers need to happen close to the end of the buffer, as the number of calls to claim/finish needs to double for such transfers.

Implementation

**Defining a Ring Buffer** A ring buffer is defined using a variable of type `ring_buf`. It must then be initialized by calling `ring_buf_init()` or `ring_buf_item_init()`.

The following code defines and initializes an empty **data item mode** ring buffer (which is part of a larger data structure). The ring buffer’s data buffer is capable of holding 64 words of data and metadata information.

```c
#define MY_RING_BUF_WORDS 64

struct my_struct {
    struct ring_buf rb;
    uint32_t buffer[MY_RING_BUF_WORDS];
    ...
};
struct my_struct ms;
```

(continues on next page)
void init_my_struct {
    ring_buf_item_init(&ms.rb, MY_RING_BUF_WORDS, ms.buffer);
    ...
}

Alternatively, a ring buffer can be defined and initialized at compile time using one of two macros at file scope. Each macro defines both the ring buffer itself and its data buffer.

The following code defines a **data item mode** ring buffer:

```c
#define MY_RING_BUF_WORDS 93
RING_BUF_ITEM_DECLARE(my_ring_buf, MY_RING_BUF_WORDS);
```

The following code defines a ring buffer intended to be used for raw bytes:

```c
#define MY_RING_BUF_BYTES 93
RING_BUF_DECLARE(my_ring_buf, MY_RING_BUF_BYTES);
```

**Enqueuing Data**  Bytes are copied to a **byte mode** ring buffer by calling `ring_buf_put()`.

```c
uint8_t my_data[MY_RING_BUF_BYTES];
uint32_t ret;

ret = ring_buf_put(&ring_buf, my_data, MY_RING_BUF_BYTES);
if (ret != MY_RING_BUF_BYTES) {
    /* not enough room, partial copy. */
    ...
}
```

Data can be added to a **byte mode** ring buffer by directly accessing the ring buffer’s memory. For example:

```c
uint32_t size;
uint32_t rx_size;
uint8_t *data;
int err;

/* Allocate buffer within a ring buffer memory. */
size = ring_buf_put_claim(&ring_buf, &data, MY_RING_BUF_BYTES);

/* Work directly on a ring buffer memory. */
rx_size = uart_rx(data, size);

/* Indicate amount of valid data. rx_size can be equal or less than size. */
err = ring_buf_put_finish(&ring_buf, rx_size);
if (err != 0) {
    /* This shouldn't happen unless rx_size > size */
    ...
}
```

A data item is added to a ring buffer by calling `ring_buf_item_put()`.

```c
uint32_t data[MY_DATA_WORDS];
int ret;

ret = ring_buf_item_put(&ring_buf, TYPE_FOO, 0, data, MY_DATA_WORDS);
if (ret == -EMSGSIZE) {
    /* not enough room for the data item */
    ...
}
If the data item requires only the type or application-specific integer value (i.e. it has no data array), a size of 0 and data pointer of NULL can be specified.

```c
int ret;
ret = ring_buf_item_put(&ring_buf, TYPE_BAR, 17, NULL, 0);
if (ret == -EMSGSIZE) {
    /* not enough room for the data item */
    ...
}
```

**Retrieving Data** Data bytes are copied out from a byte mode ring buffer by calling `ring_buf_get()`. For example:

```c
uint8_t my_data[MY_DATA_BYTES];
size_t ret;
ret = ring_buf_get(&ring_buf, my_data, sizeof(my_data));
if (ret != sizeof(my_data)) {
    /* Fewer bytes copied. */
} else {
    /* Requested amount of bytes retrieved. */
    ...
}
```

Data can be retrieved from a byte mode ring buffer by direct operations on the ring buffer’s memory. For example:

```c
uint32_t size;
uint32_t proc_size;
uint8_t *data;
int err;
/* Get buffer within a ring buffer memory. */
size = ring_buf_get_claim(&ring_buf, &data, MY_RING_BUF_BYTES);
/* Work directly on a ring buffer memory. */
proc_size = process(data, size);
/* Indicate amount of data that can be freed. proc_size can be equal or less
* than size. */
err = ring_buf_get_finish(&ring_buf, proc_size);
if (err != 0) {
    /* proc_size exceeds amount of valid data in a ring buffer. */
    ...
}
```

A data item is removed from a ring buffer by calling `ring_buf_item_get()`.

```c
uint32_t my_data[MY_DATA_WORDS];
uint16_t my_type;
uint8_t my_value;
uint8_t my_size;
int ret;
my_size = MY_DATA_WORDS;
ret = ring_buf_item_get(&ring_buf, &my_type, &my_value, my_data, &my_size);
if (ret == -EMSGSIZE) {
    printk("Buffer is too small, need %d uint32_t\n", my_size);
} else if (ret == -EAGAIN) {
    ...
}
```

(continues on next page)
printk("Ring buffer is empty\n");
} else {
    printk("Got item of type %u value &u of size %u dwords\n",
            my_type, my_value, my_size);
    ...
}

Configuration Options

Related configuration options:

• CONFIG_RING_BUFFER: Enable ring buffer.

API Reference

The following ring buffer APIs are provided by include/zephyr/sys/ring_buffer.h:

group ring_buffer_apis

Simple ring buffer implementation.

Defines

RING_BUF_DECLARE(name, size8)

Define and initialize a ring buffer for byte data.

This macro establishes a ring buffer of an arbitrary size. The basic storage unit is a byte.

The ring buffer can be accessed outside the module where it is defined using:

    extern struct ring_buf <name>;

Parameters

• name – Name of the ring buffer.
• size8 – Size of ring buffer (in bytes).

RING_BUF_ITEM_DECLARE(name, size32)

Define and initialize an “item based” ring buffer.

This macro establishes an “item based” ring buffer. Each data item is an array of 32-bit words (from zero to 1020 bytes in length), coupled with a 16-bit type identifier and an 8-bit integer value.

The ring buffer can be accessed outside the module where it is defined using:

    extern struct ring_buf <name>;

Parameters

• name – Name of the ring buffer.
• size32 – Size of ring buffer (in 32-bit words).
RING_BUF_ITEM_DECLARE_SIZE(name, size32)
Define and initialize an “item based” ring buffer.
This exists for backward compatibility reasons. `RING_BUF_ITEM_DECLARE` should be used instead.

**Parameters**
- **name** – Name of the ring buffer.
- **size32** – Size of ring buffer (in 32-bit words).

RING_BUF_ITEM_DECLARE_POW2(name, pow)
Define and initialize a power-of-2 sized “item based” ring buffer.
This macro establishes an “item based” ring buffer by specifying its size using a power of 2. This exists mainly for backward compatibility reasons. `RING_BUF_ITEM_DECLARE` should be used instead.

**Parameters**
- **name** – Name of the ring buffer.
- **pow** – Ring buffer size exponent.

RING_BUF_ITEM_SIZEOF(expr)
Compute the ring buffer size in 32-bit needed to store an element.
The argument can be a type or an expression. Note: rounds up if the size is not a multiple of 32 bits.

**Parameters**
- **expr** – Expression or type to compute the size of

**Functions**

static inline void ring_buf_internal_reset(struct ring_buf *buf, int32_t value)
Function to force `ring_buf` internal states to given value.
Any value other than 0 makes sense only in validation testing context.

static inline void ring_buf_init(struct ring_buf *buf, uint32_t size, uint8_t *data)
Initialize a ring buffer for byte data.
This routine initializes a ring buffer, prior to its first use. It is only used for ring buffers not defined using `RING_BUF_DECLARE`.

**Parameters**
- **buf** – Address of ring buffer.
- **size** – Ring buffer size (in bytes).
- **data** – Ring buffer data area (uint8_t data[size]).

static inline void ring_buf_item_init(struct ring_buf *buf, uint32_t size, uint32_t *data)
Initialize an “item based” ring buffer.
This routine initializes a ring buffer, prior to its first use. It is only used for ring buffers not defined using `RING_BUF_ITEM_DECLARE`.

Each data item is an array of 32-bit words (from zero to 1020 bytes in length), coupled with a 16-bit type identifier and an 8-bit integer value.

Each data item is an array of 32-bit words (from zero to 1020 bytes in length), coupled with a 16-bit type identifier and an 8-bit integer value.
Parameters

- buf – Address of ring buffer.
- size – Ring buffer size (in 32-bit words)
- data – Ring buffer data area (uint32_t data[size]).

static inline bool ring_buf_is_empty(struct ring_buf *buf)
Determine if a ring buffer is empty.

Parameters

- buf – Address of ring buffer.

Returns
true if the ring buffer is empty, or false if not.

static inline void ring_buf_reset(struct ring_buf *buf)
Reset ring buffer state.

Parameters

- buf – Address of ring buffer.

static inline uint32_t ring_buf_space_get(struct ring_buf *buf)
Determine free space in a ring buffer.

Parameters

- buf – Address of ring buffer.

Returns
Ring buffer free space (in bytes).

static inline uint32_t ring_buf_item_space_get(struct ring_buf *buf)
Determine free space in an “item based” ring buffer.

Parameters

- buf – Address of ring buffer.

Returns
Ring buffer free space (in 32-bit words).

static inline uint32_t ring_buf_capacity_get(struct ring_buf *buf)
Return ring buffer capacity.

Parameters

- buf – Address of ring buffer.

Returns
Ring buffer capacity (in bytes).

static inline uint32_t ring_buf_size_get(struct ring_buf *buf)
Determine used space in a ring buffer.

Parameters

- buf – Address of ring buffer.

Returns
Ring buffer space used (in bytes).

uint32_t ring_buf_put_claim(struct ring_buf *buf, uint8_t **data, uint32_t size)
Allocate buffer for writing data to a ring buffer.

With this routine, memory copying can be reduced since internal ring buffer can be used directly by the user. Once data is written to allocated area number of bytes written must be confirmed (see ring_buf_put_finish).
Warning: Use cases involving multiple writers to the ring buffer must prevent concurrent write operations, either by preventing all writers from being preemted or by using a mutex to govern writes to the ring buffer.

Warning: Ring buffer instance should not mix byte access and item access (calls prefixed with ring_buf_item_).

Parameters
- data – [out] Pointer to the address. It is set to a location within ring buffer.

Returns
Size of allocated buffer which can be smaller than requested if there is not enough free space or buffer wraps.

```
int ring_buf_put_finish(struct ring_buf *buf, uint32_t size)
```

Indicate number of bytes written to allocated buffers.

The number of bytes must be equal to or lower than the sum corresponding to all preceding `ring_buf_put_claim` invocations (or even 0). Surplus bytes will be returned to the available free buffer space.

Warning: Use cases involving multiple writers to the ring buffer must prevent concurrent write operations, either by preventing all writers from being preemted or by using a mutex to govern writes to the ring buffer.

Warning: Ring buffer instance should not mix byte access and item access (calls prefixed with ring_buf_item_).

Parameters
- buf – Address of ring buffer.
- size – Number of valid bytes in the allocated buffers.

Return values
- 0 – Successful operation.
- -EINVAL – Provided `size` exceeds free space in the ring buffer.

```
uint32_t ring_buf_put(struct ring_buf *buf, const uint8_t *data, uint32_t size)
```

Write (copy) data to a ring buffer.

This routine writes data to a ring buffer `buf`.

Warning: Use cases involving multiple writers to the ring buffer must prevent concurrent write operations, either by preventing all writers from being preemted or by using a mutex to govern writes to the ring buffer.
Warning: Ring buffer instance should not mix byte access and item access (calls prefixed with ring_buf_item_).

Parameters

- `buf` – Address of ring buffer.
- `data` – Address of data.
- `size` – Data size (in bytes).

Return values

Number – of bytes written.

```c
uint32_t ring_buf_get_claim(struct ring_buf *buf, uint8_t **data, uint32_t size)
```

Get address of a valid data in a ring buffer.

With this routine, memory copying can be reduced since internal ring buffer can be used directly by the user. Once data is processed it must be freed using `ring_buf_get_finish`.

Warning: Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

Parameters

- `data` – [out] Pointer to the address. It is set to a location within ring buffer.

Returns

Number of valid bytes in the provided buffer which can be smaller than requested if there is not enough free space or buffer wraps.

```c
int ring_buf_get_finish(struct ring_buf *buf, uint32_t size)
```

Indicate number of bytes read from claimed buffer.

The number of bytes must be equal or lower than the sum corresponding to all preceding `ring_buf_get_claim` invocations (or even 0). Surplus bytes will remain available in the buffer.

Warning: Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

Warning: Ring buffer instance should not mix byte access and item mode (calls prefixed with ring_buf_item_).
Parameters
  • buf – Address of ring buffer.
  • size – Number of bytes that can be freed.

Return values
  • 0 – Successful operation.
  • -EINVAL – Provided size exceeds valid bytes in the ring buffer.

uint32_t ring_buf_get(struct ring_buf *buf, uint8_t *data, uint32_t size)
Read data from a ring buffer.
This routine reads data from a ring buffer buf.

**Warning**: Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

**Warning**: Ring buffer instance should not mix byte access and item mode (calls prefixed with ring_buf_item_).

Parameters
  • buf – Address of ring buffer.
  • data – Address of the output buffer. Can be NULL to discard data.
  • size – Data size (in bytes).

Return values
  Number – of bytes written to the output buffer.

uint32_t ring_buf_peek(struct ring_buf *buf, uint8_t *data, uint32_t size)
Peek at data from a ring buffer.
This routine reads data from a ring buffer buf without removal.

**Warning**: Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

**Warning**: Ring buffer instance should not mix byte access and item mode (calls prefixed with ring_buf_item_).

**Warning**: Multiple calls to peek will result in the same data being ‘peeked’ multiple times. To remove data, use either ring_buf_get or ring_buf_get_claim followed by ring_buf_get_finish with a non-zero size.

Parameters
  • buf – Address of ring buffer.
• **data** – Address of the output buffer. Cannot be NULL.
• **size** – Data size (in bytes).

**Return values**

Number – of bytes written to the output buffer.

```c
int ring_buf_item_put(struct ring_buf *buf, uint16_t type, uint8_t value, uint32_t *data, uint8_t size32)
```

Write a data item to a ring buffer.

This routine writes a data item to ring buffer `buf`. The data item is an array of 32-bit words (from zero to 1020 bytes in length), coupled with a 16-bit type identifier and an 8-bit integer value.

**Warning:** Use cases involving multiple writers to the ring buffer must prevent concurrent write operations, either by preventing all writers from being preempted or by using a mutex to govern writes to the ring buffer.

**Parameters**

• **buf** – Address of ring buffer.
• **type** – Data item's type identifier (application specific).
• **value** – Data item's integer value (application specific).
• **data** – Address of data item.
• **size32** – Data item size (number of 32-bit words).

**Return values**

• 0 – Data item was written.
• -EMSGSIZE – Ring buffer has insufficient free space.

```c
int ring_buf_item_get(struct ring_buf *buf, uint16_t *type, uint8_t *value, uint32_t *data, uint8_t *size32)
```

Read a data item from a ring buffer.

This routine reads a data item from ring buffer `buf`. The data item is an array of 32-bit words (up to 1020 bytes in length), coupled with a 16-bit type identifier and an 8-bit integer value.

**Warning:** Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

**Parameters**

• **buf** – Address of ring buffer.
• **type** – Area to store the data item's type identifier.
• **value** – Area to store the data item's integer value.
• **data** – Area to store the data item. Can be NULL to discard data.
• **size32** – Size of the data item storage area (number of 32-bit chunks).

**Return values**
• 0 – Data item was fetched; size32 now contains the number of 32-bit words read into data area data.
• -EAGAIN – Ring buffer is empty.
• -EMSGSIZE – Data area data is too small; size32 now contains the number of 32-bit words needed.

```
struct ring_buf
    #include <ring_buffer.h> A structure to represent a ring buffer.
```

### 3.6 Executing Time Functions

The timing functions can be used to obtain execution time of a section of code to aid in analysis and optimization.

Please note that the timing functions may use a different timer than the default kernel timer, where the timer being used is specified by architecture, SoC or board configuration.

#### 3.6.1 Configuration

To allow using the timing functions, CONFIG_TIMING_FUNCTIONS needs to be enabled.

#### 3.6.2 Usage

To gather timing information:

1. Call `timing_init()` to initialize the timer.
2. Call `timing_start()` to signal the start of gathering of timing information. This usually starts the timer.
3. Call `timing_counter_get()` to mark the start of code execution.
4. Call `timing_counter_get()` to mark the end of code execution.
5. Call `timing_cycles_get()` to get the number of timer cycles between start and end of code execution.
6. Call `timing_cycles_to_ns()` with total number of cycles to convert number of cycles to nanoseconds.
7. Repeat from step 3 to gather timing information for other blocks of code.
8. Call `timing_stop()` to signal the end of gathering of timing information. This usually stops the timer.

**Example**

This shows an example on how to use the timing functions:

```c
#include <zephyr/timing/timing.h>

void gather_timing(void)
{
    timing_t start_time, end_time;
    uint64_t total_cycles;

    // timing code here...

    // Gather timing information
    timing_init();
    timing_start();
    timing_counter_get(&start_time);
    // Code execution
    // ...
    timing_counter_get(&end_time);
    total_cycles = timing_cycles_get();
    nanoseconds = timing_cycles_to_ns(total_cycles);
    // ...
    timing_stop();
}
```

(continues on next page)
```c
uint64_t total_ns;

timing_init();
timing_start();

start_time = timing_counter_get();

code_execution_to_beMeasured();

end_time = timing_counter_get();

start_time = timing_counter_get();

total_cycles = timing_cycles_get(&start_time, &end_time);
total_ns = timing_cycles_to_ns(total_cycles);

timing_stop();
```

### 3.6.3 API documentation

**group timing_api**

Timing Measurement APIs.

The timing measurement APIs can be used to obtain execution time of a section of code to aid in analysis and optimization.

Please note that the timing functions may use a different timer than the default kernel timer, where the timer being used is specified by architecture, SoC or board configuration.

**Functions**

**void timing_init(void)**

- Initialize the timing subsystem.

**void timing_start(void)**

- Signal the start of the timing information gathering.

**void timing_stop(void)**

- Signal the end of the timing information gathering.

**static inline timing_t timing_counter_get(void)**

- Return timing counter.

**Returns**

Timing counter.

**static inline uint64_t timing_cycles_get(volatile timing_t *const start, volatile timing_t *const end)**

- Get number of cycles between `start` and `end`.

For some architectures or SoCs, the raw numbers from counter need to be scaled to obtain actual number of cycles.
Parameters

- **start** – Pointer to counter at start of a measured execution.
- **end** – Pointer to counter at stop of a measured execution.

Returns

Number of cycles between start and end.

```c
static inline uint64_t timing_freq_get(void)
Get frequency of counter used (in Hz).
```

Returns

Frequency of counter used for timing in Hz.

```c
static inline uint64_t timing_cycles_to_ns(uint64_t cycles)
Convert number of cycles into nanoseconds.
```

Parameters

- **cycles** – Number of cycles

Returns

Converted time value

```c
static inline uint64_t timing_cycles_to_ns_avg(uint64_t cycles, uint32_t count)
Convert number of cycles into nanoseconds with averaging.
```

Parameters

- **cycles** – Number of cycles
- **count** – Times of accumulated cycles to average over

Returns

Converted time value

```c
static inline uint32_t timing_freq_get_mhz(void)
Get frequency of counter used (in MHz).
```

Returns

Frequency of counter used for timing in MHz.

### group timing_api_arch

Arch specific Timing Measurement APIs.

Implements the necessary bits to support timing measurement using architecture specific timing measurement mechanism.

### Functions

```c
void arch_timing_init(void)
Initialize the timing subsystem.
Perform the necessary steps to initialize the timing subsystem.
```

See also:

- `timing_init()`
void `arch_timing_start`(void)

Signal the start of the timing information gathering.

Signal to the timing subsystem that timing information will be gathered from this point forward.

See also:
`timing_start()`

Note: Any call to `arch_timing_counter_get()` must be done between calls to `arch_timing_start()` and `arch_timing_stop()`, and on the same CPU core.

void `arch_timing_stop`(void)

Signal the end of the timing information gathering.

Signal to the timing subsystem that timing information is no longer being gathered from this point forward.

See also:
`timing_stop()`

Note: Any call to `arch_timing_counter_get()` must be done between calls to `arch_timing_start()` and `arch_timing_stop()`, and on the same CPU core.

timing_t `arch_timing_counter_get`(void)

Return timing counter.

See also:
`timing_counter_get()`

Note: Any call to `arch_timing_counter_get()` must be done between calls to `arch_timing_start()` and `arch_timing_stop()`, and on the same CPU core.

Note: Not all architectures have a timing counter with 64 bit precision. It is possible to see this value “go backwards” due to internal rollover. Timing code must be prepared to address the rollover (with platform-dependent code, e.g. by casting to a uint32_t before subtraction) or by using `arch_timing_cycles_get()` which is required to understand the distinction.
**Returns**
Timing counter.

```c
uint64_t arch_timing_cycles_get(volatile timing_t *const start, volatile timing_t *const end)
```
Get number of cycles between start and end.

**See also:**
`timing_cycles_get()`

**Note:** For some architectures, the raw numbers from counter need to be scaled to obtain actual number of cycles, or may roll over internally. This function computes a positive-definite interval between two returned cycle values.

**Parameters**
- `start` – Pointer to counter at start of a measured execution.
- `end` – Pointer to counter at stop of a measured execution.

**Returns**
Number of cycles between start and end.

```c
uint64_t arch_timing_freq_get(void)
```
Get frequency of counter used (in Hz).

**See also:**
`timing_freq_get()`

**Returns**
Frequency of counter used for timing in Hz.

```c
uint64_t arch_timing_cycles_to_ns(uint64_t cycles)
```
Convert number of cycles into nanoseconds.

**See also:**
`timing_cycles_to_ns()`

**Parameters**
- `cycles` – Number of cycles

**Returns**
Converted time value

```c
uint64_t arch_timing_cycles_to_ns_avg(uint64_t cycles, uint32_t count)
```
Convert number of cycles into nanoseconds with averaging.

**See also:**
`timing_cycles_to_ns_avg()`

**Parameters**
Zephyr Project Documentation, Release 3.6.0-rc3

- **cycles** – Number of cycles
- **count** – Times of accumulated cycles to average over

**Returns**
Converted time value

```c
uint32_t arch_timing_freq_get_mhz(void)
```
Get frequency of counter used (in MHz).

**See also:**
`timing_freq_get_mhz()`

**Returns**
Frequency of counter used for timing in MHz.

**group timing_api_soc**
SoC specific Timing Measurement APIs.
Implements the necessary bits to support timing measurement using SoC specific timing measurement mechanism.

**Functions**

```c
void soc_timing_init(void)
```
Initialize the timing subsystem on SoC.
Perform the necessary steps to initialize the timing subsystem.

**See also:**
`timing_init()`

```c
void soc_timing_start(void)
```
Signal the start of the timing information gathering.
Signal to the timing subsystem that timing information will be gathered from this point forward.

**See also:**
`timing_start()`

```c
void soc_timing_stop(void)
```
Signal the end of the timing information gathering.
Signal to the timing subsystem that timing information is no longer being gathered from this point forward.

**See also:**
`timing_stop()`
```c
typedef struct timing_t {
    uint64_t cycles;
    uint64_t freq;
} timing_t;
```

### timing_t soc_timing_counter_get(void)

Return timing counter.

**See also:**

- `timing_counter_get()`

**Note:** Not all SoCs have timing counters with 64 bit precision. It is possible to see this value “go backwards” due to internal rollover. Timing code must be prepared to address the rollover (with SoC dependent code, e.g. by casting to a `uint32_t` before subtraction) or by using `soc_timing_cycles_get()` which is required to understand the distinction.

### Returns

Timing counter.

### uint64_t soc_timing_cycles_get(const volatile timing_t *start, const volatile timing_t *end)

Get number of cycles between `start` and `end`.

**See also:**

- `timing_cycles_get()`

**Note:** The raw numbers from counter need to be scaled to obtain actual number of cycles, or may roll over internally. This function computes a positive-definite interval between two returned cycle values.

**Parameters**

- `start` – Pointer to counter at start of a measured execution.
- `end` – Pointer to counter at stop of a measured execution.

**Returns**

Number of cycles between start and end.

### uint64_t soc_timing_freq_get(void)

Get frequency of counter used (in Hz).

**See also:**

- `timing_freq_get()`

**Returns**

Frequency of counter used for timing in Hz.

### uint64_t soc_timing_cycles_to_ns(const uint64_t cycles)

Convert number of cycles into nanoseconds.

**See also:**

- `timing_cycles_to_ns()`
Parameters

- cycles – Number of cycles

Returns

Converted time value

```c
uint64_t soc_timing_cycles_to_ns_avg(uint64_t cycles, uint32_t count)
```

Convert number of cycles into nanoseconds with averaging.

See also:

timing_cycles_to_ns_avg()

Parameters

- cycles – Number of cycles
- count – Times of accumulated cycles to average over

Returns

Converted time value

```c
uint32_t soc_timing_freq_get_mhz(void)
```

Get frequency of counter used (in MHz).

See also:

timing_freq_get_mhz()

Returns

Frequency of counter used for timing in MHz.

**group timing_api_board**

Board specific Timing Measurement APIs.

Implements the necessary bits to support timing measurement using board specific timing measurement mechanism.

**Functions**

```c
void board_timing_init(void)
```

Initialize the timing subsystem.

Perform the necessary steps to initialize the timing subsystem.

See also:

timing_init()

```c
void board_timing_start(void)
```

Signal the start of the timing information gathering.

Signal to the timing subsystem that timing information will be gathered from this point forward.
void board_timing_stop(void)
    Signal the end of the timing information gathering.
    Signal to the timing subsystem that timing information is no longer being gathered
    from this point forward.

See also:
timing_stop()

timing_t board_timing_counter_get(void)
    Return timing counter.

See also:
timing_counter_get()

Note: Not all timing counters have 64 bit precision. It is possible to see this value
“go backwards” due to internal rollover. Timing code must be prepared to address the
rollover (with board dependent code, e.g. by casting to a uint32_t before subtraction)
only by using board_timing_cycles_get() which is required to understand the distinction.

Returns
    Timing counter.

uint64_t board_timing_cycles_get(const timing_t *start, const timing_t *end)
    Get number of cycles between start and end.

See also:
timing_cycles_get()

Note: The raw numbers from counter need to be scaled to obtain actual number of
cycles, or may roll over internally. This function computes a positive-definite interval
between two returned cycle values.

Parameters
    • start – Pointer to counter at start of a measured execution.
    • end – Pointer to counter at stop of a measured execution.

Returns
    Number of cycles between start and end.

uint64_t board_timing_freq_get(void)
    Get frequency of counter used (in Hz).

See also:
timing_freq_get()
Returns
Frequency of counter used for timing in Hz.

uint64_t board_timing_cycles_to_ns(uint64_t cycles)
Convert number of cycles into nanoseconds.

See also:
timing_cycles_to_ns()

Parameters
• cycles – Number of cycles

Returns
Converted time value

uint64_t board_timing_cycles_to_ns_avg(uint64_t cycles, uint32_t count)
Convert number of cycles into nanoseconds with averaging.

See also:
timing_cycles_to_ns_avg()

Parameters
• cycles – Number of cycles
• count – Times of accumulated cycles to average over

Returns
Converted time value

uint32_t board_timing_freq_get_mhz(void)
Get frequency of counter used (in MHz).

See also:
timing_freq_get_mhz()

Returns
Frequency of counter used for timing in MHz.

3.7 Object Cores

Object cores are a kernel debugging tool that can be used to both identify and perform operations on registered objects.

• Object Core Concepts
• Object Core Statistics Concepts
• Implementation
  – Defining a New Object Type
  – Initializing a New Object Core
3.7.1 Object Core Concepts

Each instance of an object embeds an object core field named `obj_core`. Objects of the same type are linked together via their respective object cores to form a singly linked list. Each object core also links to the their respective object type. Each object type contains a singly linked list linking together all the object cores of that type. Object types are also linked together via a singly linked list. Together, this can allow debugging tools to traverse all the objects in the system.

Object cores have been integrated into following kernel objects:

- Condition Variables
- Events
- FIFOs and LIFOs
- Mailboxes
- Memory Slabs
- Message Queues
- Mutexes
- Pipes
- Semaphores
- Threads
- Timers
- System Memory Blocks

Developers are free to integrate them if desired into other objects within their projects.

3.7.2 Object Core Statistics Concepts

A variety of kernel objects allow for the gathering and reporting of statistics. Object cores provide a uniform means to retrieve that information via object core statistics. When enabled, the object type contains a pointer to a statistics descriptor that defines the various operations that have been enabled for interfacing with the object's statistics. Additionally, the object core contains a pointer to the “raw” statistical information associated with that object. Raw data is the raw, unmanipulated data associated with the statistics. Queried data may be “raw”, but it may also have been manipulated in some way by calculation (such as determining an average).

The following table indicates both what objects have been integrated into the object core statistics as well as the structures used for both “raw” and “queried” data.
Object          | Raw Data Type          | Query Data Type          |
<table>
<thead>
<tr>
<th></th>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>struct mem_slab</td>
<td>struct mem_slab_info</td>
<td>struct sys_memory_stats</td>
</tr>
<tr>
<td>struct sys_mem_blocks</td>
<td>struct sys_mem_blocks_info</td>
<td>struct sys_memory_stats</td>
</tr>
<tr>
<td>struct k_thread</td>
<td>struct k_cycle_stats</td>
<td>struct k_thread_runtime_stats</td>
</tr>
<tr>
<td>struct _cpu</td>
<td>struct k_cycle_stats</td>
<td>struct k_thread_runtime_stats</td>
</tr>
<tr>
<td>struct z_kernel</td>
<td>struct k_cycle_stats[num CPUs]</td>
<td>struct k_thread_runtime_stats</td>
</tr>
</tbody>
</table>

### 3.7.3 Implementation

#### Defining a New Object Type

An object type is defined using a global variable of type `k_obj_type`. It must be initialized before any objects of that type are initialized. The following code shows how a new object type can be initialized for use with object cores and object core statistics.

```c
/* Unique object type ID */
#define K_OBJ_TYPE_MY_NEW_TYPE K_OBJ_TYPE_ID_GEN("UNIQ")

struct k_obj_type my_obj_type;

struct my_obj_type_raw_info {
    ...
};

struct my_obj_type_query_stats {
    ...
};

struct my_new_obj {
    ...
    struct k_obj_core obj_core;
    struct my_obj_type_raw_info info;
};

struct k_obj_core_stats_desc my_obj_type_stats_desc = {
    .raw_size = sizeof(struct my_obj_type_raw_stats),
    .query_size = sizeof(struct my_obj_type_query_stats),
    .raw = my_obj_type_stats_raw,
    .query = my_obj_type_stats_query,
    .reset = my_obj_type_stats_reset,
    .disable = NULL,    /* Stats gathering is always on */
    .enable = NULL,     /* Stats gathering is always on */
};

void my_obj_type_init(void)
{
    z_obj_type_init(&my_obj_type, K_OBJ_TYPE_MY_NEW_TYPE,
                    offsetof(struct my_new_obj, obj_core);
    k_obj_type_stats_init(&my_obj_type, &my_obj_type_stats_desc);
}
```

#### Initializing a New Object Core

Kernel objects that have already been integrated into the object core framework automatically have their object cores initialized when the object is initialized. However, developers that wish
to add their own objects into the framework need to both initialize the object core and link it. The following code builds on the example above and initializes the object core.

```c
void my_new_obj_init(struct my_new_obj *new_obj)
{
    ...
    k_obj_core_init(K_OBJ_CORE(new_obj), &my_obj_type);
    k_obj_core_link(K_OBJ_CORE(new_obj));
    k_obj_core_stats_register(K_OBJ_CORE(new_obj), &new_obj->raw_stats,
                            sizeof(struct my_obj_type_raw_info));
}
```

### Walking a List of Object Cores

Two routines exist for walking the list of object cores linked to an object type. These are `k_obj_type_walk_locked()` and `k_obj_type_walk_unlocked()`. The following code builds upon the example above and prints the addresses of all the objects of that new object type.

```c
int walk_op(struct k_obj_core *obj_core, void *data)
{
    uint8_t *ptr;
    ptr = obj_core;
    ptr -= obj_core->type->obj_core_offset;
    printk("%p\n", ptr);
    return 0;
}

void print_object_addresses(void)
{
    struct k_obj_type *obj_type;
    /* Find the object type */
    obj_type = k_obj_type_find(K_OBJ_TYPE_MY_NEW_TYPE);
    /* Walk the list of objects */
    k_obj_type_walk_unlocked(obj_type, walk_op, NULL);
}
```

### Object Core Statistics Querying

The following code builds on the examples above and shows how an object integrated into the object core statistics framework can both retrieve queried data and reset the stats associated with the object.

```c
struct my_new_obj my_obj;
...

void my_func(void)
{
    struct my_obj_type_query_stats my_stats;
    int status;
    (continues on next page)
my_obj_type_init(&my_obj);
...

status = k_obj_core_stats_query(K_OBJ_CORE(&my_obj), &my_stats, sizeof(my_stats));
if (status != 0) {
    /* Failed to get stats */
    ...
} else {
    k_obj_core_stats_reset(K_OBJ_CORE(&my_obj));
}
...

3.7.4 Configuration Options

Related configuration options:
- CONFIG_OBJ_CORE
- CONFIG_OBJ_CORE_CONDVAR
- CONFIG_OBJ_CORE_EVENT
- CONFIG_OBJ_CORE_FIFO
- CONFIG_OBJ_CORE_LIFO
- CONFIG_OBJ_CORE_MAILBOX
- CONFIG_OBJ_CORE_MEM_SLAB
- CONFIG_OBJ_CORE_MSGQ
- CONFIG_OBJ_CORE_MUTEX
- CONFIG_OBJ_CORE_PIPE
- CONFIG_OBJ_CORE_SEM
- CONFIG_OBJ_CORE_STACK
- CONFIG_OBJ_CORE_THREAD
- CONFIG_OBJ_CORE_TIMER
- CONFIG_OBJ_CORE_SYS_MEM_BLOCKS
- CONFIG_OBJ_CORE_STATS
- CONFIG_OBJ_CORE_STATS_MEM_SLAB
- CONFIG_OBJ_CORE_STATS_THREAD
- CONFIG_OBJ_CORE_STATS_SYSTEM
- CONFIG_OBJ_CORE_STATS_SYS_MEM_BLOCKS

3.7.5 API Reference

$group obj_core_apis$
Defines

K_OBJ_CORE(kobj)
    Convert kernel object pointer into its object core pointer.

K_OBJ_TYPE_ID_GEN(s)
    Generate new object type IDs based on a 4 letter string.

K_OBJ_TYPE_CONDVAR_ID
    Condition variable object type.

K_OBJ_TYPE_CPU_ID
    CPU object type.

K_OBJ_TYPE_EVENT_ID
    Event object type.

K_OBJ_TYPE_FIFO_ID
    FIFO object type.

K_OBJ_TYPE_KERNEL_ID
    Kernel object type.

K_OBJ_TYPE_LIFO_ID
    LIFO object type.

K_OBJ_TYPE_MEM_BLOCK_ID
    Memory block object type.

K_OBJ_TYPE_MBOX_ID
    Mailbox object type.

K_OBJ_TYPE_MEM_SLAB_ID
    Memory slab object type.

K_OBJ_TYPE_MSGQ_ID
    Message queue object type.

K_OBJ_TYPE_MUXTEX_ID
    Mutex object type.

K_OBJ_TYPE_PIPE_ID
    Pipe object type.

K_OBJ_TYPE_SEM_ID
    Semaphore object type.

K_OBJ_TYPE_STACK_ID
    Stack object type.
K_OBJ_TYPE_THREAD_ID
Thread object type.

K_OBJ_TYPE_TIMER_ID
Timer object type.

Functions

struct k_obj_type *k_obj_type_find(uint32_t type_id)
Find a specific object type by ID.

Given an object type ID, this function searches for the object type that is associated with the specified type ID type_id.

Parameters

• type_id – Type ID associated with object type

Return values

• NULL – if object type not found
• Pointer – to object type if found

int k_obj_type_walk_locked(struct k_obj_type *type, int (*func)(struct k_obj_core*, void*), void *data)
Walk the object type's list of object cores.

This function takes a global spinlock and walks the object type's list of object cores and invokes the callback function on each element while holding that lock. Although this will ensure that the list is not modified, one can expect a significant penalty in terms of performance and latency.

The callback function shall either return non-zero to stop further walking, or it shall return 0 to continue walking.

Parameters

• type – Pointer to the object type
• func – Callback to invoke on each object core of the object type
• data – Custom data passed to the callback

Return values

non-zero – if walk is terminated by the callback; otherwise 0

int k_obj_type_walk_unlocked(struct k_obj_type *type, int (*func)(struct k_obj_core*, void*), void *data)
Walk the object type's list of object cores.

This function is similar to k_obj_type_walk_locked() except that it walks the list without obtaining the global spinlock. No synchronization is provided here. Mutation of the list of objects while this function is in progress must be prevented at the application layer, otherwise undefined/unreliable behavior, corruption and/or crashes may result.

The callback function shall either return non-zero to stop further walking, or it shall return 0 to continue walking.

Parameters

• type – Pointer to the object type
• func – Callback to invoke on each object core of the object type
• data – Custom data passed to the callback

Return values
non-zero – if walk is terminated by the callback; otherwise 0

void k_obj_core_init(struct k_obj_core *obj_core, struct k_obj_type *type)
Initialize the core of the kernel object.
Initializing the kernel object core associates it with the specified kernel object type.

Parameters
• obj_core – Pointer to the kernel object to initialize
• type – Pointer to the kernel object type

void k_obj_core_link(struct k_obj_core *obj_core)
Link the kernel object to the kernel object type list.
A kernel object can be optionally linked into the kernel object type's list of objects. A
kernel object must have been initialized before it can be linked. Linked kernel objects
can be traversed and have information extracted from them by system tools.

Parameters
• obj_core – Pointer to the kernel object

void k_obj_core_init_and_link(struct k_obj_core *obj_core, struct k_obj_type *type)
Automatically link the kernel object after initializing it.
A useful wrapper to both initialize the core of the kernel object and automatically link
it into the kernel object type's list of objects.

Parameters
• obj_core – Pointer to the kernel object
• type – Pointer to the kernel object type

void k_obj_core_unlink(struct k_obj_core *obj_core)
Unlink the kernel object from the kernel object type list.
Kernel objects can be unlinked from their respective kernel object type lists. If on a
list, it must be done at the end of the kernel object's life cycle.

Parameters
• obj_core – Pointer to the kernel object

struct k_obj_core_stats_desc
#include <obj_core.h> Object core statistics descriptor.

Public Members

size_t raw_size
Internal representation stats buffer size.

size_t query_size
Stats buffer size used for reporting.

int (*raw)(struct k_obj_core *obj_core, void *stats)
Function pointer to retrieve internal representation of stats.
int (*query)(struct k_obj_core *obj_core, void *stats)
Function pointer to retrieve reported statistics.

int (*reset)(struct k_obj_core *obj_core)
Function pointer to reset object's statistics.

int (*disable)(struct k_obj_core *obj_core)
Function pointer to disable object's statistics gathering.

int (*enable)(struct k_obj_core *obj_core)
Function pointer to enable object's statistics gathering.

struct k_obj_type
#include <obj_core.h> Object type structure.

Public Members

sys_snode_t node
    Node within list of object types.

sys_slist_t list
    List of objects of this object type.

uint32_t id
    Unique type ID.

size_t obj_core_offset
    Offset to obj_core field.

struct k_obj_core
#include <obj_core.h> Object core structure.

Public Members

sys_snode_t node
    Object node within object type's list.

struct k_obj_type *type
    Object type to which object belongs.

group obj_core_stats.Apis

Functions
int k_obj_core_stats_register(struct k_obj_core *obj_core, void *stats, size_t stats_len)

Register kernel object for gathering statistics.

Before a kernel object can gather statistics, it must be registered to do so. Registering will also automatically enable the kernel object to gather its statistics.

Parameters

• obj_core – Pointer to kernel object core
• stats – Pointer to raw kernel statistics
• stats_len – Size of raw kernel statistics buffer

Return values

• 0 – on success
• -errno – on failure

int k_obj_core_stats_deregister(struct k_obj_core *obj_core)

Deregister kernel object from gathering statistics.

Deregistering a kernel object core from gathering statistics prevents it from gathering any more statistics. It is expected to be invoked at the end of a kernel object’s life cycle.

Parameters

• obj_core – Pointer to kernel object core

Return values

• 0 – on success
• -errno – on failure

int k_obj_core_stats_raw(struct k_obj_core *obj_core, void *stats, size_t stats_len)

Retrieve the raw statistics associated with the kernel object.

This function copies the raw statistics associated with the kernel object core specified by obj_core into the buffer stats. Note that the size of the buffer (stats_len) must match the size specified by the kernel object type’s statistics descriptor.

Parameters

• obj_core – Pointer to kernel object core
• stats – Pointer to memory buffer into which to copy raw stats
• stats_len – Length of the memory buffer

Return values

• 0 – on success
• -errno – on failure

int k_obj_core_stats_query(struct k_obj_core *obj_core, void *stats, size_t stats_len)

Retrieve the statistics associated with the kernel object.

This function copies the statistics associated with the kernel object core specified by obj_core into the buffer stats. Unlike the raw statistics this may report calculated values such as averages. Note that the size of the buffer (stats_len) must match the size specified by the kernel object type’s statistics descriptor.

Parameters

• obj_core – Pointer to kernel object core
• stats – Pointer to memory buffer into which to copy the queried stats
• stats_len – Length of the memory buffer
Return values
• 0 – on success
• -errno – on failure

int k_obj_core_stats_reset(struct k_obj_core *obj_core)
Reset the stats associated with the kernel object.
This function resets the statistics associated with the kernel object core specified by obj_core.

Parameters
• obj_core – Pointer to kernel object core

Return values
• 0 – on success
• -errno – on failure

int k_obj_core_stats_disable(struct k_obj_core *obj_core)
Stop gathering the stats associated with the kernel object.
This function temporarily stops the gathering of statistics associated with the kernel object core specified by obj_core. The gathering of statistics can be resumed by invoking :c:func:`k_obj_core_stats_enable`

Parameters
• obj_core – Pointer to kernel object core

Return values
• 0 – on success
• -errno – on failure

int k_obj_core_stats_enable(struct k_obj_core *obj_core)
Reset the stats associated with the kernel object.
This function resumes the gathering of statistics associated with the kernel object core specified by obj_core.

Parameters
• obj_core – Pointer to kernel object core

Return values
• 0 – on success
• -errno – on failure

3.8 Time Utilities

3.8.1 Overview

Uptime in Zephyr is based on the a tick counter. With the default CONFIG_TICKLESS_KERNEL this counter advances at a nominally constant rate from zero at the instant the system started. The POSIX equivalent to this counter is something like CLOCK_MONOTONIC or, in Linux, CLOCK_MONOTONIC_RAW. k_uptime_get() provides a millisecond representation of this time.

Applications often need to correlate the Zephyr internal time with external time scales used in daily life, such as local time or Coordinated Universal Time. These systems interpret time
in different ways and may have discontinuities due to leap seconds and local time offsets like
daylight saving time.

Because of these discontinuities, as well as significant inaccuracies in the clocks underlying the
cycle counter, the offset between time estimated from the Zephyr clock and the actual time in a
“real” civil time scale is not constant and can vary widely over the runtime of a Zephyr applica-
tion.

The time utilities API supports:

- converting between time representations
- synchronizing and aligning time scales

For terminology and concepts that support these functions see Concepts Underlying Time Support
in Zephyr.

3.8.2 Time Utility APIs

Representation Transformation

Time scale instants can be represented in multiple ways including:

- Seconds since an epoch. POSIX representations of time in this form include time_t and
  struct timespec, which are generally interpreted as a representation of “UNIX Time”.
- Calendar time as a year, month, day, hour, minutes, and seconds relative to an epoch. POSIX
  representations of time in this form include struct tm.

Keep in mind that these are simply time representations that must be interpreted relative to a
time scale which may be local time, UTC, or some other continuous or discontinuous scale.

Some necessary transformations are available in standard C library routines. For example,
time_t measuring seconds since the POSIX EPOCH is converted to struct tm representing cal-
deral time with gmtime(). Sub-second timestamps like struct timespec can also use this to
produce the calendar time representation and deal with sub-second offsets separately.

The inverse transformation is not standardized: APIs like mktime() expect information
about time zones. Zephyr provides this transformation with timeutil_timegm() and timeu-
til_timegm64().

Functions

int64_t timeutil_timegm64(const struct tm *tm)

Convert broken-down time to a POSIX epoch offset in seconds.

See also:

Parameters

- tm – pointer to broken down time.

Returns

the corresponding time in the POSIX epoch time scale.
time_t timeutil_timegm(const struct tm *tm)
  Convert broken-down time to a POSIX epoch offset in seconds.

See also:

Parameters
  • tm – pointer to broken down time.

Returns
  the corresponding time in the POSIX epoch time scale. If the time cannot be represented then (time_t)-1 is returned and errno is set to ERANGE.

Time Scale Synchronization

There are several factors that affect synchronizing time scales:
  • The rate of discrete instant representation change. For example Zephyr uptime is tracked in ticks which advance at events that nominally occur at CONFIG_SYS_CLOCK_TICKS_PER_SEC Hertz, while an external time source may provide data in whole or fractional seconds (e.g. microseconds).
  • The absolute offset required to align the two scales at a single instant.
  • The relative error between observable instants in each scale, required to align multiple instants consistently. For example a reference clock that's conditioned by a 1-pulse-per-second GPS signal will be much more accurate than a Zephyr system clock driven by a RC oscillator with a +/- 250 ppm error.

Synchronization or alignment between time scales is done with a multi-step process:
  • An instant in a time scale is represented by an (unsigned) 64-bit integer, assumed to advance at a fixed nominal rate.
  • timeutil_sync_config records the nominal rates of a reference time scale/source (e.g. TAI) and a local time source (e.g. k_uptime_ticks()).
  • timeutil_sync_instant records the representation of a single instant in both the reference and local time scales.
  • timeutil_sync_state provides storage for an initial instant, a recently received second observation, and a skew that can adjust for relative errors in the actual rate of each time scale.
  • timeutil_sync_ref_from_local() and timeutil_sync_local_from_ref() convert instants in one time scale to another taking into account skew that can be estimated from the two instances stored in the state structure by timeutil_sync_estimate_skew().

group timeutil_sync_apis

Functions

int timeutil_sync_state_update(struct timeutil_sync_state *tsp, const struct timeutil_sync_instant *inst)
  Record a new instant in the time synchronization state.
  Note that this updates only the latest persisted instant. The skew is not adjusted automatically.
Parameters
• \( \text{tsp} \) – pointer to a `timeutil_sync_state` object.
• \( \text{inst} \) – the new instant to be recorded. This becomes the base instant if there is no base instant, otherwise the value must be strictly after the base instant in both the reference and local time scales.

Return values
• 0 – if installation succeeded in providing a new base
• 1 – if installation provided a new latest instant
• \(-\text{EINVAL}\) – if the new instant is not compatible with the base instant

```c
int timeutil_sync_state_set_skew(struct timeutil_sync_state *tsp, float skew, const struct timeutil_sync_instant *base)
```

Update the state with a new skew and possibly base value.

Set the skew from a value retrieved from persistent storage, or calculated based on recent skew estimations including from `timeutil_sync_estimate_skew()`.

Optionally update the base timestamp. If the base is replaced the latest instant will be cleared until `timeutil_sync_state_update()` is invoked.

Parameters
• \( \text{tsp} \) – pointer to a time synchronization state.
• \( \text{skew} \) – the skew to be used. The value must be positive and shouldn’t be too far away from 1.
• \( \text{base} \) – optional new base to be set. If provided this becomes the base timestamp that will be used along with skew to convert between reference and local timescale instants. Setting the base clears the captured latest value.

Returns
0 if skew was updated

Returns
\(-\text{EINVAL}\) if skew was not valid

```c
float timeutil_sync_estimate_skew(const struct timeutil_sync_state *tsp)
```

Estimate the skew based on current state.

Using the base and latest syncpoints from the state determine the skew of the local clock relative to the reference clock. See `timeutil_sync_state::skew`.

Parameters
• \( \text{tsp} \) – pointer to a time synchronization state. The base and latest syncpoints must be present and the latest syncpoint must be after the base point in the local time scale.

Returns
the estimated skew, or zero if skew could not be estimated.

```c
int timeutil_sync_ref_from_local(const struct timeutil_sync_state *tsp, uint64_t local, uint64_t *refp)
```

Interpolate a reference timescale instant from a local instant.

Parameters
• \( \text{tsp} \) – pointer to a time synchronization state. This must have a base and a skew installed.
• **local** – an instant measured in the local timescale. This may be before or after the base instant.

• **refp** – where the corresponding instant in the reference timescale should be stored. A negative interpolated reference time produces an error. If interpolation fails the referenced object is not modified.

**Return values**

• **0** – if interpolated using a skew of 1

• **1** – if interpolated using a skew not equal to 1

• **-EINVAL** –
  – the times synchronization state is not adequately initialized
  – **refp** is null

• **-ERANGE** – the interpolated reference time would be negative

```c
int timeutil_sync_local_from_ref(const struct timeutil_sync_state *tsp, uint64_t ref, int64_t *localp)
```

Interpolate a local timescale instant from a reference instant.

**Parameters**

• **tsp** – pointer to a time synchronization state. This must have a base and a skew installed.

• **ref** – an instant measured in the reference timescale. This may be before or after the base instant.

• **localp** – where the corresponding instant in the local timescale should be stored. An interpolated value before local time 0 is provided without error. If interpolation fails the referenced object is not modified.

**Return values**

• **0** – if successful with a skew of 1

• **1** – if successful with a skew not equal to 1

• **-EINVAL** –
  – the time synchronization state is not adequately initialized
  – **refp** is null

```c
int32_t timeutil_sync_skew_to_ppb(float skew)
```

Convert from a skew to an error in parts-per-billion.

A skew of 1.0 has zero error. A skew less than 1 has a positive error (clock is faster than it should be). A skew greater than one has a negative error (clock is slower than it should be).

Note that due to the limited precision of **float** compared with **double** the smallest error that can be represented is about 120 ppb. A “precise” time source may have error on the order of 2000 ppb.

A skew greater than 3.14748 may underflow the 32-bit representation; this represents a clock running at less than 1/3 its nominal rate.

**Returns**

skew error represented as parts-per-billion, or **INT32_MIN** if the skew cannot be represented in the return type.
struct `timeutil_sync_config`  

```c
#include <timeutil.h>
```

Immutable state for synchronizing two clocks. Values required to convert durations between two time scales.

**Note:** The accuracy of the translation and calculated skew between sources depends on the resolution of these frequencies. A reference frequency with microsecond or nanosecond resolution would produce the most accurate tracking when the local reference is the Zephyr tick counter. A reference source like an RTC chip with 1 Hz resolution requires a much larger interval between sampled instants to detect relative clock drift.

### Public Members

- `uint32_t ref_Hz`  
  The nominal instance counter rate in Hz.  
  This value is assumed to be precise, but may drift depending on the reference clock source.  
  The value must be positive.

- `uint32_t local_Hz`  
  The nominal local counter rate in Hz.  
  This value is assumed to be inaccurate but reasonably stable. For a local clock driven by a crystal oscillator an error of 25 ppm is common; for an RC oscillator larger errors should be expected. The timeutil sync infrastructure can calculate the skew between the local and reference clocks and apply it when converting between time scales.  
  The value must be positive.

struct `timeutil_sync_instant`  

```c
#include <timeutil.h>
```

Representation of an instant in two time scales.

Capturing the same instant in two time scales provides a registration point that can be used to convert between those time scales.

### Public Members

- `uint64_t ref`  
  An instant in the reference time scale.  
  This must never be zero in an initialized `timeutil_sync_instant` object.

- `uint64_t local`  
  The corresponding instance in the local time scale.  
  This may be zero in a valid `timeutil_sync_instant` object.
struct timeutil_sync_state
    #include <timeutil.h> State required to convert instants between time scales. 
    This state in conjunction with functions that manipulate it capture the offset information necessary to convert between two timescales along with information that corrects for skew due to inaccuracies in clock rates. 
    State objects should be zero-initialized before use. 

Public Members

const struct timeutil_sync_config *cfg
    Pointer to reference and local rate information. 

struct timeutil_sync_instant base
    The base instant in both time scales. 

struct timeutil_sync_instant latest
    The most recent instant in both time scales. 
    This is captured here to provide data for skew calculation. 

float skew
    The scale factor used to correct for clock skew. 
    The nominal rate for the local counter is assumed to be inaccurate but stable, i.e. it will generally be some parts-per-million faster or slower than specified. 
    A duration in observed local clock ticks must be multiplied by this value to produce a duration in ticks of a clock operating at the nominal local rate. 
    A zero value indicates that the skew has not been initialized. If the value is zero when base is initialized the skew will be set to 1. Otherwise the skew is assigned through timeutil_sync_state_set_skew().

3.8.3 Concepts Underlying Time Support in Zephyr

Terms from ISO/TC 154/WG 5 N0038 (ISO/WD 8601-1) and elsewhere:

- A time axis is a representation of time as an ordered sequence of instants. 
- A time scale is a way of representing an instant relative to an origin that serves as the epoch. 
- A time scale is monotonic (increasing) if the representation of successive time instants never decreases in value. 
- A time scale is continuous if the representation has no abrupt changes in value, e.g. jumping forward or back when going between successive instants. 
- Civil time generally refers to time scales that legally defined by civil authorities, like local governments, often to align local midnight to solar time. 

Relevant Time Scales

International Atomic Time (TAI) is a time scale based on averaging clocks that count in SI seconds. TAI is a monotonic and continuous time scale.
Universal Time (UT) is a time scale based on Earth’s rotation. UT is a discontinuous time scale as it requires occasional adjustments (leap seconds) to maintain alignment to changes in Earth’s rotation. Thus the difference between TAI and UT varies over time. There are several variants of UT, with UTC being the most common.

UT times are independent of location. UT is the basis for Standard Time (or “local time”) which is the time at a particular location. Standard time has a fixed offset from UT at any given instant, primarily influenced by longitude, but the offset may be adjusted (“daylight saving time”) to align standard time to the local solar time. In a sense local time is “more discontinuous” than UT.

POSIX Time is a time scale that counts seconds since the “POSIX epoch” at 1970-01-01T00:00:00Z (i.e. the start of 1970 UTC). UNIX Time is an extension of POSIX time using negative values to represent times before the POSIX epoch. Both of these scales assume that every day has exactly 86400 seconds. In normal use instants in these scales correspond to times in the UTC scale, so they inherit the discontinuity.

The continuous analogue is UNIX Leap Time which is UNIX time plus all leap-second corrections added after the POSIX epoch (when TAI-UTC was 8 s).

Example of Time Scale Differences A positive leap second was introduced at the end of 2016, increasing the difference between TAI and UTC from 36 seconds to 37 seconds. There was no leap second introduced at the end of 1999, when the difference between TAI and UTC was only 32 seconds. The following table shows relevant civil and epoch times in several scales:

<table>
<thead>
<tr>
<th>UTC Date</th>
<th>UNIX time</th>
<th>TAI Date</th>
<th>TAI-UTC</th>
<th>UNIX Leap Time</th>
</tr>
</thead>
<tbody>
<tr>
<td>1970-01-01T00:00:00Z</td>
<td>0</td>
<td>1970-01-01T00:00:08</td>
<td>+8</td>
<td>0</td>
</tr>
<tr>
<td>1999-12-31T23:59:28Z</td>
<td>946684768</td>
<td>2000-01-01T00:00:00</td>
<td>+32</td>
<td>946684792</td>
</tr>
<tr>
<td>1999-12-31T23:59:59Z</td>
<td>946684799</td>
<td>2000-01-01T00:00:00</td>
<td>+32</td>
<td>946684823</td>
</tr>
<tr>
<td>2000-01-01T00:00:00Z</td>
<td>946684800</td>
<td>2000-01-01T00:00:00</td>
<td>+32</td>
<td>946684824</td>
</tr>
<tr>
<td>2016-12-31T23:59:59Z</td>
<td>1483228799</td>
<td>2017-01-01T00:00:00</td>
<td>+36</td>
<td>1483228827</td>
</tr>
<tr>
<td>2016-12-31T23:59:60Z</td>
<td>undefined</td>
<td>2017-01-01T00:00:00</td>
<td>+36</td>
<td>1483228828</td>
</tr>
<tr>
<td>2017-01-01T00:00:00Z</td>
<td>1483228800</td>
<td>2017-01-01T00:00:00</td>
<td>+37</td>
<td>1483228829</td>
</tr>
</tbody>
</table>

Functional Requirements The Zephyr tick counter has no concept of leap seconds or standard time offsets and is a continuous time scale. However it can be relatively inaccurate, with drifts as much as three minutes per hour (assuming an RC timer with 5% tolerance).

There are two stages required to support conversion between Zephyr time and common human time scales:

- Translation between the continuous but inaccurate Zephyr time scale and an accurate external stable time scale;
- Translation between the stable time scale and the (possibly discontinuous) civil time scale.

The API around `timeutil_sync_state_update()` supports the first step of converting between continuous time scales.

The second step requires external information including schedules of leap seconds and local time offset changes. This may be best provided by an external library, and is not currently part of the time utility APIs.

Selecting an External Source and Time Scale If an application requires civil time accuracy within several seconds then UTC could be used as the stable time source. However, if the external source adjusts to a leap second there will be a discontinuity: the elapsed time between two observations taken at 1 Hz is not equal to the numeric difference between their timestamps.

For precise activities a continuous scale that is independent of local and solar adjustments simplifies things considerably. Suitable continuous scales include:
• GPS time: epoch of 1980-01-06T00:00:00Z, continuous following TAI with an offset of TAI-GPS=19 s.
• Bluetooth Mesh time: epoch of 2000-01-01T00:00:00Z, continuous following TAI with an offset of -32.
• UNIX Leap Time: epoch of 1970-01-01T00:00:00Z, continuous following TAI with an offset of -8.

Because C and Zephyr library functions support conversion between integral and calendar time representations using the UNIX epoch, UNIX Leap Time is an ideal choice for the external time scale.

The mechanism used to populate synchronization points is not relevant: it may involve reading from a local high-precision RTC peripheral, exchanging packets over a network using a protocol like NTP or PTP, or processing NMEA messages received a GPS with or without a 1pps signal.

### 3.9 Utilities

This page contains reference documentation for `<sys/util.h>`, which provides miscellaneous utility functions and macros.

```c
#include <sys/util.h>
```

#### Group `sys-util`

**Defines**

- `POINTER_TO_UINT(x)`
  Cast `x`, a pointer, to an unsigned integer.
- `UINT_TO_POINTER(x)`
  Cast `x`, an unsigned integer, to a `void*`.
- `POINTER_TO_INT(x)`
  Cast `x`, a pointer, to a signed integer.
- `INT_TO_POINTER(x)`
  Cast `x`, a signed integer, to a `void*`.
- `BITS_PER_LONG`:
  Number of bits in a long int.
- `BITS_PER_LONG_LONG`:
  Number of bits in a long long int.
- `GENMASK(h, l)`
  Create a contiguous bitmask starting at bit position `l` and ending at position `h`.
- `GENMASK64(h, l)`
  Create a contiguous 64-bit bitmask starting at bit position `l` and ending at position `h`.
- `LSB_GET(value)`
  Extract the Least Significant Bit from `value`.
- `FIELD_GET(mask, value)`
  Extract a bitfield element from `value` corresponding to the field mask `mask`. 
FIELD_PREP(mask, value)
    Prepare a bitfield element using value with mask representing its field position and width.
    The result should be combined with other fields using a logical OR.

ZERO_OR_COMPILE_ERROR(cond)
    0 if cond is true-ish; causes a compile error otherwise.

IS_ARRAY(array)
    Zero if array has an array type, a compile error otherwise.
    This macro is available only from C, not C++.

ARRAY_SIZE(array)
    Number of elements in the given array.
    In C++, due to language limitations, this will accept as array any type that implements operator[]. The results may not be particularly meaningful in this case.
    In C, passing a pointer as array causes a compile error.

IS_ARRAY_ELEMENT(array, ptr)
    Whether ptr is an element of array.
    This macro can be seen as a slightly stricter version of PART_OF_ARRAY in that it also ensures that ptr is aligned to an array-element boundary of array.
    In C, passing a pointer as array causes a compile error.

Parameters
    • array – the array in question
    • ptr – the pointer to check

Returns
    1 if ptr is part of array, 0 otherwise

ARRAY_INDEX(array, ptr)
    Index of ptr within array.
    With CONFIG_ASSERT=y, this macro will trigger a runtime assertion when ptr does not fall into the range of array or when ptr is not aligned to an array-element boundary of array.
    In C, passing a pointer as array causes a compile error.

Parameters
    • array – the array in question
    • ptr – pointer to an element of array

Returns
    the array index of ptr within array, on success

PART_OF_ARRAY(array, ptr)
    Check if a pointer ptr lies within array.
    In C but not C++, this causes a compile error if array is not an array (e.g. if ptr and array are mixed up).

Parameters
    • array – an array
    • ptr – a pointer
Returns
1 if ptr is part of array, 0 otherwise

ARRAY_INDEX_FLOOR(array, ptr)
Array-index of ptr within array, rounded down.
This macro behaves much like ARRAY_INDEX with the notable difference that it accepts any ptr in the range of array rather than exclusively a ptr aligned to an array-element boundary of array.
With CONFIG_ASSERT=y, this macro will trigger a runtime assertion when ptr does not fall into the range of array.
In C, passing a pointer as array causes a compile error.

Parameters
• array – the array in question
• ptr – pointer to an element of array

Returns
the array index of ptr within array, on success

ARRAY_FOR_EACH(array, idx)
Iterate over members of an array using an index variable.

Parameters
• array – the array in question
• idx – name of array index variable

ARRAY_FOR_EACH_PTR(array, ptr)
Iterate over members of an array using a pointer.

Parameters
• array – the array in question
• ptr – pointer to an element of array

SAME_TYPE(a, b)
Validate if two entities have a compatible type.

Parameters
• a – the first entity to be compared
• b – the second entity to be compared

Returns
1 if the two elements are compatible, 0 if they are not

CONTAINER_OF_VALIDATE(ptr, type, field)
Validate CONTAINER_OF parameters, only applies to C mode.

CONTAINER_OF(ptr, type, field)
Get a pointer to a structure containing the element.
Example:

```c
struct foo {
    int bar;
};

struct foo my_foo;
int *ptr = &my_foo.bar;
```
Above, container points at my_foo.

**Parameters**

- `ptr` – pointer to a structure element
- `type` – name of the type that `ptr` is an element of
- `field` – the name of the field within the struct `ptr` points to

**Returns**

a pointer to the structure that contains `ptr`

**CONCAT(...)**

Concatenate input arguments.

Concatenate provided tokens into a combined token during the preprocessor pass. This can be used to, for ex., build an identifier out of multiple parts, where one of those parts may be, for ex, a number, another macro, or a macro argument.

**Parameters**

- `...` – Tokens to concatenate

**Returns**

Concatenated token.

**ROUND_UP(x, align)**

Value of `x` rounded up to the next multiple of `align`.

**ROUND_DOWN(x, align)**

Value of `x` rounded down to the previous multiple of `align`.

**WB_UP(x)**

Value of `x` rounded up to the next word boundary.

**WB_DN(x)**

Value of `x` rounded down to the previous word boundary.

**DIV_ROUND_UP(n, d)**

Divide and round up.

Example:

```c
DIV_ROUND_UP(1, 2); // 1
DIV_ROUND_UP(3, 2); // 2
```

**Parameters**

- `n` – Numerator.
- `d` – Denominator.

**Returns**

The result of `n / d`, rounded up.

**DIV_ROUND_CLOSEST(n, d)**

Divide and round to the nearest integer.

Example:
DIV_ROUND_CLOSEST(5, 2); // 3
DIV_ROUND_CLOSEST(5, -2); // -3
DIV_ROUND_CLOSEST(5, 3); // 2

Parameters
- n – Numerator.
- d – Denominator.

Returns
The result of \( n / d \), rounded to the nearest integer.

ceiling_fraction(numerator, divider)
Ceiling function applied to \( \frac{numerator}{divider} \) as a fraction.

 Deprecated:
Use DIV_ROUND_UP() instead.

MAX(a, b)
Obtain the maximum of two values.

Note: Arguments are evaluated twice. Use Z_MAX for a GCC-only, single evaluation version.

Parameters
- a – First value.
- b – Second value.

Returns
Maximum value of \( a \) and \( b \).

MIN(a, b)
Obtain the minimum of two values.

Note: Arguments are evaluated twice. Use Z_MIN for a GCC-only, single evaluation version.

Parameters
- a – First value.
- b – Second value.

Returns
Minimum value of \( a \) and \( b \).

CLAMP(val, low, high)
Clamp a value to a given range.

Note: Arguments are evaluated multiple times. Use Z_CLAMP for a GCC-only, single evaluation version.

Parameters
• val – Value to be clamped.
• low – Lowest allowed value (inclusive).
• high – Highest allowed value (inclusive).

**Returns**
Clamped value.

**IN_RANGE(val, min, max)**
Checks if a value is within range.

**Note:** val is evaluated twice.

**Parameters**
• val – Value to be checked.
• min – Lower bound (inclusive).
• max – Upper bound (inclusive).

**Return values**
• true – If value is within range
• false – If the value is not within range

**LOG2(x)**
Compute log2(x)

**Note:** This macro expands its argument multiple times (to permit use in constant expressions), which must not have side effects.

**Parameters**
• x – An unsigned integral value to compute logarithm of (positive only)

**Returns**
log2(x) when 1 <= x <= max(x), -1 when x < 1

**LOG2CEIL(x)**
Compute ceil(log2(x))

**Note:** This macro expands its argument multiple times (to permit use in constant expressions), which must not have side effects.

**Parameters**
• x – An unsigned integral value

**Returns**
ceil(log2(x)) when 1 <= x <= max(type(x)), 0 when x < 1

**NHPOT(x)**
Compute next highest power of two.
Equivalent to 2^ceil(log2(x))
Note: This macro expands its argument multiple times (to permit use in constant expressions), which must not have side effects.

Parameters

- \( x \) – An unsigned integral value

Returns

\( 2^{\lceil \log_2(x) \rceil} \) or 0 if \( 2^{\lceil \log_2(x) \rceil} \) would saturate 64-bits

**KB**\( (x) \)

Number of bytes in \( x \) kibibytes.

**MB**\( (x) \)

Number of bytes in \( x \) mebibytes.

**GB**\( (x) \)

Number of bytes in \( x \) gibibytes.

**KHZ**\( (x) \)

Number of Hz in \( x \) kHz.

**MHZ**\( (x) \)

Number of Hz in \( x \) MHz.

**WAIT\_FOR**(expr, timeout, delay\_stmt)

Wait for an expression to return true with a timeout.

Spin on an expression with a timeout and optional delay between iterations

Commonly needed when waiting on hardware to complete an asynchronous request to read/write/initialize/reset, but useful for any expression.

Parameters

- \( \text{expr} \) – Truth expression upon which to poll, e.g.: \( \text{XYZREG} \& \text{XYZREG\_EN} \)
- \( \text{timeout} \) – Timeout to wait for in microseconds, e.g.: 1000 (1ms)
- \( \text{delay\_stmt} \) – Delay statement to perform each poll iteration e.g.: NULL, \( \text{k\_yield()} \), \( \text{k\_msleep(1)} \) or \( \text{k\_busy\_wait(1)} \)

Return values

\( \text{expr} \) – As a boolean return, if false then it has timed out.

**BIT**\( (n) \)

Unsigned integer with bit position \( n \) set (signed in assembly language).

**BIT64**\( (_n) \)

64-bit unsigned integer with bit position \( _n \) set.

**WRITE\_BIT**(var, bit, set)

Set or clear a bit depending on a boolean value.

The argument \( \text{var} \) is a variable whose value is written to as a side effect.

Parameters

- \( \text{var} \) – Variable to be altered
- \( \text{bit} \) – Bit number
- \( \text{set} \) – if 0, clears \( \text{bit} \) in \( \text{var} \); any other value sets \( \text{bit} \)

---

Chapter 3. Kernel
BIT_MASK(n)
Bit mask with bits 0 through n-1 (inclusive) set, or 0 if n is 0.

BIT64_MASK(n)
64-bit bit mask with bits 0 through n-1 (inclusive) set, or 0 if n is 0.

IS_POWER_OF_TWO(x)
Check if a x is a power of two.

IS_SHIFTED_BIT_MASK(m, s)
Check if bits are set continuously from the specified bit.
The macro is not dependent on the bit-width.

Parameters

• m – Check whether the bits are set continuously or not.
• s – Specify the lowest bit for that is continuously set bits.

IS_BIT_MASK(m)
Check if bits are set continuously from the LSB.

Parameters

• m – Check whether the bits are set continuously from LSB.

IS_ENABLED(config_macro)
Check for macro definition in compiler-visible expressions.

This trick was pioneered in Linux as the config_enabled() macro. It has the effect of
taking a macro value that may be defined to “1” or may not be defined at all and turning
it into a literal expression that can be handled by the C compiler instead of just the
preprocessor. It is often used with a CONFIG_FOO macro which may be defined to 1 via
Kconfig, or left undefined.

That is, it works similarly to #if defined(CONFIG_FOO) except that its expansion is a C
expression. Thus, much #ifdef usage can be replaced with equivalents like:

```c
if (IS_ENABLED(CONFIG_FOO)) {
    do_something_with_foo
}
```

This is cleaner since the compiler can generate errors and warnings for
do_something_with_foo even when CONFIG_FOO is undefined.

Note: Use of IS_ENABLED in a #if statement is discouraged as it doesn’t provide any
benefit vs plain #if defined()

Parameters

• config_macro – Macro to check

Returns

1 if config_macro is defined to 1, 0 otherwise (including if config_macro is
not defined)

COND_CODE_1(_flag, _if_1_code, _else_code)
Insert code depending on whether _flag expands to 1 or not.

This relies on similar tricks as IS_ENABLED(), but as the result of _flag expansion,
results in either _if_1_code or _else_code is expanded.

To prevent the preprocessor from treating commas as argument separators, the
_if_1_code and _else_code expressions must be inside brackets/parentheses: ().
These are stripped away during macro expansion.

Example:
COND_CODE_1(CONFIG_FLAG, (uint32_t x;), (there_is_no_flag();))

If CONFIG_FLAG is defined to 1, this expands to:

uint32_t x;

It expands to there_is_no_flag(); otherwise.

This could be used as an alternative to:

```c
#if defined(CONFIG_FLAG) && (CONFIG_FLAG == 1)
#define MAYBE_DECLARE(x) uint32_t x
#else
#define MAYBE_DECLARE(x) there_is_no_flag()
#endif
MAYBE_DECLARE(x);
```

However, the advantage of `COND_CODE_1()` is that code is resolved in place where it is used, while the `#if` method defines `MAYBE_DECLARE` on two lines and requires it to be invoked again on a separate line. This makes `COND_CODE_1()` more concise and also sometimes more useful when used within another macro's expansion.

**Note:** _flag can be the result of preprocessor expansion, e.g. an expression involving `NUM_VA_ARGS_LESS_1(...).` However, _if_1_code is only expanded if _flag expands to the integer literal 1. Integer expressions that evaluate to 1, e.g. after doing some arithmetic, will not work.

**Parameters**

- **_flag** – evaluated flag
- **_if_1_code** – result if _flag expands to 1; must be in parentheses
- **_else_code** – result otherwise; must be in parentheses

**COND_CODE_0(_flag, _if_0_code, _else_code)**

Like `COND_CODE_1()` except tests if _flag is 0.

This is like `COND_CODE_1()`, except that it tests whether _flag expands to the integer literal 0. It expands to _if_0_code if so, and _else_code otherwise; both of these must be enclosed in parentheses.

**See also:**

`COND_CODE_1()`

**Parameters**

- **_flag** – evaluated flag
- **_if_0_code** – result if _flag expands to 0; must be in parentheses
- **_else_code** – result otherwise; must be in parentheses

**IF_ENABLED(_flag, _code)**

Insert code if _flag is defined and equals 1.

Like `COND_CODE_1()`, this expands to _code if _flag is defined to 1; it expands to nothing otherwise.

Example:
IF_ENABLED(CONFIG_FLAG, (uint32_t foo;))

If CONFIG_FLAG is defined to 1, this expands to:

```
uint32_t foo;
```

and to nothing otherwise.

It can be considered as a more compact alternative to:

```
#if defined(CONFIG_FLAG) && (CONFIG_FLAG == 1)
uint32_t foo;
#endif
```

**Parameters**

- _flag – evaluated flag
- _code – result if _flag expands to 1; must be in parentheses

IF_DISABLED(_flag, _code)

Insert code if _flag is not defined as 1.

This expands to nothing if _flag is defined and equal to 1; it expands to _code otherwise.

Example:

```
IF_DISABLED(CONFIG_FLAG, (uint32_t foo;))
```

If CONFIG_FLAG isn’t defined or different than 1, this expands to:

```
uint32_t foo;
```

and to nothing otherwise.

IF_DISABLED does the opposite of IF_ENABLED.

**Parameters**

- _flag – evaluated flag
- _code – result if _flag does not expand to 1; must be in parentheses

IS_EMPTY(...)

Check if a macro has a replacement expression.

If a is a macro defined to a nonempty value, this will return true, otherwise it will return false. It only works with defined macros, so an additional ifdef test may be needed in some cases.

This macro may be used with COND_CODE_1() and COND_CODE_0() while processing __VA_ARGS__ to avoid processing empty arguments.

Example:

```
#define EMPTY
#define NON_EMPTY 1
#undef UNDEFINED
IS_EMPTY(EMPTY)
IS_EMPTY(NON_EMPTY)
IS_EMPTY(UNDEFINED)
#if defined(EMPTY) && IS_EMPTY(EMPTY) == true
some_conditional_code
#endif
```
In above examples, the invocations of `IS_EMPTY(…)` return true, false, and true; some conditional code is included.

**Parameters**

- ... – macro to check for emptiness (may be `__VA_ARGS__`)

**IS_EQ(a, b)**

Like `a == b`, but does evaluation and short-circuiting at C preprocessor time.

This however only works for integer literal from 0 to 4095.

**LIST_DROP_EMPTY(…)**

Remove empty arguments from list.

During macro expansion, `__VA_ARGS__` and other preprocessor generated lists may contain empty elements, e.g.:

```
#define LIST ,a,b,,d,
```

Using EMPTY to show each empty element, LIST contains:

```
EMPTY, a, b, EMPTY, d
```

When processing such lists, e.g. using `FOR_EACH()`, all empty elements will be processed, and may require filtering out. To make that process easier, it is enough to invoke `LIST_DROP_EMPTY` which will remove all empty elements.

Example:

```
LIST_DROP_EMPTY(LIST)
```

expands to:

```
a, b, d
```

**Parameters**

- ... – list to be processed

**EMPTY**

Macro with an empty expansion.

This trivial definition is provided for readability when a macro should expand to an empty result, which e.g. is sometimes needed to silence checkpatch.

Example:

```
#define LIST_ITEM(n) , item##n
```

The above would cause checkpatch to complain, but:

```
#define LIST_ITEM(n) EMPTY, item##n
```

would not.

**IDENTITY(V)**

Macro that expands to its argument.

This is useful in macros like `FOR_EACH()` when there is no transformation required on the list elements.

**Parameters**

- V – any value
GET_ARG_N(N, ...)  
Get nth argument from argument list.

**Parameters**  
- N – Argument index to fetch. Counter from 1.
- ... – Variable list of arguments from which one argument is returned.

**Returns**  
Nth argument.

GET_ARGS_LESS_N(N, ...)  
Strips n first arguments from the argument list.

**Parameters**  
- N – Number of arguments to discard.
- ... – Variable list of arguments.

**Returns**  
argument list without N first arguments.

UTIL_OR(a, b)  
Like a || b, but does evaluation and short-circuiting at C preprocessor time.

This is not the same as the binary || operator; in particular, a should expand to an integer literal 0 or 1. However, b can be any value.

This can be useful when b is an expression that would cause a build error when a is 1.

UTIL_AND(a, b)  
Like a && b, but does evaluation and short-circuiting at C preprocessor time.

This is not the same as the binary &&, however; in particular, a should expand to an integer literal 0 or 1. However, b can be any value.

This can be useful when b is an expression that would cause a build error when a is 0.

UTIL_INC(x)  
**UTIL_INC(x)** for an integer literal x from 0 to 4095 expands to an integer literal whose value is x+1.

**See also:**  
**UTIL_DEC(x)**

UTIL_DEC(x)  
**UTIL_DEC(x)** for an integer literal x from 0 to 4095 expands to an integer literal whose value is x-1.

**See also:**  
**UTIL_INC(x)**

UTIL_X2(y)  
**UTIL_X2(y)** for an integer literal y from 0 to 4095 expands to an integer literal whose value is 2y.

LISTIFY(LEN, F, sep, ...)  
Generates a sequence of code with configurable separator.
Example:
#define FOO(i, _) MY_PWM ## i
{ LISTIFY(PWM_COUNT, FOO, (_,)) }

The above two lines expand to:
{ MY_PWM0, MY_PWM1 }

Note: Calling LISTIFY with undefined arguments has undefined behavior.

Parameters

- **LEN** – The length of the sequence. Must be an integer literal less than 4095.
- **F** – A macro function that accepts at least two arguments: \( F(i, \ldots) \). \( F \) is called repeatedly in the expansion. Its first argument \( i \) is the index in the sequence, and the variable list of arguments passed to LISTIFY are passed through to \( F \).
- **sep** – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

**FOR_EACH(F, sep, ...)**

Call a macro \( F \) on each provided argument with a given separator between each call.

Example:

```c
#define F(x) int a##x
FOR_EACH(F, (;), 4, 5, 6);
```

This expands to:

```c
int a4;
int a5;
int a6;
```

Parameters

- **F** – Macro to invoke
- **sep** – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- **...** – Variable argument list. The macro \( F \) is invoked as \( F(element) \) for each element in the list.

**FOR_EACH_NONEMPTY_TERM(F, term, ...)**

Like **FOR_EACH()**, but with a terminator instead of a separator, and drops empty elements from the argument list.

The \( sep \) argument to **FOR_EACH(F, (sep), a, b)** is a separator which is placed between calls to \( F \), like this:

```c
FOR_EACH(F, (sep), a, b) // F(a) sep F(b)
```

// ^^^ no sep here!

By contrast, the \( term \) argument to **FOR_EACH_NONEMPTY_TERM(F, (term), a, b)** is added after each time \( F \) appears in the expansion:

```c
FOR_EACH_NONEMPTY_TERM(F, (term), a, b) // F(a) term F(b) term
```

// ^^^
Further, any empty elements are dropped:

```plaintext
FOR_EACH_NONEMPTY_TERM(F, (term), a, EMPTY, b) // F(a) term F(b) term
```

This is more convenient in some cases, because `FOR_EACH_NONEMPTY_TERM()` expands to nothing when given an empty argument list, and it’s often cumbersome to write a macro `F` that does the right thing even when given an empty argument.

One example is when `__VA_ARGS__` may or may not be empty, and the results are embedded in a larger initializer:

```plaintext
#define SQUARE(x) ((x)*(x))
int my_array[] = {
    FOR_EACH_NONEMPTY_TERM(SQUARE, (,), FOO(...))
    FOR_EACH_NONEMPTY_TERM(SQUARE, (,), BAR(...))
    FOR_EACH_NONEMPTY_TERM(SQUARE, (,), BAZ(...))
};
```

This is more convenient than:

a. figuring out whether the `FOO`, `BAR`, and `BAZ` expansions are empty and adding a comma manually (or not) between `FOR_EACH()` calls

b. rewriting `SQUARE` so it reacts appropriately when “x” is empty (which would be necessary if e.g. `FOO` expands to nothing)

**Parameters**

- `F` – Macro to invoke on each nonempty element of the variable arguments
- `term` – Terminator (e.g. comma or semicolon) placed after each invocation of `F`. Must be in parentheses; this is required to enable providing a comma as separator.
- `...` – Variable argument list. The macro `F` is invoked as `F(element)` for each nonempty element in the list.

**FOR_EACH_IDX(F, sep, ...)**

Call macro `F` on each provided argument, with the argument’s index as an additional parameter.

This is like `FOR_EACH()`, except `F` should be a macro which takes two arguments: `F(index, variable_arg)`.

**Example:**

```plaintext
#define F(idx, x) int a##idx = x
FOR_EACH_IDX(F, (;), 4, 5, 6);
```

This expands to:

```plaintext
int a0 = 4;
int a1 = 5;
int a2 = 6;
```

**Parameters**

- `F` – Macro to invoke
- `sep` – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
• ... – Variable argument list. The macro \( F \) is invoked as \( F(index, \text{element}) \) for each element in the list.

\texttt{FOR\_EACH\_FIXED\_ARG}(F, sep, fixed_arg, ...)

Call macro \( F \) on each provided argument, with an additional fixed argument as a parameter.

This is like \texttt{FOR\_EACH()}, except \( F \) should be a macro which takes two arguments: \( F(variable\_arg, fixed\_arg) \).

Example:

\begin{verbatim}
static void func(int val, void *dev);
FOR_EACH_FIXED_ARG(func, (;), dev, 4, 5, 6);
\end{verbatim}

This expands to:

\begin{verbatim}
func(4, dev);
func(5, dev);
func(6, dev);
\end{verbatim}

Parameters

• \( F \) – Macro to invoke
• \( sep \) – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
• \( fixed\_arg \) – Fixed argument passed to \( F \) as the second macro parameter.
• ... – Variable argument list. The macro \( F \) is invoked as \( F(element, fixed\_arg) \) for each element in the list.

\texttt{FOR\_EACH\_IDX\_FIXED\_ARG}(F, sep, fixed_arg, ...)

Calls macro \( F \) for each variable argument with an index and fixed argument.

This is like the combination of \texttt{FOR\_EACH\_IDX()} with \texttt{FOR\_EACH\_FIXED\_ARG()}. Example:

\begin{verbatim}
#define F(idx, x, fixed_arg) int fixed_arg##idx = x
FOR_EACH_IDX_FIXED_ARG(F, (;), a, 4, 5, 6);
\end{verbatim}

This expands to:

\begin{verbatim}
int a0 = 4;
int a1 = 5;
int a2 = 6;
\end{verbatim}

Parameters

• \( F \) – Macro to invoke
• \( sep \) – Separator (e.g. comma or semicolon). Must be in parentheses; This is required to enable providing a comma as separator.
• \( fixed\_arg \) – Fixed argument passed to \( F \) as the third macro parameter.
• ... – Variable list of arguments. The macro \( F \) is invoked as \( F(index, element, fixed\_arg) \) for each element in the list.

\texttt{REVERSE\_ARGS(...)}

Reverse arguments order.

Parameters
• ... – Variable argument list.

**NUM_VA_ARGS_LESS_1(...)**
Number of arguments in the variable arguments list minus one.

**Parameters**
• ... – List of arguments

**Returns**
Number of variadic arguments in the argument list, minus one

**MACRO_MAP_CAT(...)**
Mapping macro that pastes results together.
This is similar to `FOR_EACH()` in that it invokes a macro repeatedly on each element of `__VA_ARGS__`. However, unlike `FOR_EACH()`, `MACRO_MAP_CAT()` pastes the results together into a single token.

For example, with this macro `FOO`:
```c
#define FOO(x) item_##x##_
```

`MACRO_MAP_CAT(FOO, a, b, c)`, expands to the token:

```c
item_a_item_b_item_c_```

**Parameters**
• ... – Macro to expand on each argument, followed by its arguments.
   (The macro should take exactly one argument.)

**Returns**
The results of expanding the macro on each argument, all pasted together

**MACRO_MAP_CAT_N(N, ...)**
Mapping macro that pastes a fixed number of results together.
Similar to `MACRO_MAP_CAT()`, but expects a fixed number of arguments. If more arguments are given than are expected, the rest are ignored.

**Parameters**
• N – Number of arguments to map
• ... – Macro to expand on each argument, followed by its arguments.
   (The macro should take exactly one argument.)

**Returns**
The results of expanding the macro on each argument, all pasted together

**Functions**

static inline bool is_power_of_two(unsigned int x)
Is x a power of two?

**Parameters**
• x – value to check

**Returns**
true if x is a power of two, false otherwise
static inline int64_t arithmetic_shift_right(int64_t value, uint8_t shift)
    Arithmetic shift right.

    Parameters
    • value – value to shift
    • shift – number of bits to shift

    Returns
    value shifted right by shift; opened bit positions are filled with the sign bit

static inline void bytecpy(void *dst, const void *src, size_t size)
    byte by byte memcpy.

    Copy size bytes of src into dest. This is guaranteed to be done byte by byte.

    Parameters
    • dst – Pointer to the destination memory.
    • src – Pointer to the source of the data.
    • size – The number of bytes to copy.

static inline void byteswp(void *a, void *b, size_t size)
    byte by byte swap.

    Swap size bytes between memory regions a and b. This is guaranteed to be done byte by byte.

    Parameters
    • a – Pointer to the the first memory region.
    • b – Pointer to the the second memory region.
    • size – The number of bytes to swap.

int char2hex(char c, uint8_t *x)
    Convert a single character into a hexadecimal nibble.

    Parameters
    • c – The character to convert
    • x – The address of storage for the converted number.

    Returns
    Zero on success or (negative) error code otherwise.

int hex2char(uint8_t x, char *c)
    Convert a single hexadecimal nibble into a character.

    Parameters
    • c – The number to convert
    • x – The address of storage for the converted character.

    Returns
    Zero on success or (negative) error code otherwise.

size_t bin2hex(const uint8_t *buf, size_t buflen, char *hex, size_t hexlen)
    Convert a binary array into string representation.

    Parameters
    • buf – The binary array to convert
    • buflen – The length of the binary array to convert
• **hex** – Address of where to store the string representation.
• **hexlen** – Size of the storage area for string representation.

**Returns**
The length of the converted string, or 0 if an error occurred.

```c
size_t hex2bin(const char *hex, size_t hexlen, uint8_t *buf, size_t buflen)
```
Convert a hexadecimal string into a binary array.

**Parameters**
• **hex** – The hexadecimal string to convert
• **hexlen** – The length of the hexadecimal string to convert.
• **buf** – Address of where to store the binary data
• **buflen** – Size of the storage area for binary data

**Returns**
The length of the binary array, or 0 if an error occurred.

```c
static inline uint8_t bcd2bin(uint8_t bcd)
```
Convert a binary coded decimal (BCD 8421) value to binary.

**Parameters**
• **bcd** – BCD 8421 value to convert.

**Returns**
Binary representation of input value.

```c
static inline uint8_t bin2bcd(uint8_t bin)
```
Convert a binary value to binary coded decimal (BCD 8421).

**Parameters**
• **bin** – Binary value to convert.

**Returns**
BCD 8421 representation of input value.

```c
uint8_t u8_to_dec(char *buf, uint8_t buflen, uint8_t value)
```
Convert a uint8_t value into its ASCII decimal string representation. The string is terminated if there is enough space in buf.

**Parameters**
• **buf** – Address of where to store the string representation.
• **buflen** – Size of the storage area for string representation.
• **value** – The value to convert to decimal string

**Returns**
The length of the converted string (excluding terminator if any), or 0 if an error occurred.

```c
char *utf8_trunc(char *utf8_str)
```
Properly truncate a NULL-terminated UTF-8 string.

Take a NULL-terminated UTF-8 string and ensure that if the string has been truncated (by setting the NULL terminator) earlier by other means, that the string ends with a properly formatted UTF-8 character (1-4 bytes).

**Parameters**
• **utf8_str** – NULL-terminated string
Returns

Pointer to the utf8_str

static inline void mem_xor_n(uint8_t *dst, const uint8_t *src1, const uint8_t *src2, size_t len)

XOR n bytes.

Parameters

• dst – Destination of where to store result. Shall be len bytes.
• src1 – First source. Shall be len bytes.
• src2 – Second source. Shall be len bytes.
• len – Number of bytes to XOR.

static inline void mem_xor_32(uint8_t dst[4], const uint8_t src1[4], const uint8_t src2[4])

XOR 32 bits.

Parameters

• dst – Destination of where to store result. Shall be 32 bits.
• src1 – First source. Shall be 32 bits.
• src2 – Second source. Shall be 32 bits.

static inline void mem_xor_128(uint8_t dst[16], const uint8_t src1[16], const uint8_t src2[16])

XOR 128 bits.

Parameters

• dst – Destination of where to store result. Shall be 128 bits.
• src1 – First source. Shall be 128 bits.
• src2 – Second source. Shall be 128 bits.

3.10 Iterable Sections

This page contains the reference documentation for the iterable sections APIs, which can be used for defining iterable areas of equally-sized data structures, that can be iterated on using STRUCT_SECTION_FOREACH.
3.10.1 Usage

Iterable section elements are typically used by defining the data structure and associated initializer in a common header file, so that they can be instantiated anywhere in the code base.

```c
struct my_data {
    int a, b;
};
#define DEFINE_DATA(name, _a, _b) 
    STRUCT_SECTION_ITERABLE(my_data, name) = { \ 
        .a = _a, \ 
        .b = _b, \ 
    }

...DEFINE_DATA(d1, 1, 2);
DEFINE_DATA(d2, 3, 4);
DEFINE_DATA(d3, 5, 6);
```

Then the linker has to be setup to place the place the structure in a contiguous segment using one of the linker macros such as `ITERABLE_SECTION_RAM` or `ITERABLE_SECTION_ROM`. Custom linker snippets are normally declared using one of the `zephyr_linker_sources()` CMake functions, using the appropriate section identifier, `DATA_SECTIONS` for RAM structures and `SECTIONS` for ROM ones.

```c
# CMakeLists.txt
zephyr_linker_sources(DATA_SECTIONS iterables.ld)

# iterables.ld
ITERABLE_SECTION_RAM(my_data, 4)
```

The data can then be accessed using `STRUCT_SECTION_FOREACH`.

```c
STRUCT_SECTION_FOREACH(my_data, data) {
    printk("%p: a: %d, b: %d\n", data, data->a, data->b);
}
```

**Note:** The linker is going to place the entries sorted by name, so the example above would visit d1, d2 and d3 in that order, regardless of how they were defined in the code.

3.10.2 API Reference

`group iterable_section_apis`

Iterable Sections APIs.

**Defines**

`ITERABLE_SECTION_ROM(struct_type, subalign)`

Define a read-only iterable section output.

Define an output section which will set up an iterable area of equally-sized data structures. For use with `STRUCT_SECTION_ITERABLE()`. Input sections will be sorted by name, per ld's SORT_BY_NAME.
This macro should be used for read-only data.

Note that this keeps the symbols in the image even though they are not being directly referenced. Use this when symbols are indirectly referenced by iterating through the section.

ITERABLE_SECTION_ROM_NUMERIC(struct_type, subalign)
Define a read-only iterable section output, sorted numerically.

This version of ITERABLE_SECTION_ROM() sorts the entries numerically, that is, SECNAME_10 will come after SECNAME_2. _ separator is required, and up to 2 numeric digits are handled (0-99).

See also:
ITERABLE_SECTION_ROM()

ITERABLE_SECTION_ROM_GC_ALLOWED(struct_type, subalign)
Define a garbage collectable read-only iterable section output.

Define an output section which will set up an iterable area of equally-sized data structures. For use with STRUCT_SECTION_ITERABLE(). Input sections will be sorted by name, per ld's SORT_BY_NAME.

This macro should be used for read-only data.

Note that the symbols within the section can be garbage collected.

ITERABLE_SECTION_RAM(struct_type, subalign)
Define a read-write iterable section output.

Define an output section which will set up an iterable area of equally-sized data structures. For use with STRUCT_SECTION_ITERABLE(). Input sections will be sorted by name, per ld's SORT_BY_NAME.

This macro should be used for read-write data that is modified at runtime.

Note that this keeps the symbols in the image even though they are not being directly referenced. Use this when symbols are indirectly referenced by iterating through the section.

ITERABLE_SECTION_RAM_NUMERIC(struct_type, subalign)
Define a read-write iterable section output, sorted numerically.

This version of ITERABLE_SECTION_RAM() sorts the entries numerically, that is, SECNAME10 will come after SECNAME2. Up to 2 numeric digits are handled (0-99).

See also:
ITERABLE_SECTION_RAM()

ITERABLE_SECTION_RAM_GC_ALLOWED(struct_type, subalign)
Define a garbage collectable read-write iterable section output.

Define an output section which will set up an iterable area of equally-sized data structures. For use with STRUCT_SECTION_ITERABLE(). Input sections will be sorted by name, per ld's SORT_BY_NAME.

This macro should be used for read-write data that is modified at runtime.

Note that the symbols within the section can be garbage collected.
Zephyr Project Documentation, Release 3.6.0-rc3

TYPE_SECTION_ITERABLE(type, varname, secname, section_postfix)
Defines a new element for an iterable section for a generic type.

Convenience helper combining __in_section() and Z_DECL.ALIGN(). The section name
will be ‘.[SECNAME].static.[SECTION_POSTFIX]’

In the linker script, create output sections for these using ITERABLE_SECTION_ROM() or
ITERABLE_SECTION_RAM().

Note: In order to store the element in ROM, a const specifier has to be added to the
declaration: const TYPE_SECTION_ITERABLE(…);

Parameters
• type – [in] data type of variable
• varname – [in] name of variable to place in section
• secname – [in] type name of iterable section.
• section_postfix – [in] postfix to use in section name

TYPE_SECTION_START(secname)
iterable section start symbol for a generic type
will return ‘_[OUT_TYPE]_list_start’.

Parameters
• secname – [in] type name of iterable section. For ‘struct foobar’ this
  would be TYPE_SECTION_START(foobar)

TYPE_SECTION_END(secname)
iterable section end symbol for a generic type
will return ‘_<SECNAME>_list_end’.

Parameters
• secname – [in] type name of iterable section. For ‘struct foobar’ this
  would be TYPE_SECTION_START(foobar)

TYPE_SECTION_START_EXTERN(type, secname)
iterable section extern for start symbol for a generic type
Helper macro to give extern for start of iterable section. The macro typically will be
called TYPE_SECTION_START_EXTERN(struct foobar; foobar). This allows the macro to
hand different types as well as cases where the type and section name may differ.

Parameters
• type – [in] data type of section
• secname – [in] name of output section

TYPE_SECTION_END_EXTERN(type, secname)
iterable section extern for end symbol for a generic type
Helper macro to give extern for end of iterable section. The macro typically will be
called TYPE_SECTION_END_EXTERN(struct foobar; foobar). This allows the macro to
hand different types as well as cases where the type and section name may differ.

Parameters
• type – [in] data type of section
• secname – [in] name of output section
TYPE_SECTION_FOREACH(type, secname, iterator)
Iterate over a specified iterable section for a generic type.

Iterator for structure instances gathered by `TYPE_SECTION_ITERABLE()`. The linker must provide a `<SECNAME>_list_start` symbol and a `<SECNAME>_list_end` symbol to mark the start and the end of the list of struct objects to iterate over. This is normally done using `ITERABLE_SECTION_ROM()` or `ITERABLE_SECTION_RAM()` in the linker script.

TYPE_SECTION_GET(type, secname, i, dst)
Get element from section for a generic type.

**Note:** There is no protection against reading beyond the section.

**Parameters**
- `type` – `[in]` type of element
- `secname` – `[in]` name of output section
- `i` – `[in]` Index.
- `dst` – `[out]` Pointer to location where pointer to element is written.

TYPE_SECTION_COUNT(type, secname, dst)
Count elements in a section for a generic type.

**Parameters**
- `type` – `[in]` type of element
- `secname` – `[in]` name of output section
- `dst` – `[out]` Pointer to location where result is written.

STRUCT_SECTION_START(struct_type)
iterable section start symbol for a struct type

**Parameters**
- `struct_type` – `[in]` data type of section

STRUCT_SECTION_START_EXTERN(struct_type)
iterable section extern for start symbol for a struct

Helper macro to give extern for start of iterable section.

**Parameters**
- `struct_type` – `[in]` data type of section

STRUCT_SECTION_END(struct_type)
iterable section end symbol for a struct type

**Parameters**
- `struct_type` – `[in]` data type of section

STRUCT_SECTION_END_EXTERN(struct_type)
iterable section extern for end symbol for a struct

Helper macro to give extern for end of iterable section.

**Parameters**
- `struct_type` – `[in]` data type of section
**STRUCT_SECTION_ITERABLE_ALTERNATE**(secname, struct_type, varname)
Defines a new element of alternate data type for an iterable section.

Special variant of **STRUCT_SECTION_ITERABLE()**, for placing alternate data types within the iterable section of a specific data type. The data type sizes and semantics must be equivalent!

**STRUCT_SECTION_ITERABLE_ARRAY_ALTERNATE**(secname, struct_type, varname, size)
Defines an array of elements of alternate data type for an iterable section.

**See also:**

**STRUCT_SECTION_ITERABLE_ALTERNATE**

**STRUCT_SECTION_ITERABLE**(struct_type, varname)
Defines a new element for an iterable section.

Convenience helper combining __in_section() and Z_DECL_ALIGN(). The section name is the struct type prepended with an underscore. The subsection is “static” and the subsubsection is the variable name.

In the linker script, create output sections for these using **ITERABLE_SECTION_ROM()** or **ITERABLE_SECTION_RAM()**.

**Note:** In order to store the element in ROM, a const specifier has to be added to the declaration: const **STRUCT_SECTION_ITERABLE(...)**;

**STRUCT_SECTION_ITERABLE_ARRAY**(struct_type, varname, size)
Defines an array of elements for an iterable section.

**See also:**

**STRUCT_SECTION_ITERABLE**

**STRUCT_SECTION_ITERABLE_NAMED**(struct_type, name, varname)
Defines a new element for an iterable section with a custom name.

The name can be used to customize how iterable section entries are sorted.

**See also:**

**STRUCT_SECTION_ITERABLE()**

**STRUCT_SECTION_ITERABLE_NAMED_ALTERNATE**(struct_type, secname, name, varname)
Defines a new element for an iterable section with a custom name, placed in a custom section.

The name can be used to customize how iterable section entries are sorted.

**See also:**

**STRUCT_SECTION_ITERABLE_NAMED()**

**STRUCT_SECTION_FOREACH_ALTERNATE**(secname, struct_type, iterator)
Iterate over a specified iterable section (alternate).

Iterator for structure instances gathered by **STRUCT_SECTION_ITERABLE()**. The linker must provide a _<SECNAME>_list_start symbol and a _<SECNAME>_list_end symbol to mark the start and the end of the list of struct objects to iterate over. This is normally done using **ITERABLE_SECTION_ROM()** or **ITERABLE_SECTION_RAM()** in the linker script.
Zephyr Project Documentation, Release 3.6.0-rc3

**STRUCT_SECTION_FOREACH**(struct_type, iterator)
Iterate over a specified iterable section.

Iterator for structure instances gathered by **STRUCT_SECTION_ITERABLE()**. The linker must provide a \_<struct_type>_list_start symbol and a \_<struct_type>_list_end symbol to mark the start and the end of the list of struct objects to iterate over. This is normally done using **ITERABLE_SECTION_ROM()** or **ITERABLE_SECTION_RAM()** in the linker script.

**STRUCT_SECTION_GET**(struct_type, i, dst)
Get element from section.

**Note:** There is no protection against reading beyond the section.

**Parameters**
- i – [in] Index.
- dst – [out] Pointer to location where pointer to element is written.

**STRUCT_SECTION_COUNT**(struct_type, dst)
Count elements in a section.

**Parameters**
- struct_type – [in] Struct type
- dst – [out] Pointer to location where result is written.

3.11 Code And Data Relocation

3.11.1 Overview

This feature will allow relocating .text, .rodata, .data, and .bss sections from required files and place them in the required memory region. The memory region and file are given to the scripts/build/gen_relocate_app.py script in the form of a string. This script is always invoked from inside cmake.

This script provides a robust way to re-order the memory contents without actually having to modify the code. In simple terms this script will do the job of \__attribute__((section("name"))) for a bunch of files together.

3.11.2 Details

The memory region and file are given to the scripts/build/gen_relocate_app.py script in the form of a string.

An example of such a string is: SRAM2:/home/xyz/zephyr/samples/hello_world/src/main.c, SRAM1:/home/xyz/zephyr/samples/hello_world/src/main2.c

This script is invoked with the following parameters: python3 gen_relocate_app.py -i input_string -o generated_linker -c generated_code

Kconfig CONFIG_CODE_DATA_RELOCATION option, when enabled in prj.conf, will invoke the script and do the required relocation.
This script also triggers the generation of linker_relocate.ld and code_relocation.c files. The linker_relocate.ld file creates appropriate sections and links the required functions or variables from all the selected files.

**Note:** The text section is split into 2 parts in the main linker script. The first section will have some info regarding vector tables and other debug related info. The second section will have the complete text section. This is needed to force the required functions and data variables to the correct locations. This is due to the behavior of the linker. The linker will only link once and hence this text section had to be split to make room for the generated linker script.

The code_relocation.c file has code that is needed for initializing data sections, and a copy of the text sections (if XIP). Also this contains code needed for bss zeroing and for data copy operations from ROM to required memory type.

**The procedure to invoke this feature is:**

- Enable CONFIG_CODE_DATA_RELOCATION in the prj.conf file
- Inside the CMakeLists.txt file in the project, mention all the files that need relocation.
  
  ```
  zephyr_code_relocate(FILES src/*.c LOCATION SRAM2)
  ```
  
  Where the first argument is the file/files and the second argument is the memory where it must be placed.

  **Note:** function zephyr_code_relocate() can be called as many times as required.

**Additional Configurations**

This section shows additional configuration options that can be set in CMakeLists.txt

- if the memory is SRAM1, SRAM2, CCD, or AON, then place the full object in the sections for example:
  
  ```
  zephyr_code_relocate(FILES src/file1.c LOCATION SRAM2)
  zephyr_code_relocate(FILES src/file2.c LOCATION SRAM)
  ```

- if the memory type is appended with _DATA, _TEXT, _RODATA or _BSS, only the selected memory is placed in the required memory region. for example:
  
  ```
  zephyr_code_relocate(FILES src/file1.c LOCATION SRAM2_DATA)
  zephyr_code_relocate(FILES src/file2.c LOCATION SRAM2_TEXT)
  ```

- Multiple regions can also be appended together such as: SRAM2_DATA_BSS. This will place data and bss inside SRAM2.
- Multiple files can be passed to the FILES argument, or CMake generator expressions can be used to relocate a comma-separated list of files
  
  ```
  file(GLOB sources "file*.c")
  zephyr_code_relocate(FILES ${sources} LOCATION SRAM)
  zephyr_code_relocate(FILES $<TARGET_PROPERTY:my_tgt,SOURCES> LOCATION SRAM)
  ```

**NOKEEP flag**

By default, all relocated functions and variables will be marked with KEEP() when generating linker_relocate.ld. Therefore, if any input file happens to contain unused symbols, then they
will not be discarded by the linker, even when it is invoked with --gc-sections. If you’d like to override this behavior, you can pass NOKEEP to your zephyr_code_relocate() call.

```c
zephyr_code_relocate(FILES src/file1.c LOCATION SRAM2_TEXT NOKEEP)
```

The example above will help ensure that any unused code found in the .text sections of file1.c will not stick to SRAM2.

**NOCOPY flag**

When a NOCOPY option is passed to the zephyr_code_relocate() function, the relocation code is not generated in code_relocation.c. This flag can be used when we want to move the content of a specific file (or set of files) to a XIP area.

This example will place the .text section of the xip_external_flash.c file to the EXTFLASH memory region where it will be executed from (XIP). The .data will be relocated as usual into SRAM.

```c
zephyr_code_relocate(FILES src/xip_external_flash.c LOCATION EXTFLASH_TEXT NOCOPY)
zephyr_code_relocate(FILES src/xip_external_flash.c LOCATION SRAM_DATA)
```

**Relocating libraries**

Libraries can be relocated using the LIBRARY argument to zephyr_code_relocate() with the library name. For example, the following snippet will relocate kernel code to ITCM and serial drivers to SRAM2:

```c
zephyr_code_relocate(LIBRARY kernel LOCATION ITCM_TEXT)
zephyr_code_relocate(LIBRARY drivers__serial LOCATION SRAM2)
```

**Samples/Tests**

A test showcasing this feature is provided at `$ZEPHYR_BASE/tests/application_development/code_relocation`

This test shows how the code relocation feature is used.

This test will place .text, .data, .bss from 3 files to various parts in the SRAM using a custom linker file derived from include/zephyr/arch/arm/cortex_m/scripts/linker.ld

A sample showcasing the NOCOPY flag is provided at `$ZEPHYR_BASE/samples/application_development/code_relocation_nocopy/`
Chapter 4

OS Services

4.1 Binary Descriptors

Binary Descriptors are constant data objects storing information about the binary executable. Unlike “regular” constants, binary descriptors are linked to a known offset in the binary, making them accessible to other programs, such as a different image running on the same device or a host tool. A few examples of constants that would make useful binary descriptors are: kernel version, app version, build time, compiler version, environment variables, compiling host name, etc.

Binary descriptors are created by using the DEFINE_BINDESC_* macros. For example:

```c
#include <zephyr/bindesc.h>
BINDESC_STR_DEFINE(my_string, 2, "Hello world!"); // Unique ID is 2
```

my_string could then be accessed using:

```c
printk("my_string: %s\n", BINDESC_GET_STR(my_string));
```

But it could also be retrieved by `west bindesc`:

```
$ west bindesc custom_search STR 2 build/zephyr/zephyr.bin
"Hello world!"
```

4.1.1 Internals

Binary descriptors are implemented with a TLV (tag, length, value) header linked to a known offset in the binary image. This offset may vary between architectures, but generally the descriptors are linked as close to the beginning of the image as possible. In architectures where the image must begin with a vector table (such as ARM), the descriptors are linked right after the vector table. The reset vector points to the beginning of the text section, which is after the descriptors. In architectures where the image must begin with executable code (e.g. x86), a jump instruction is injected at the beginning of the image, in order to skip over the binary descriptors, which are right after the jump instruction.

Each tag is a 16 bit unsigned integer, where the most significant nibble (4 bits) is the type (currently uint, string or bytes), and the rest is the ID. The ID is globally unique to each descriptor. For example, the ID of the app version string is 0x800, and a string is denoted by 0x1, making the app version tag 0x1800. The length is a 16 bit number equal to the length of the data in bytes. The data is the actual descriptor value. All binary descriptor numbers (magic, tags, uints) are laid out in memory in the endianness native to the SoC. `west bindesc` assumes little endian by
default, so if the image belongs to a big endian SoC, the appropriate flag should be given to the tool.

The binary descriptor header starts with the magic number \(0xb9863e5a7ea46046\). It's followed by the TLVs, and ends with the DESCRIPROTORS_END (0xffff) tag. The tags are always aligned to 32 bits. If the value of the previous descriptor had a non-aligned length, zero padding will be added to ensure that the current tag is aligned.

Putting it all together, here is what the example above would look like in memory (of a little endian SoC):

```
46 60 a4 7e 5a 3e 86 b9 02 10 0d 00 48 65 6c 6c 6f 20 77 6f 72 6c 64 21 00 00 00 00 ff ff
```

| magic | tag | length | H e l l o w o r l d ! | pad | end |

### 4.1.2 Usage

Binary descriptors are always created by the BINDESC_*_DEFINE macros. As shown in the example above, a descriptor can be generated from any string or integer, with any ID. However, it is recommended to comply with the standard tags defined in include/zephyr/bindesc.h, as that would have the following benefits:

1. The `west bindesc` tool would be able to recognize what the descriptor means and print a meaningful tag
2. It would enforce consistency between various apps from various sources
3. It allows upstream-ability of descriptor generation (see Standard Descriptors)

To define a descriptor with a standard tag, just use the tags included from bindesc.h:

```c
#include <zephyr/bindesc.h>
BINDESC_STR_DEFINE(app_version, BINDESC_ID_APP_VERSION_STRING, "1.2.3");
```

### Standard Descriptors

Some descriptors might be trivial to implement, and could therefore be implemented in a standard way in upstream Zephyr. These could then be enabled via Kconfig, instead of requiring every user to reimplement them. These include build times, kernel version, and host info. For example, to add the build date and time as a string, the following configs should be enabled:

```c
# Enable binary descriptors
CONFIG_BINDESC=y

# Enable definition of binary descriptors
CONFIG_BINDESC_DEFINE=y

# Enable default build time binary descriptors
CONFIG_BINDESC_DEFINE_BUILD_TIME=y
CONFIG_BINDESC_BUILD_DATE_TIME_STRING=y
```

To avoid collisions with user defined descriptors, the standard descriptors were allotted the range between 0x800-0xffff. This leaves 0x000-0x7ff to users. For more information read the help sections of these Kconfig symbols. By convention, each Kconfig symbol corresponds to a binary descriptor whose name is the Kconfig name (with `CONFIG_BINDESC_` removed) in lower case. For example, `CONFIG_BINDESC_KERNEL_VERSION_STRING` creates a descriptor that can be accessed using BINDESC_GET_STR(kernel_version_string).
west bindesc tool

west is able to parse and display binary descriptors from a given executable image. For more information refer to `west bindesc --help` or the documentation.

4.1.3 API Reference

**Related code samples**

**Binary descriptors "Hello World"**

Set and access binary descriptors for a basic Zephyr application.

```
group bindesc_define
    Binary Descriptor Definition.

Defines

BINDESC_ID_APP_VERSION_STRING
    The app version string such as "1.2.3".

BINDESC_ID_APP_VERSION_MAJOR
    The app version major such as 1.

BINDESC_ID_APP_VERSION_MINOR
    The app version minor such as 2.

BINDESC_ID_APP_VERSION_PATCHLEVEL
    The app version patchlevel such as 3.

BINDESC_ID_APP_VERSION_NUMBER
    The app version number such as 0x10203.

BINDESC_ID_KERNEL_VERSION_STRING
    The kernel version string such as "3.4.0".

BINDESC_ID_KERNEL_VERSION_MAJOR
    The kernel version major such as 3.

BINDESC_ID_KERNEL_VERSION_MINOR
    The kernel version minor such as 4.

BINDESC_ID_KERNEL_VERSION_PATCHLEVEL
    The kernel version patchlevel such as 0.

BINDESC_ID_KERNEL_VERSION_NUMBER
    The kernel version number such as 0x30400.
```
BINDESC_ID_BUILD_TIME_YEAR
The year the image was compiled in.

BINDESC_ID_BUILD_TIME_MONTH
The month of the year the image was compiled in.

BINDESC_ID_BUILD_TIME_DAY
The day of the month the image was compiled in.

BINDESC_ID_BUILD_TIME_HOUR
The hour of the day the image was compiled in.

BINDESC_ID_BUILD_TIME_MINUTE
The minute the image was compiled in.

BINDESC_ID_BUILD_TIME_SECOND
The second the image was compiled in.

BINDESC_ID_BUILD_TIME_UNIX
The UNIX time (seconds since midnight of 1970/01/01) the image was compiled in.

BINDESC_ID_BUILD_DATE_TIME_STRING
The date and time of compilation such as “2023/02/05 00:07:04”.

BINDESC_ID_BUILD_DATE_STRING
The date of compilation such as “2023/02/05”.

BINDESC_ID_BUILD_TIME_STRING
The time of compilation such as “00:07:04”.

BINDESC_ID_HOST_NAME
The name of the host that compiled the image.

BINDESC_ID_C_COMPILER_NAME
The C compiler name.

BINDESC_ID_C_COMPILER_VERSION
The C compiler version.

BINDESC_ID_CXX_COMPILER_NAME
The C++ compiler name.

BINDESC_ID_CXX_COMPILER_VERSION
The C++ compiler version.

BINDESC_TAG_DESCRIPTORS_END
**BINDESC_STR_DEFINE**(name, id, value)
Define a binary descriptor of type string.

Define a string that is registered in the binary descriptor header. The defined string can be accessed using **BINDESC_GET_STR**

**Note:** The defined string is not static, so its name must not collide with any other symbol in the executable.

**Parameters**
- *name* – Name of the descriptor
- *id* – Unique ID of the descriptor
- *value* – A string value for the descriptor

**BINDESC_UINT_DEFINE**(name, id, value)
Define a binary descriptor of type uint.

Define an integer that is registered in the binary descriptor header. The defined integer can be accessed using **BINDESC_GET_UINT**

**Note:** The defined integer is not static, so its name must not collide with any other symbol in the executable.

**Parameters**
- *name* – Name of the descriptor
- *id* – Unique ID of the descriptor
- *value* – An integer value for the descriptor

**BINDESC_BYTES_DEFINE**(name, id, value)
Define a binary descriptor of type bytes.

Define a uint8_t array that is registered in the binary descriptor header. The defined array can be accessed using **BINDESC_GET_BYTES**. The value should be given as an array literal, wrapped in parentheses, for example:

```
BINDESC_BYTES_DEFINE(name, id, ((1, 2, 3, 4)))
```

**Note:** The defined array is not static, so its name must not collide with any other symbol in the executable.

**Parameters**
- *name* – Name of the descriptor
- *id* – Unique ID of the descriptor
- *value* – A uint8_t array as data for the descriptor

**BINDESC_GET_STR**(name)
Get the value of a string binary descriptor.

Get the value of a string binary descriptor, previously defined by **BINDESC_STR_DEFINE**.

### 4.1. Binary Descriptors
Parameters

- name – Name of the descriptor

`BINCDESC_GET_UINT(name)`
Get the value of a uint binary descriptor.

Get the value of a uint binary descriptor, previously defined by `BINCDESC_UINT_DEFINE`.

Parameters

- name – Name of the descriptor

`BINCDESC_GET_BYTES(name)`
Get the value of a bytes binary descriptor.

Get the value of a string binary descriptor, previously defined by `BINCDESC_BYTES_DEFINE`. The returned value can be accessed as an array:

```c
for (size_t i = 0; i < BINCDESC_GET_SIZE(name); i++)
    BINCDESC_GET_BYTES(name)[i];
```

Parameters

- name – Name of the descriptor

`BINCDESC_GET_SIZE(name)`
Get the size of a binary descriptor.

Get the size of a binary descriptor. This is particularly useful for bytes binary descriptors where there’s no null terminator.

Parameters

- name – Name of the descriptor

### 4.2 Console

**Related code samples**

**Console echo**
Echo an input character back to the output using the Console API.

```c
group console_api
```

Console API.

**Functions**

`int console_init(void)`
Initialize console device.

This function should be called once to initialize pull-style access to console via `console_putchar()` function and buffered output using `console_putchar()` function. This function supersedes, and incompatible with, callback (push-style) console handling (via `console_putchar()` function).

**Returns**

0 on success, error code (<0) otherwise
ssize_t console_read(void *dummy, void *buf, size_t size)
Read data from console.

Parameters
  • dummy – ignored, present to follow read() prototype
  • buf – buffer to read data to
  • size – maximum number of bytes to read

Returns
  >0, number of actually read bytes (can be less than size param) =0, in case of EOF <0, in case of error (e.g. -EAGAIN if timeout expired). errno variable is also set.

ssize_t console_write(void *dummy, const void *buf, size_t size)
Write data to console.

Parameters
  • dummy – ignored, present to follow write() prototype
  • buf – buffer to write data to
  • size – maximum number of bytes to write

Returns
  =>0, number of actually written bytes (can be less than size param) <0, in case of error (e.g. -EAGAIN if timeout expired). errno variable is also set.

int console_getchar(void)
Get next char from console input buffer.

Return next input character from console. If no characters available, this function will block. This function is similar to ANSI C getchar() function and is intended to ease porting of existing software. Before this function can be used, console_init() should be called once. This function is incompatible with native Zephyr callback-based console input processing, shell subsystem, or console_getline().

Returns
  0-255: a character read, including control characters. <0: error occurred.

int console_putchar(char c)
Output a char to console (buffered).

Puts a character into console output buffer. It will be sent to a console asynchronously, e.g. using an IRQ handler.

Returns
  <0 on error; otherwise 0.

void console_getline_init(void)
Initialize console_getline() call.

This function should be called once to initialize pull-style access to console via console_getline() function. This function supersedes, and incompatible with, callback (push-style) console handling (via console_input_fn callback, etc.).

char *console_getline(void)
Get next line from console input buffer.

Return next input line from console. Until full line is available, this function will block. This function is similar to ANSI C gets() function (except a line is returned in system-owned buffer, and system takes care of the buffer overflow checks) and is intended to ease porting of existing software. Before this function can be used, console_getline_init() should be called once. This function is incompatible with native Zephyr callback-based console input processing, shell subsystem, or console_getchar().

4.2. Console
Returns
A pointer to a line read, not including EOL character(s). A line resides in a system-owned buffer, so an application should finish any processing of this line immediately after `console_getline()` call, or the buffer can be reused.

4.3 Cryptography

The crypto section contains information regarding the cryptographic primitives supported by the Zephyr kernel. Use the information to understand the principles behind the operation of the different algorithms and how they were implemented.

The following crypto libraries have been included:

4.3.1 TinyCrypt Cryptographic Library

Overview

The TinyCrypt Library provides an implementation for targeting constrained devices with a minimal set of standard cryptography primitives, as listed below. To better serve applications targeting constrained devices, TinyCrypt implementations differ from the standard specifications (see the Important Remarks section for some important differences). Certain cryptographic primitives depend on other primitives, as mentioned in the list below.

Aside from the Important Remarks section below, valuable information on the usage, security and technicalities of each cryptographic primitive are found in the corresponding header file.

- SHA-256:
  - Type of primitive: Hash function.
  - Requires: –

- HMAC-SHA256:
  - Type of primitive: Message authentication code.
  - Requires: SHA-256

- HMAC-PRNG:
  - Type of primitive: Pseudo-random number generator.
  - Standard Specification: NIST SP 800-90A.
  - Requires: SHA-256 and HMAC-SHA256.

- AES-128:
  - Type of primitive: Block cipher.
  - Requires: –

- AES-CBC mode:
  - Type of primitive: Encryption mode of operation.
  - Standard Specification: NIST SP 800-38A.
  - Requires: AES-128.
• AES-CTR mode:
  – Type of primitive: Encryption mode of operation.
  – Standard Specification: NIST SP 800-38A.
  – Requires: AES-128.

• AES-CMAC mode:
  – Type of primitive: Message authentication code.
  – Standard Specification: NIST SP 800-38B.
  – Requires: AES-128.

• AES-CCM mode:
  – Type of primitive: Authenticated encryption.
  – Standard Specification: NIST SP 800-38C.
  – Requires: AES-128.

• ECC-DH:
  – Type of primitive: Key exchange.
  – Requires: ECC auxiliary functions (ecc.h/c).

• ECC-DSA:
  – Type of primitive: Digital signature.
  – Requires: ECC auxiliary functions (ecc.h/c).

**Design Goals**

• Minimize the code size of each cryptographic primitive. This means minimize the size of a board-independent implementation, as presented in TinyCrypt. Note that various applications may require further features, optimizations with respect to other metrics and countermeasures for particular threats. These peculiarities would increase the code size and thus are not considered here.

• Minimize the dependencies among the cryptographic primitives. This means that it is unnecessary to build and allocate object code for more primitives than the ones strictly required by the intended application. In other words, one can select and compile only the primitives required by the application.

**Important Remarks**

The cryptographic implementations in TinyCrypt library have some limitations. Some of these limitations are inherent to the cryptographic primitives themselves, while others are specific to TinyCrypt. Some of these limitations are discussed in-depth below.

**General Remarks**

• TinyCrypt does **not** intend to be fully side-channel resistant. Due to the variety of side-channel attacks, many of them making certain boards vulnerable. In this sense, instead of penalizing all library users with side-channel countermeasures such as increasing the overall code size, TinyCrypt only implements certain generic timing-attack countermeasures.
Specific Remarks

• SHA-256:
  – The number of bits hashed in the state is not checked for overflow. Note however that this will only be a problem if you intend to hash more than $2^{64}$ bits, which is an extremely large window.

• HMAC:
  – The HMAC verification process is assumed to be performed by the application. This compares the computed tag with some given tag. Note that conventional memory-comparison methods (such as memcmp function) might be vulnerable to timing attacks; thus be sure to use a constant-time memory comparison function (such as compare_constant_time function provided in lib/utils.c).

• HMAC-PRNG:
  – Before using HMAC-PRNG, you must find an entropy source to produce a seed. PRNGs only stretch the seed into a seemingly random output of arbitrary length. The security of the output is exactly equal to the unpredictability of the seed.
  – NIST SP 800-90A requires three items as seed material in the initialization step: entropy seed, personalization and a nonce (which is not implemented). TinyCrypt requires the personalization byte array and automatically creates the entropy seed using a mandatory call to the re-seed function.

• AES-128:
  – The current implementation does not support other key-lengths (such as 256 bits). Note that if you need AES-256, it doesn’t sound as though your application is running in a constrained environment. AES-256 requires keys twice the size as for AES-128, and the key schedule is 40% larger.

• CTR mode:
  – The AES-CTR mode limits the size of a data message they encrypt to $2^{32}$ blocks. If you need to encrypt larger data sets, your application would need to replace the key after $2^{32}$ block encryptions.

• CBC mode:
  – TinyCrypt CBC decryption assumes that the iv and the ciphertext are contiguous (as produced by TinyCrypt CBC encryption). This allows for a very efficient decryption algorithm that would not otherwise be possible.

• CMAC mode:
  – AES128-CMAC mode of operation offers 64 bits of security against collision attacks. Note however that an external attacker cannot generate the tags him/herself without knowing the MAC key. In this sense, to attack the collision property of AES128-CMAC, an external attacker would need the cooperation of the legal user to produce an exponentially high number of tags (e.g. $2^{64}$) to finally be able to look for collisions and benefit from them. As an extra precaution, the current implementation allows to at most $2^{48}$ calls to tc_cmac_update function before re-calling tc_cmac_setup (allowing a new key to be set), as suggested in Appendix B of SP 800-38B.

• CCM mode:
  – There are a few tradeoffs for the selection of the parameters of CCM mode. In special, there is a tradeoff between the maximum number of invocations of CCM under a given key and the maximum payload length for those invocations. Both things are related to the parameter ‘q’ of CCM mode. The maximum number of invocations of CCM under a given key is determined by the nonce size, which is: 15-q bytes. The maximum payload length for those invocations is defined as $2^{(8q)}$ bytes.
To achieve minimal code size, TinyCrypt CCM implementation fixes \( q = 2 \), which is a quite reasonable choice for constrained applications. The implications of this choice are:

The nonce size is: 13 bytes.

The maximum payload length is: \( 2^{16} \) bytes = 65 KB.

The mac size parameter is an important parameter to estimate the security against collision attacks (that aim at finding different messages that produce the same authentication tag). TinyCrypt CCM implementation accepts any even integer between 4 and 16, as suggested in SP 800-38C.

- TinyCrypt CCM implementation accepts associated data of any length between 0 and \( (2^{16} - 2^8) = 65280 \) bytes.
- TinyCrypt CCM implementation accepts:
  * Both non-empty payload and associated data (it encrypts and authenticates the payload and only authenticates the associated data);
  * Non-empty payload and empty associated data (it encrypts and authenticates the payload);
  * Non-empty associated data and empty payload (it degenerates to an authentication-only mode on the associated data).

- RFC-3610, which also specifies CCM, presents a few relevant security suggestions, such as: it is recommended for most applications to use a mac size greater than 8. Besides, it is emphasized that the usage of the same nonce for two different messages which are encrypted with the same key obviously destroys the security properties of CCM mode.

- ECC-DH and ECC-DSA:
  - TinyCrypt ECC implementation is based on nano-ecc (see https://github.com/iSECPartners/nano-ecc) which in turn is based on micro-ecc (see https://github.com/kmackay/micro-ecc). In the original nano and micro-ecc documentation, there is an important remark about the way integers are represented:
    “Integer representation: To reduce code size, all large integers are represented using little-endian words - so the least significant word is first. You can use the ‘ecc_bytes2native()’ and ‘ecc_native2bytes()’ functions to convert between the native integer representation and the standardized octet representation.”

Examples of Applications

It is possible to do useful cryptography with only the given small set of primitives. With this list of primitives it becomes feasible to support a range of cryptography usages:

- Measurement of code, data structures, and other digital artifacts (SHA256);
- Generate commitments (SHA256);
- Construct keys (HMAC-SHA256);
- Extract entropy from strings containing some randomness (HMAC-SHA256);
- Construct random mappings (HMAC-SHA256);
- Construct nonces and challenges (HMAC-PRNG);
- Authenticate using a shared secret (HMAC-SHA256);
- Create an authenticated, replay-protected session (HMAC-SHA256 + HMAC-PRNG);
- Authenticated encryption (AES-128 + AES-CCM);
- Key-exchange (EC-DH);
Test Vectors

The library provides a test program for each cryptographic primitive (see ‘test’ folder). Besides illustrating how to use the primitives, these tests evaluate the correctness of the implementations by checking the results against well-known publicly validated test vectors.

For the case of the HMAC-PRNG, due to the necessity of performing an extensive battery test to produce meaningful conclusions, we suggest the user to evaluate the unpredictability of the implementation by using the NIST Statistical Test Suite (see References).

For the case of the EC-DH and EC-DSA implementations, most of the test vectors were obtained from the site of the NIST Cryptographic Algorithm Validation Program (CAVP), see References.

References

- NIST FIPS PUB 180-4 (SHA-256)
- NIST FIPS PUB 197 (AES-128)
- NIST SP800-90A (HMAC-PRNG)
- NIST SP 800-38A (AES-CBC and AES-CTR)
- NIST SP 800-38B (AES-CMAC)
- NIST SP 800-38C (AES-CCM)
- NIST Statistical Test Suite
- NIST Cryptographic Algorithm Validation Program (CAVP) site
- RFC 2104 (HMAC-SHA256)
- RFC 6090 (ECC-DH and ECC-DSA)

4.3.2 Random Number Generation

The random API subsystem provides random number generation APIs in both cryptographically and non-cryptographically secure instances. Which random API to use is based on the cryptographic requirements of the random number. The non-cryptographic APIs will return random values much faster if non-cryptographic values are needed.

The cryptographically secure random functions shall be compliant to the FIPS 140-2 [?] recommended algorithms. Hardware based random-number generators (RNG) can be used on platforms with appropriate hardware support. Platforms without hardware RNG support shall use the CTR-DRBG algorithm. The algorithm can be provided by TinyCrypt or mbedTLS depending on your application performance and resource requirements.

Note: The CTR-DRBG generator needs an entropy source to establish and maintain the cryptographic security of the PRNG.

Kconfig Options

These options can be found in the following path subsys/random/Kconfig.
CONFIG_TEST_RANDOM_GENERATOR
For testing, this option allows a non-random number generator to be used and permits random number APIs to return values that are not truly random.

The random number generator choice group allows selection of the RNG source function for the system via the RNG_GENERATOR_CHOICE choice group. An override of the default value can be specified in the SOC or board .defconfig file by using:

```
choice RNG_GENERATOR_CHOICE
  default XOSHIRO_RANDOM_GENERATOR
endchoice
```

The random number generators available include:

**CONFIG_TIMER_RANDOM_GENERATOR**
 enables number generator based on system timer clock. This number generator is not random and used for testing only.

**CONFIG_ENTROPY_DEVICE_RANDOM_GENERATOR**
enables a random number generator that uses the enabled hardware entropy gathering driver to generate random numbers.

**CONFIG_XOSHIRO_RANDOM_GENERATOR**
enables the Xoshiro128++ pseudo-random number generator, that uses the entropy driver as a seed source.

The CSPRNG_GENERATOR_CHOICE choice group provides selection of the cryptographically secure random number generator source function. An override of the default value can be specified in the SOC or board .defconfig file by using:

```
choice CSPRNG_GENERATOR_CHOICE
  default CTR_DRBG_CSPRNG_GENERATOR
endchoice
```

The cryptographically secure random number generators available include:

**CONFIG_HARDWAREDEVICE_CS_GENERATOR**
enables a cryptographically secure random number generator using the hardware random generator driver

**CONFIG_CTR_DRBG_CSPRNG_GENERATOR**
enables the CTR-DRBG pseudo-random number generator. The CTR-DRBG is a FIPS140-2 recommended cryptographically secure random number generator.

Personalization data can be provided in addition to the entropy source to make the initialization of the CTR-DRBG as unique as possible.

**CONFIG_CS_CTR_DRBG_PERSONALIZATION**
CTR-DRBG Initialization Personalization string

---

**API Reference**

**Related code samples**

**AWS IoT Core MQTT**
Connect to AWS IoT Core and publish messages using MQTT.

**Microsoft Azure IoT Hub MQTT**
Connect to Azure IoT Hub and publish messages using MQTT.

---

4.3. Cryptography  653
**Random Function APIs.**

**Functions**

```c
uint32_t sys_rand32_get(void)
```

Return a 32-bit random value that should pass general randomness tests.

**Note:** The random value returned is not a cryptographically secure random number value.

**Returns**

32-bit random value.

```c
void sys_rand_get(void *dst, size_t len)
```

Fill the destination buffer with random data values that should pass general randomness tests.

**Note:** The random values returned are not considered cryptographically secure random number values.

**Parameters**

- `dst` – [out] destination buffer to fill with random data.
- `len` – size of the destination buffer.

```c
int sys_csrand_get(void *dst, size_t len)
```

Fill the destination buffer with cryptographically secure random data values.

**Note:** If the random values requested do not need to be cryptographically secure then use `sys_rand_get()` instead.

**Parameters**

- `dst` – [out] destination buffer to fill.
- `len` – size of the destination buffer.

**Returns**

0 if success, -EIO if entropy reseed error

### 4.3.3 Crypto APIs

**Overview**

**API Reference**

**Generic API for crypto drivers**

**Related code samples**
Crypto
Use the crypto APIs to perform various encryption/decryption operations.

---

group crypto
Crypto APIs.

Defines

- CAP_OPAQUE_KEY_HNDL
- CAP_RAW_KEY
- CAP_KEY_LOADING_API
- CAP_INPLACE_OPS
  Whether the output is placed in separate buffer or not.
- CAP_SEPARATE_IO_BUFS
- CAP_SYNC_OPS
  These denotes if the output (completion of a cipher_xxx_op) is conveyed by the op function returning, or it is conveyed by an async notification.
- CAP_ASYNC_OPS
- CAP_AUTONONCE
  Whether the hardware/driver supports autononce feature.
- CAP_NO_IV_PREFIX
  Don’t prefix IV to cipher blocks.

Functions

static inline int crypto_query_hwcaps(const struct device *dev)
Query the crypto hardware capabilities.

This API is used by the app to query the capabilities supported by the crypto device. Based on this the app can specify a subset of the supported options to be honored for a session during cipher_begin_session().

- Parameters
  - dev – Pointer to the device structure for the driver instance.

- Returns
  bitmask of supported options.

---

4.3. Cryptography
Ciphers API

group crypto_cipher
    Crypto Cipher APIs.

Typedefs

typedef int (*block_op_t)(struct cipher_ctx *ctx, struct cipher_pkt *pkt)
typedef int (*cbc_op_t)(struct cipher_ctx *ctx, struct cipher_pkt *pkt, uint8_t *iv)
typedef int (*ctr_op_t)(struct cipher_ctx *ctx, struct cipher_pkt *pkt, uint8_t *ctr)
typedef int (*ccm_op_t)(struct cipher_ctx *ctx, struct cipher_aead_pkt *pkt, uint8_t *nonce)
typedef int (*gcm_op_t)(struct cipher_ctx *ctx, struct cipher_aead_pkt *pkt, uint8_t *nonce)
typedef void (*cipher_completion_cb)(struct cipher_pkt *completed, int status)

 Enums

enum cipher_algo
    Cipher Algorithm.
    Values:
    enumerator CRYPTO_CIPHER_ALGO_AES = 1

enum cipher_op
    Cipher Operation.
    Values:
    enumerator CRYPTO_CIPHER_OP_DECRYPT = 0
    enumerator CRYPTO_CIPHER_OP_ENCRYPT = 1

enum cipher_mode
    Possible cipher mode options.
    More to be added as required.
    Values:
    enumerator CRYPTO_CIPHER_MODE_ECB = 1
    enumerator CRYPTO_CIPHER_MODE_CBC = 2
    enumerator CRYPTO_CIPHER_MODE_CTR = 3
enumerator CRYPTO_CIPHER_MODE_CCM = 4

enumerator CRYPTO_CIPHER_MODE_GCM = 5

Functions

static inline int cipher_begin_session(const struct device *dev, struct cipher_ctx *ctx, enum cipher_algo algo, enum cipher_mode mode, enum cipher_op optype)

Setup a crypto session.
Initializes one time parameters, like the session key, algorithm and cipher mode which may remain constant for all operations in the session. The state may be cached in hardware and/or driver data state variables.

Parameters

• dev – Pointer to the device structure for the driver instance.
• ctx – Pointer to the context structure. Various one time parameters like key, keylength, etc. are supplied via this structure. The structure documentation specifies which fields are to be populated by the app before making this call.
• algo – The crypto algorithm to be used in this session. e.g AES
• mode – The cipher mode to be used in this session. e.g CBC, CTR
• optype – Whether we should encrypt or decrypt in this session

Returns

0 on success, negative errno code on fail.

static inline int cipher_free_session(const struct device *dev, struct cipher_ctx *ctx)

Cleanup a crypto session.
Clears the hardware and/or driver state of a previous session.

Parameters

• dev – Pointer to the device structure for the driver instance.
• ctx – Pointer to the crypto context structure of the session to be freed.

Returns

0 on success, negative errno code on fail.

static inline int cipher_callback_set(const struct device *dev, cipher_completion_cb cb)

Registers an async crypto op completion callback with the driver.
The application can register an async crypto op completion callback handler to be invoked by the driver, on completion of a prior request submitted via cipher_do_op(). Based on crypto device hardware semantics, this is likely to be invoked from an ISR context.

Parameters

• dev – Pointer to the device structure for the driver instance.
• cb – Pointer to application callback to be called by the driver.

Returns

0 on success, -ENOTSUP if the driver does not support async op, negative errno code on other error.
static inline int cipher_block_op(struct cipher_ctx *ctx, struct cipher_pkt *pkt)
    Perform single-block crypto operation (ECB cipher mode).

    This should not be overloaded to operate on multiple blocks for security reasons.

    **Parameters**
    - *ctx* – Pointer to the crypto context of this op.
    - *pkt* – Structure holding the input/output buffer pointers.

    **Returns**
    0 on success, negative errno code on fail.

static inline int cipher_cbc_op(struct cipher_ctx *ctx, struct cipher_pkt *pkt, uint8_t *iv)
    Perform Cipher Block Chaining (CBC) crypto operation.

    **Parameters**
    - *ctx* – Pointer to the crypto context of this op.
    - *pkt* – Structure holding the input/output buffer pointers.
    - *iv* – Initialization Vector (IV) for the operation. Same IV value should not be reused across multiple operations (within a session context) for security.

    **Returns**
    0 on success, negative errno code on fail.

static inline int cipher_ctr_op(struct cipher_ctx *ctx, struct cipher_pkt *pkt, uint8_t *iv)
    Perform Counter (CTR) mode crypto operation.

    **Parameters**
    - *ctx* – Pointer to the crypto context of this op.
    - *pkt* – Structure holding the input/output buffer pointers.
    - *iv* – Initialization Vector (IV) for the operation. We use a split counter formed by appending IV and ctr. Consequently ivlen = keylen - ctrlen. ‘ctrlen’ is specified during session setup through the ‘ctx.mode_params.ctr_params.ctr_len’ parameter. IV should not be reused across multiple operations (within a session context) for security. The non-IV part of the split counter is transparent to the caller and is fully managed by the crypto provider.

    **Returns**
    0 on success, negative errno code on fail.

static inline int cipher_cmc_op(struct cipher_ctx *ctx, struct cipher_aead_pkt *pkt, uint8_t *nonce)
    Perform Counter with CBC-MAC (CCM) mode crypto operation.

    **Parameters**
    - *ctx* – Pointer to the crypto context of this op.
    - *pkt* – Structure holding the input/output, Associated Data (AD) and auth tag buffer pointers.
    - *nonce* – Nonce for the operation. Same nonce value should not be reused across multiple operations (within a session context) for security.

    **Returns**
    0 on success, negative errno code on fail.
static inline int cipher_gcm_op(struct cipher_ctx *ctx, struct cipher_aead_pkt *pkt, uint8_t *nonce)

Perform Galois/Counter Mode (GCM) crypto operation.

**Parameters**
- *ctx* – Pointer to the crypto context of this op.
- *pkt* – Structure holding the input/output, Associated Data (AD) and auth tag buffer pointers.
- *nonce* – Nonce for the operation. Same nonce value should not be reused across multiple operations (within a session context) for security.

**Returns**
- 0 on success, negative errno code on fail.

```c
struct cipher_ops
  #include <cipher.h>
```

```c
struct ccm_params
  #include <cipher.h>
```

```c
struct ctr_params
  #include <cipher.h>
```

```c
struct gcm_params
  #include <cipher.h>
```

```c
struct cipher_ctx
  #include <cipher.h> Structure encoding session parameters.
```

Refer to comments for individual fields to know the contract in terms of who fills what and when w.r.t begin_session() call.

**Public Members**

```c
struct cipher_ops ops
  Place for driver to return function pointers to be invoked per cipher operation.
  To be populated by crypto driver on return from begin_session() based on the algo/mode chosen by the app.
```

```c
union cipher_ctx key
  To be populated by the app before calling begin_session()
```

```c
const struct device *device
  The device driver instance this crypto context relates to.
  Will be populated by the begin_session() API.
```

```c
void *drv_sessn_state
  If the driver supports multiple simultaneously crypto sessions, this will identify the specific driver state this crypto session relates to.
```
Since dynamic memory allocation is not possible, it is suggested that at build time drivers allocate space for the max simultaneous sessions they intend to support. To be populated by the driver on return from begin_session().

```c
void *app_sessn_state
```
Place for the user app to put info relevant stuff for resuming when completion callback happens for async ops.
Totally managed by the app.

```c
union cipher_ctx mode_params
```
Cypher mode parameters, which remain constant for all ops in a session.
To be populated by the app before calling begin_session().

```c
uint16_t keylen
```
Cryptographic keylength in bytes.
To be populated by the app before calling begin_session().

```c
uint16_t flags
```
How certain fields are to be interpreted for this session.
(A bitmask of CAP_* below.) To be populated by the app before calling begin_session(). An app can obtain the capability flags supported by a hw/driver by calling `crypto_query_hwcaps()`.

```c
struct cipher_pkt
```
#include <cipher.h> Structure encoding IO parameters of one cryptographic operation like encrypt/decrypt.
The fields which has not been explicitly called out has to be filled up by the app before making the cipher_xxx_op() call.

**Public Members**

```c
uint8_t *in_buf
```
Start address of input buffer.

```c
int in_len
```
Bytes to be operated upon.

```c
uint8_t *out_buf
```
Start of the output buffer, to be allocated by the application.
Can be NULL for in-place ops. To be populated with contents by the driver on return from op / async callback.

```c
int out_buf_max
```
Size of the out_buf area allocated by the application.
Drivers should not write past the size of output buffer.
int out_len
To be populated by driver on return from cipher_xxx_op() and holds the size of the actual result.

struct cipher_ctx *ctx
Context this packet relates to.
This can be useful to get the session details, especially for async ops. Will be populated by the cipher_xxx_op() API based on the ctx parameter.

struct cipher_aead_pkt
#include <cipher.h> Structure encoding IO parameters in AEAD (Authenticated Encryption with Associated Data) scenario like in CCM.
App has to furnish valid contents prior to making cipher_ccm_op() call.

Public Members

uint8_t *ad
Start address for Associated Data.
This has to be supplied by app.

uint32_t ad_len
Size of Associated Data.
This has to be supplied by the app.

uint8_t *tag
Start address for the auth hash.
For an encryption op this will be populated by the driver when it returns from cipher_ccm_op call. For a decryption op this has to be supplied by the app.

4.4 Debugging

4.4.1 Thread analyzer
The thread analyzer module enables all the Zephyr options required to track the thread information, e.g. thread stack size usage and other runtime thread runtime statistics.
The analysis is performed on demand when the application calls thread_analyzer_run() or thread_analyzer_print().
For example, to build the synchronization sample with Thread Analyser enabled, do the following:

```
west build -b qemu_x86 samples/synchronization/ -- -DCONFIG_QEMU_ICOUNT=n -
-DCONFIG_THREAD_ANALYZER=y \
-DCONFIG_THREAD_ANALYZER_USE_PRINTK=y -DCONFIG_THREAD_ANALYZER_AUTO=y \
-DCONFIG_THREAD_ANALYZER_AUTO_INTERVAL=5
```
When you run the generated application in Qemu, you will get the additional information from Thread Analyzer:
Configuration

Configure this module using the following options.

- **THREAD_ANALYZER**: enable the module.
- **THREAD_ANALYZER_USE_PRINTK**: use printk for thread statistics.
- **THREAD_ANALYZER_USE_LOG**: use the logger for thread statistics.
- **THREAD_ANALYZER_AUTO**: run the thread analyzer automatically. You do not need to add any code to the application when using this option.
- **THREAD_ANALYZER_AUTO_INTERVAL**: the time for which the module sleeps between consecutive printing of thread analysis in automatic mode.
- **THREAD_ANALYZER_AUTO_STACK_SIZE**: the stack for thread analyzer automatic thread.
- **THREAD_NAME**: enable this option in the kernel to print the name of the thread instead of its ID.
- **THREAD_RUNTIME_STATS**: enable this option to print thread runtime data such as utilization (This options is automatically selected by THREAD_ANALYZER).

API documentation
group thread_analyzer

Module for analyzing threads.
This module implements functions and the configuration that simplifies thread analysis.

Typedefs

typedef void (*thread_analyzer_cb)(struct thread_analyzer_info *info)
Thread analyzer stack size callback function.
Callback function with thread analysis information.

Param info
Thread analysis information.

Functions

void thread_analyzer_run(thread_analyzer_cb cb)
Run the thread analyzer and provide information to the callback.
This function analyzes the current state for all threads and calls a given callback on
every thread found.

Parameters
• cb – The callback function handler

void thread_analyzer_print(void)
Run the thread analyzer and print stack size statistics.
This function runs the thread analyzer and prints the output in standard form.

struct thread_analyzer_info
#include <thread_analyzer.h>

Public Members

const char *name
The name of the thread or stringified address of the thread handle if name is not set.

size_t stack_size
The total size of the stack.

size_t stack_used
Stack size in used.

4.4.2 Core Dump

The core dump module enables dumping the CPU registers and memory content for offline de-
bugging. This module is called when a fatal error is encountered and prints or stores data ac-
ccording to which backends are enabled.
Configuration

Configure this module using the following options.

- **DEBUG_COREDUMP**: enable the module.

Here are the options to enable output backends for core dump:

- **DEBUG_COREDUMP_BACKEND_LOGGING**: use log module for core dump output.
- **DEBUG_COREDUMP_BACKEND_FLASH_PARTITION**: use flash partition for core dump output.
- **DEBUG_COREDUMP_BACKEND_NULL**: fallback core dump backend if other backends cannot be enabled. All output is sent to null.

Here are the choices regarding memory dump:

- **DEBUG_COREDUMP_MEMORY_DUMP_MIN**: only dumps the stack of the exception thread, its thread struct, and some other bare minimal data to support walking the stack in the debugger. Use this only if absolute minimum of data dump is desired.

Additional memory can be included in a dump (even with the “DEBUG_COREDUMP_MEMORY_DUMP_MIN” config selected) through one or more coredump devices

Usage

When the core dump module is enabled, during a fatal error, CPU registers and memory content are printed or stored according to which backends are enabled. This core dump data can fed into a custom-made GDB server as a remote target for GDB (and other GDB compatible debuggers). CPU registers, memory content and stack can be examined in the debugger.

This usually involves the following steps:

1. Get the core dump log from the device depending on enabled backends. For example, if the log module backend is used, get the log output from the log module backend.

2. Convert the core dump log into a binary format that can be parsed by the GDB server. For example, scripts/coredump/coredump_serial_log_parser.py can be used to convert the serial console log into a binary file.

3. Start the custom GDB server using the script scripts/coredump/coredump_gdbserver.py with the core dump binary log file, and the Zephyr ELF file as parameters.

4. Start the debugger corresponding to the target architecture.

Note: Developers for Intel ADSP CAVS 15-25 platforms using ZEPHYR_TOOLCHAIN_VARIANT=zephyr should use the debugger in the xtensa-intel_apl_adsp toolchain of the SDK.

5. When **DEBUG_COREDUMP_BACKEND_FLASH_PARTITION** is enabled the core dump data is stored in the flash partition. The flash partition must be defined in the device tree:

```c
&flash0 {
    partitions {
        coredump_partition: partition@255000 {
            label = "coredump-partition";
            reg = <0x255000 DT_SIZE_K(4)>;
        }
    }
};
```
Example  This example uses the log module backend tied to serial console. This was done on qemu_x86 where a null pointer was dereferenced.
This is the core dump log from the serial console, and is stored in coredump.log:

```
Booting from ROM...*** Booting Zephyr OS build zephyr-v2.3.0-1840-g7bba9144a63 ***
Hello World! qemu_x86
E: Page fault at address 0x0 (error code 0x2)
E: Linear address not present in page tables
E: PDE: 0x0000000000115827 Writable, User, Execute Enabled
E: PTE: Non-present
E: EAX: 0x00000000, EBX: 0x00000000, ECX: 0x00119d74, EDX: 0x000003f8
E: ESI: 0x00000000, EDI: 0x00101aa7, EBP: 0x00119d10, ESP: 0x00119d00
E: EFLAGS: 0x00000206 CS: 0x0008 CR3: 0x00119000
E: call trace:
E: EIP: 0x00100459
```
(continues on next page)
1. Run the core dump serial log converter:

   ```bash
   ./scripts/coredump/coredump_serial_log_parser.py coredump.log coredump.bin
   ```

2. Start the custom GDB server:

   ```bash
   ./scripts/coredump/coredump_gdbserver.py build/zephyr/zephyr.elf coredump.bin
   ```

3. Start GDB:

   ```bash
   <path to SDK>/x86_64-zephyr-elf/bin/x86_64-zephyr-elf-gdb build/zephyr/zephyr.elf
   ```

4. Inside GDB, connect to the GDB server via port 1234:

   ```gdb
   target remote localhost:1234
   ```

5. Examine the CPU registers:

   ```gdb
   info registers
   ```

   Output from GDB:

   ```
   eax   0x0 0
   ecx   0x119d74 1154420
   edx   0x3f8 1016
   ebx   0x0 0
   esp   0x119d00 <z_main_stack+844>
   ebp   0x119d10 <z_main_stack+860>
   esi   0x0 0
   edi   0x101aa7 1055399
   ebp   0x100459 <func_3+16>
   es    <unavailable>
   fs    <unavailable>
   gs    <unavailable>
   ```

6. Examine the backtrace:

   ```gdb
   bt
   ```

   Output from GDB:

   ```
   #0 0x00100459 in func_3 (addr=0x0) at zephyr/rtos/zephyr/samples/hello_world/src/main.c:14
   #1 0x00100477 in func_2 (addr=0x0) at zephyr/rtos/zephyr/samples/hello_world/src/main.c:21
   #2 0x00100492 in func_1 (addr=0x0) at zephyr/rtos/zephyr/samples/hello_world/src/main.c:28
   #3 0x001004c8 in main () at zephyr/rtos/zephyr/samples/hello_world/src/main.c:42
   ```
File Format

The core dump binary file consists of one file header, one architecture-specific block, and multiple memory blocks. All numbers in the headers below are little endian.

**File Header**  The file header consists of the following fields:

<table>
<thead>
<tr>
<th>Field</th>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Header version</td>
<td>uint16_t</td>
<td>Identify the version of the header. This needs to be incremented whenever the header struct is modified. This allows parser to reject older header versions so it will not incorrectly parse the header.</td>
</tr>
<tr>
<td>Target code</td>
<td>uint16_t</td>
<td>Indicate which target (e.g. architecture or SoC) so the parser can instantiate the correct register block parser.</td>
</tr>
<tr>
<td>Pointer size</td>
<td>'uint8_t'</td>
<td>Size of uintptr_t in power of 2. (e.g. 5 for 32-bit, 6 for 64-bit). This is needed to accommodate 32-bit and 64-bit target in parsing the memory block addresses.</td>
</tr>
<tr>
<td>Flags</td>
<td>uint8_t</td>
<td>Reason for the fatal error, as the same in enum k_fatal_error_reason defined in include/zephyr/fatal.h</td>
</tr>
<tr>
<td>Fatal error reason</td>
<td>unsigned int</td>
<td>Reason for the fatal error, as the same in enum k_fatal_error_reason defined in include/zephyr/fatal.h</td>
</tr>
</tbody>
</table>

**Architecture-specific Block**  The architecture-specific block contains the byte stream of data specific to the target architecture (e.g. CPU registers)

<table>
<thead>
<tr>
<th>Field</th>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ID</td>
<td>char</td>
<td>A to indicate this is a architecture-specific block.</td>
</tr>
<tr>
<td>Header version</td>
<td>uint16_t</td>
<td>Identify the version of this block. To be interpreted by the target architecture specific block parser.</td>
</tr>
<tr>
<td>Number of bytes</td>
<td>uint16_t</td>
<td>Number of bytes following the header which contains the byte stream for target data. The format of the byte stream is specific to the target and is only being parsed by the target parser.</td>
</tr>
<tr>
<td>Register stream</td>
<td>byte</td>
<td>Contains target architecture specific data.</td>
</tr>
</tbody>
</table>

**Memory Block**  The memory block contains the start and end addresses and the data within the memory region.
### Table 3: Memory Block

<table>
<thead>
<tr>
<th>Field</th>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ID</td>
<td>char</td>
<td>M to indicate this is a memory block.</td>
</tr>
<tr>
<td>Header version</td>
<td>uint16_t</td>
<td>Identify the version of the header. This needs to be incremented</td>
</tr>
<tr>
<td></td>
<td></td>
<td>whenever the header struct is modified. This allows parser to reject</td>
</tr>
<tr>
<td></td>
<td></td>
<td>older header versions so it will not incorrectly parse the header.</td>
</tr>
<tr>
<td>Start address</td>
<td>uintptr_t</td>
<td>The start address of the memory region.</td>
</tr>
<tr>
<td>End address</td>
<td>uintptr_t</td>
<td>The end address of the memory region.</td>
</tr>
<tr>
<td>Memory byte</td>
<td>uint8_t[]</td>
<td>Contains the memory content between the start and end addresses.</td>
</tr>
</tbody>
</table>

### Adding New Target

The architecture-specific block is target specific and requires new dumping routine and parser for new targets. To add a new target, the following needs to be done:

1. Add a new target code to the enum coredump_tgt_code in `include/zephyr/debug/coredump.h`.
2. Implement `arch_coredump_tgt_code_get()` simply to return the newly introduced target code.
3. Implement `arch_coredump_info_dump()` to construct a target architecture block and call `coredump_buffer_output()` to output the block to core dump backend.
4. Add a parser to the core dump GDB stub scripts under `scripts/coredump/gdbstubs/`
   1. Extends the gdbstubs.gdbstub.GdbStub class.
   2. During `__init__`, store the GDB signal corresponding to the exception reason in `self.gdb_signal`.
   3. Parse the architecture-specific block from `self.logfile.get_arch_data()`. This needs to match the format as implemented in step 3 (inside `arch_coredump_info_dump()`).
   4. Implement the abstract method `handle_register_group_read_packet` where it returns the register group as GDB expected. Refer to GDB's code and documentation on what it is expecting for the new target.
   5. Optionally implement `handle_register_single_read_packet` for registers not covered in the g packet.
5. Extend `get_gdbstub()` in `scripts/coredump/gdbstubs/__init__.py` to return the newly implemented GDB stub.

### API documentation

**group coredump_apis**

Coredump APIs.

**Enums**
enum coredump_query_id
Query ID.

Values:

denumerator COREDUMP_QUERY_GET_ERROR
Returns error code from backend.

denumerator COREDUMP_QUERY_HAS_STORED_DUMP
Check if there is a stored coredump from backend.

Returns:
• 1 if there is a stored coredump, 0 if none.
• -ENOTSUP if this query is not supported.
• Otherwise, error code from backend.

denumerator COREDUMP_QUERY_GET_STORED_DUMP_SIZE
Returns:
• coredump raw size from backend, 0 if none.
• -ENOTSUP if this query is not supported.
• Otherwise, error code from backend.

denumerator COREDUMP_QUERY_MAX
Max value for query ID.

enum coredump_cmd_id
Command ID.

Values:

denumerator COREDUMP_CMD_CLEAR_ERROR
Clear error code from backend.

Returns 0 if successful, failed otherwise.

denumerator COREDUMP_CMD_VERIFY_STORED_DUMP
Verify that the stored coredump is valid.

Returns:
• 1 if valid.
• 0 if not valid or no stored coredump.
• -ENOTSUP if this command is not supported.
• Otherwise, error code from backend.

denumerator COREDUMP_CMD_ERASE_STORED_DUMP
Erase the stored coredump.

Returns:
• 0 if successful.
• -ENOTSUP if this command is not supported.
• Otherwise, error code from backend.
enumerator COREDUMP_CMD_COPY_STORED_DUMP

Copy the raw stored coredump.

Returns:
• copied size if successful
• 0 if stored coredump is not found
• -ENOTSUP if this command is not supported.
• Otherwise, error code from backend.

elements
enumerator COREDUMP_CMD_INvalidate_STORED_DUMP

Invalidates the stored coredump.

This is faster than erasing the whole partition.

Returns:
• 0 if successful.
• -ENOTSUP if this command is not supported.
• Otherwise, error code from backend.

enumerator COREDUMP_CMD_MAX

Max value for command ID.

Functions

void coredump(unsigned int reason, const z_arch_esf_t *esf, struct k_thread *thread)

Perform coredump.

Normally, this is called inside z_fatal_error() to generate coredump when a fatal error is encountered. This can also be called on demand whenever a coredump is desired.

Parameters
• reason – Reason for the fatal error
• esf – Exception context
• thread – Thread information to dump

void coredump_memory_dump(uintptr_t start_addr, uintptr_t end_addr)

Dump memory region.

Parameters
• start_addr – Start address of memory region to be dumped
• end_addr – End address of memory region to be dumped

void coredump_buffer_output(uint8_t *buf, size_t buflen)

Output the buffer via coredump.

This outputs the buffer of byte array to the coredump backend. For example, this can be called to output the coredump section containing registers, or a section for memory dump.

Parameters
• buf – Buffer to be send to coredump output
• buflen – Buffer length
int coredump_query(enum coredump_query_id query_id, void *arg)

Perform query on coredump subsystem.

Query the coredump subsystem for information, for example, if there is an error.

Parameters

- query_id – [in] Query ID
- arg – [inout] Pointer to argument for exchanging information

Returns

Depends on the query

int coredump_cmd(enum coredump_cmd_id query_id, void *arg)

Perform command on coredump subsystem.

Perform command on coredump subsystem, for example, output the stored coredump via logging.

Parameters

- cmd_id – [in] Command ID
- arg – [inout] Pointer to argument for exchanging information

Returns

Depends on the command

struct coredump_cmd_copy_arg

#include <coredump.h> Coredump copy command (COREDUMP_CMD_COPY_STORED_DUMP) argument definition.

Public Members

off_t offset

Copy offset.

uint8_t *buffer

Copy destination buffer.

size_t length

Copy length.

group arch-coredump

Functions

void arch_coredump_info_dump(const z_arch_esf_t *esf)

Architecture-specific handling during coredump.

This dumps architecture-specific information during coredump.

Parameters

- esf – Exception Stack Frame (arch-specific)

uint16_t arch_coredump_tgt_code_get(void)

Get the target code specified by the architecture.
4.4.3 GDB stub

Overview

The gdbstub feature provides an implementation of the GDB Remote Serial Protocol (RSP) that allows you to remotely debug Zephyr using GDB.

The protocol supports different connection types: serial, UDP/IP and TCP/IP. Zephyr currently supports only serial device communication.

The GDB program acts as the client while Zephyr acts as the server. When this feature is enabled, Zephyr stops its execution after `gdb_init()` starts gdbstub service and waits for a GDB connection. Once a connection is established it is possible to synchronously interact with Zephyr. Note that currently it is not possible to asynchronously send commands to the target.

Features

The following features are supported:

- Add and remove breakpoints
- Continue and step the target
- Print backtrace
- Read or write general registers
- Read or write the memory

Enabling GDB Stub

GDB stub can be enabled with the `CONFIG_GDBSTUB` option.

Using Serial Backend

The serial backend for GDB stub can be enabled with the `CONFIG_GDBSTUB_SERIAL_BACKEND` option.

Since serial backend utilizes UART devices to send and receive GDB commands,

- If there are spare UART devices on the board, set `zephyr,gdbstub-uart` property of the chosen node to the spare UART device so that `printk()` and log messages are not being printed to the same UART device used for GDB.

- For boards with only one UART device, `printk()` and logging must be disabled if they are also using the same UART device for output. GDB related messages may interleave with log messages which may have unintended consequences. Usually this can be done by disabling `CONFIG_PRINTK` and `CONFIG_LOG`. 
Debugging

Using Serial Backend

1. Build with GDB stub and serial backend enabled.
2. Flash built image onto board and reset the board.
   • Execution should now be paused at `gdb_init()`.
3. Execute GDB on development machine and connect to the GDB stub.

   ```bash
target remote <serial device>
```

   For example,

   ```bash
target remote /dev/ttyUSB1
```

4. GDB commands can be used to start debugging.

Example

This is an example to demonstrate how GDB stub works. You can also refer to `tests/subsys/debug/gdbstub` for its implementation as a Twister test.

1. Open two terminal windows.
2. On the first terminal, build and run the sample:

   ```bash
   # From the root of the zephyr repository
   west build -b qemu_x86 samples/subsys/debug/gdbstub
   west build -t run
   ```

3. On the second terminal, start GDB:

   ```bash
   <SDK install directory>/x86_64-zephyr-elf/bin/x86_64-zephyr-elf-gdb
   ```

   1. Tell GDB where to look for the built ELF file:

      ```bash
      (gdb) file <build directory>/zephyr/zephyr.elf
      Response from GDB:
      Reading symbols from <build directory>/zephyr/zephyr.elf...
      ```

   2. Tell GDB to connect to the server:

      ```bash
      (gdb) target remote localhost:5678
      Note that QEMU is setup to redirect the serial used for GDB stub in the Zephyr image to a networking port. Hence the connection to localhost, port 5678.
      Response from GDB:
      Remote debugging using :5678
      arch_gdb_init () at <ZEPHYR_BASE>/arch/x86/core/ia32/gdbstub.c:232
      232 }
      GDB also shows where the code execution is stopped. In this case, it is at `arch/x86/core/ia32/gdbstub.c: line 232`.

3. Use command `bt` or `backtrace` to show the backtrace of stack frames.
4. Use command `list` to show the source code and surroundings where code execution is stopped.

```c
(gdb) list
227 }
228
229 void arch_gdb_init(void)
230 {
231 __asm__ volatile("int3");
232 }
233
234 /* Hook current IDT. */
235 _EXCEPTION_CONNECT_NOCODE(z_gdb_debug_isr, IV_DEBUG, 3);
236 _EXCEPTION_CONNECT_NOCODE(z_gdb_break_isr, IV_BREAKPOINT, 3);
```

5. Use command `s` or `step` to step through program until it reaches a different source line. Now that it finished executing `arch_gdb_init()` and is continuing in `gdb_init()`.

```c
(gdb) s
```

```c
834 return 0;
```

```c
(gdb) list
829 LOG_ERR("Could not initialize gdbstub backend.");
830 return -1;
831 }
832
833 arch_gdb_init();
834 return 0;
835 }
836
837 #ifdef CONFIG_XTENSA
838 /*
```

6. Use command `br` or `break` to setup a breakpoint. This example sets up a breakpoint at `main()`, and let code execution continue without any intervention using command `c` (or `continue`).

```c
(gdb) break main
Breakpoint 1 at 0x1005a9: file <ZEPHYR_BASE>/samples/subsys/debug/gdbstub/src/
main.c, line 32.
```

```c
(gdb) continue
```

Once code execution reaches `main()`, execution will be stopped and GDB prompt returns.

```c
Breakpoint 1, main () at <ZEPHYR_BASE>/samples/subsys/debug/gdbstub/src/main.c:32
```

```c
32 ret = test();
```

Now GDB is waiting at the beginning of `main()`: 
4.4. Debugging

7. To examine the value of `ret`, the command `p` or `print` can be used.

```
(gdb) p ret
$1 = 0x11318c
```

Since `ret` has not been assigned a value yet, what it contains is simply a random value.

8. If `step` is used here, it will continue execution until `printk()` is reached, thus skipping the interior of `test()`. To examine code execution inside `test()`, a breakpoint can be set for `test()`, or simply using `si` (or `stepi`) to execute one machine instruction, where it has the side effect of going into the function.

```
(gdb) si
```

9. Here, `step` can be used to go through all code inside `test()` until it returns. Or the command `finish` can be used to continue execution without intervention until the function returns.

```
(gdb) finish
```

And now, execution is back to `main()`.

10. Examine `ret` again which should have the return value from `test()`. Sometimes, the assignment is not done until another `step` is issued, as in this case. This is due to the assignment code is done after returning from function. The assignment code is generated by the toolchain as machine instructions which are not visible when viewing the corresponding C source file.

```
(gdb) p ret
$3 = 0x11318c
(gdb) s
33 printk("%d\n", ret);
```

(continues on next page)
If `continue` is issued here, code execution will continue indefinitely as there are no breakpoints to further stop execution. Breaking execution in GDB via Ctrl-C does not currently work as the GDB stub does not support this functionality (yet).

### 4.4.4 Cortex-M Debug Monitor

Monitor mode debugging is a Cortex-M feature, that provides a non-halting approach to debugging. With this it's possible to continue the execution of high-priority interrupts, even when waiting on a breakpoint. This strategy makes it possible to debug time-sensitive software, that would otherwise crash when the core halts (e.g. applications that need to keep communication links alive).

Zephyr provides support for enabling and configuring the Debug Monitor exception. It also contains a ready implementation of the interrupt, which can be used with SEGGER J-Link debuggers.

**Configuration**

Configure this module using the following options.

- `CONFIG_CORTEX_M_DEBUG_MONITOR_HOOK`: enable the module. This option, by itself, requires an implementation of debug monitor interrupt that will be executed every time the program enters a breakpoint.

With a SEGGER debug probe, it's possible to use a ready, SEGGER-provided implementation of the interrupt.

- `CONFIG_SEGGER_DEBUGMON`: enables SEGGER debug monitor interrupt. Can be used with SEGGER JLinkGDBServer and a SEGGER debug probe.

**Usage**

When monitor mode debugging is enabled, entering a breakpoint will not halt the processor, but rather generate an interrupt with ISR implemented under `z_arm_debug_monitor` symbol. `CONFIG_CORTEX_M_DEBUG_MONITOR_HOOK` configures this interrupt to be the lowest available priority, which will allow other interrupts to execute while processor spins on a breakpoint.

**Using SEGGER-provided ISR** The ready implementation provided with `CONFIG_SEGGER_DEBUGMON` provides functionality required to debug in the monitor mode using regular GDB commands. Steps to configure SEGGER debug monitor:

1. Build a sample with `CONFIG_CORTEX_M_DEBUG_MONITOR_HOOK` and `CONFIG_SEGGER_DEBUGMON` configs enabled.
2. Attach JLink GDB server to the target. Example linux command: `JLinkGDBServerCLExe -device <device> -if swd`.
3. Connect to the server with your GDB installation. Example linux command: `arm-none-eabi-gdb --ex="file build/zephyr.elf" --ex="target remote localhost:2331"`.

After these steps use regular gdb commands to debug your program.
Using other custom ISR  In order to provide a custom debug monitor interrupt, override `z_arm_debug_monitor` symbol. Additionally, manual configuration of some registers is required (see debug monitor sample).

4.5 Device Management

4.5.1 MCUmgr

Overview

The management subsystem allows remote management of Zephyr-enabled devices. The following management operations are available:

- Image management
- File System management
- OS management
- Settings (config) management
- Shell management
- Statistic management
- Zephyr management

over the following transports:

- BLE (Bluetooth Low Energy)
- Serial (UART)
- UDP over IP

The management subsystem is based on the Simple Management Protocol (SMP) provided by MCUmgr, an open source project that provides a management subsystem that is portable across multiple real-time operating systems.

The management subsystem is located in `subsys/mgmt/` inside of the Zephyr tree.

Additionally, there is a sample sample that provides management functionality over BLE and serial.

Tools/libraries

There are various tools and libraries available which enable usage of MCUmgr functionality on a device which are listed below. Note that these tools are not part of or related to the Zephyr project.
<table>
<thead>
<tr>
<th>Name</th>
<th>OS support</th>
<th>Transports</th>
<th>Groups</th>
<th>OS</th>
<th>IMG</th>
<th>Stat</th>
<th>Settings</th>
<th>FS</th>
<th>Shell</th>
<th>Zephyr</th>
<th>Type</th>
<th>Language</th>
</tr>
</thead>
<tbody>
<tr>
<td>AuTerm</td>
<td>Windows, Linux, macOS</td>
<td>Serial, Bluetooth, UDP</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>App</td>
<td>C++ (Qt)</td>
</tr>
<tr>
<td>mcumgr-client</td>
<td>Windows, Linux, macOS</td>
<td>Serial</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>App</td>
<td>Rust</td>
</tr>
<tr>
<td>mcumgr-web</td>
<td>Windows, Linux, macOS</td>
<td>Bluetooth</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>Web (chrome only)</td>
<td>Javascript</td>
</tr>
<tr>
<td>nRF Connect Device Manager:</td>
<td>iOS, Android</td>
<td>Bluetooth</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>Library, App</td>
<td>Java, Kotlin, Swift</td>
</tr>
<tr>
<td>Zephyr MCUmgr client (in-tree)</td>
<td>Linux, Zephyr</td>
<td>Serial, Bluetooth, UDP</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>✓</td>
<td>Library</td>
<td>C</td>
</tr>
</tbody>
</table>
Note that a tick for a particular group indicates basic support for that group in the code, it is possible that not all commands/features of a group are supported by the implementation.

**Command-line Tool**

MCUmgr provides a command-line tool, `mcumgr`, for managing remote devices. The tool is written in the Go programming language.

**Note:** This tool is provided for evaluation use only and is not recommended for use in a production environment. It has known issues and will not respect the MCUmgr protocol properly e.g. when an error is received, instead of aborting will, in some circumstances, sit in an endless loop of sending the same command over and over again. A universal replacement for this tool is currently in development and once released, support for the go tool will be dropped entirely. It is recommended that usage of tools listed above in the *Tools/libraries* section are used instead of the go client.

To install the tool:

golang version < 1.18
```bash
go get github.com/apache/mynewt-mcumgr-cli/mcumgr
```

golang version >= 1.18
```bash
go install github.com/apache/mynewt-mcumgr-cli/mcumgr@latest
```

**Configuring the transport**

There are two command-line options that are responsible for setting and configuring the transport layer to use when communicating with managed device:

- `--conntype` is used to choose the transport used, and
- `--connstring` is used to pass a comma separated list of options in the `key=value` format, where each valid key depends on the particular `conntype`.

Valid transports for `--conntype` are `serial`, `ble` and `udp`. Each transport expects a different set of `key/value` options:

- **serial**
  - `--connstring` accepts the following `key` values:
    - `dev` the device name for the OS `mcumgr` is running on (e.g. `/dev/ttyUSB0`, `/dev/tty.usbserial.COM1`, etc).
    - `baud` the communication speed; must match the baudrate of the server.
    - `mtu` aka Maximum Transmission Unit, the maximum protocol packet size.

- **ble**
  - `--connstring` accepts the following key values:
ctlr_name

an OS specific string for the controller name.

own_addr_type

can be one of public, random, rpa_pub, rpa_rnd, where random is the default.

peer_name

the name the peer BLE device advertises, this should match the configuration specified with CONFIG_BT_DEVICE_NAME.

peer_id

the peer BLE device address or UUID. Only required when peer_name was not given. The format depends on the OS where mcumgr is run, it is a 6 bytes hexadecimal string separated by colons on Linux, or a 128-bit UUID on macOS.

conn_timeout

a float number representing the connection timeout in seconds.

udp

--connstring takes the form [addr]:port where:

<table>
<thead>
<tr>
<th>addr</th>
<th>can be a DNS name (if it can be resolved to the device IP), IPv4 addr (app must be built with CONFIG_MCUMGR_TRANSPORT_UDP_IPV4), or IPv6 addr (app must be built with CONFIG_MCUMGR_TRANSPORT_UDP_IPV6)</th>
</tr>
</thead>
<tbody>
<tr>
<td>port</td>
<td>any valid UDP port.</td>
</tr>
</tbody>
</table>

Saving the connection config

The transport configuration can be managed with the conn sub-command and later used with --conn (or -c) parameter to skip typing both --conntype and --connstring. For example a new config for a serial device that would require typing mcumgr --conntype serial --connstring dev=/dev/ttyACM0,baud=115200,mtu=512 can be saved with:

```
mcumgr conn add acm0 type="serial" connstring="dev=/dev/ttyACM0,baud=115200,mtu=512"
```

Accessing this port can now be done with:

```
mcumgr -c acm0
```

General options

Some options work for every mcumgr command and might be helpful to debug and fix issues with the communication, among them the following deserve special mention:

- \[l\] <log-level>

Configures the log level, which can be one of critical, error, warn, info or debug, from less to most verbose. When there are communication issues, -lDEBUG might be useful to dump the packets for later inspection.

- \[t\] <timeout>

Changes the timeout waiting for a response from the default of 10s to a given value. Some commands might take a long time of processing, eg, the erase before an image upload, and might need incrementing the timeout to a larger value.

- \[r\] <tries>

Changes the number of retries on timeout from the default of 1 to a given value.

List of Commands

Not all commands defined by mcumgr (and SMP protocol) are currently supported on Zephyr. The ones that are supported are described in the following table:

Tip: Running mcumgr with no parameters, or -h will display the list of commands.
<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>echo</td>
<td>Send data to a device and display the echoed back data. This command is part of the OS group, which must be enabled by setting CONFIG_MCUMGR_GRP_OS. The echo command itself can be enabled by setting CONFIG_MCUMGR_GRP_OS_ECHO.</td>
</tr>
<tr>
<td>fs</td>
<td>Access files on a device. More info in Filesystem Management.</td>
</tr>
<tr>
<td>image</td>
<td>Manage images on a device. More info in Image Management.</td>
</tr>
<tr>
<td>reset</td>
<td>Perform a soft reset of a device. This command is part of the OS group, which must be enabled by setting CONFIG_MCUMGR_GRP_OS. The reset command itself is always enabled and the time taken for a reset to happen can be set with CONFIG_MCUMGR_GRP_OS_RESET_MS (in ms).</td>
</tr>
<tr>
<td>shell</td>
<td>Execute a command in the remote shell. This option is disabled by default and can be enabled with CONFIG_MCUMGR_GRP_SHELL=y. To know more about the shell in Zephyr check Shell.</td>
</tr>
<tr>
<td>taskstat</td>
<td>Read task statistics from a device. This command is part of the OS group, which must be enabled by setting CONFIG_MCUMGR_GRP_OS. The taskstat command itself can be enabled by setting CONFIG_MCUMGR_GRP_OS_TASKSTAT. CONFIG_THREAD_MONITOR also needs to be enabled otherwise a -8 (MGMT_ERR_ENOTSUP) will be returned.</td>
</tr>
</tbody>
</table>

**Tip:** taskstat has a few options that might require tweaking. The CONFIG_THREAD_NAME must be set to display the task names, otherwise the priority is displayed. Since the taskstat packets are large, they might need increasing the CONFIG_MCUMGR_TRANSPORT_NETBUF_SIZE option.

**Warning:** To display the correct stack size in the taskstat command, the CONFIG_THREAD_STACK_INFO option must be set. To display the correct stack usage in the taskstat command, both CONFIG_THREAD_STACK_INFO and CONFIG_INIT_STACKS options must be set.

**J-Link Virtual MSD Interaction Note**

On boards where a J-Link OB is present which has both CDC and MSC (virtual Mass Storage Device, also known as drag-and-drop) support, the MSD functionality can prevent MCUmgr commands over the CDC UART port from working due to how USB endpoints are configured in the J-Link firmware (for example on the Nordic nrf52840dk_nrf52840 board) because of limiting the maximum packet size (most likely to occur when using image management commands for updating firmware). This issue can be resolved by disabling MSD functionality on the J-Link device, follow the instructions on nordic_segger_msd to disable MSD support.

**Image Management**

The image management provided by mcumgr is based on the image format defined by MCUboot. For more details on the internals see MCUboot design and Signing Binaries.

To list available images in a device:

```
mcumgr <connection-options> image list
```

This should result in an output similar to this:
$ mcumgr -c acm0 image list
Images:
  image=0 slot=0
  version: 1.0.0
  bootable: true
  flags: active confirmed
  hash: 86dca73a3439112b310b5e033d811ec2df728d2264265f2046fced5a9ed00cc7
Split status: N/A (0)

Where image is the number of the image pair in a multi-image system, and slot is the number of the slot where the image is stored, 0 for primary and 1 for secondary. This image being active and confirmed means it will run again on next reset. Also relevant is the hash, which is used by other commands to refer to this specific image when performing operations.

An image can be manually erased using:

mcumgr <connection-options> image erase

The behavior of erase is defined by the server (MCUmgr in the device). The current implementation is limited to erasing the image in the secondary partition.

To upload a new image:

mcumgr <connection-options> image upload [-n] [-e] [-u] [-w] <signed-bin>

- **-n**: This option allows uploading a new image to a specific set of images in a multi-image system, and is currently only supported by MCUboot when the CONFIG_MCUBOOT_SERIAL option is enabled.
- **-e**: This option avoids performing a full erase of the partition before starting a new upload.

**Tip**: The -e option should always be passed in because the upload command already checks if an erase is required, respecting the CONFIG_IMG_ERASE_PROGRESSIVELY setting.

**Tip**: If the upload command times out while waiting for a response from the device, -t might be used to increase the wait time to something larger than the default of 10s. See general_options.

**Warning**: mcumgr does not understand .hex files, when uploading a new image always use the .bin file.

- **-u**: This option allows upgrading only to newer image version.
- **-w**: This option allows setting the maximum size for the window of outstanding chunks in transit. It is set to 5 by default.

**Tip**: If the option is set to a value lower than the default one, for example -w 1, less chunks are transmitted on the window, resulting in lower risk of errors. Conversely, setting a value higher than 5 increases risk of errors and may impact performance.

After an image upload is finished, a new image list would now have an output like this:

$ mcumgr -c acm0 image upload -e build/zephyr/zephyr.signed.bin
35.69 KiB / 92.92 KiB [========================] 38.41% 2.97 KiB/s 00m19

Now listing the images again:
$ mcumgr -c acm0 image list
Images:
  image=0 slot=0
  version: 1.0.0
  bootable: true
  flags: active confirmed
  hash: 86dca73a3439112b310b5e033d811ec2df728d2264265f2046fced5a9ed00cc7
  image=0 slot=1
  version: 1.1.0
  bootable: true
  flags: pending
  hash: e8cf0dcef3ec8addee07e8c4d5dc89e64ba3fae46a2c5267fc4efbea4ca0e9f4
  Split status: N/A (0)

To test a new upgrade image the test command is used:

mcumgr <connection-options> image test <hash>

This command should mark a test upgrade, which means that after the next reboot the bootloader will execute the upgrade and jump into the new image. If no other image operations are executed on the newly running image, it will revert back to the image that was previously running on the device on the subsequent reset. When a test is requested, flags will be updated with pending to inform that a new image will be run after a reset:

$ mcumgr -c acm0 image test e8cf0dcef3ec8addee07e8c4d5dc89e64ba3fae46a2c5267fc4efbea4ca0e9f4
Images:
  image=0 slot=0
  version: 1.0.0
  bootable: true
  flags: active confirmed
  hash: 86dca73a3439112b310b5e033d811ec2df728d2264265f2046fced5a9ed00cc7
  image=0 slot=1
  version: 1.1.0
  bootable: true
  flags: pending
  hash: e8cf0dcef3ec8addee07e8c4d5dc89e64ba3fae46a2c5267fc4efbea4ca0e9f4
  Split status: N/A (0)

After a reset the output with change to:

$ mcumgr -c acm0 image list
Images:
  image=0 slot=0
  version: 1.1.0
  bootable: true
  flags: active
  hash: e8cf0dcef3ec8addee07e8c4d5dc89e64ba3fae46a2c5267fc4efbea4ca0e9f4
  image=0 slot=1
  version: 1.0.0
  bootable: true
  flags: confirmed
  hash: 86dca73a3439112b310b5e033d811ec2df728d2264265f2046fced5a9ed00cc7
  Split status: N/A (0)

Tip: It’s important to mention that an upgrade only ever happens if the image is valid. The first thing MCUboot does when an upgrade is requested is to validate the image, using the SHA-256 and/or the signature (depending on the configuration). So before uploading an image, one way to be sure it is valid is to run imgtool verify -k <your-signature-key> <your-image>, where -k <your-signature-key> can be skipped if no signature validation was enabled.
The confirmed flag in the secondary slot tells that after the next reset a revert upgrade will be performed to switch back to the original layout.

The confirm command used to confirm that an image is OK and no revert should happen (empty hash required) is:

```
mcumgr <connection-options> image confirm ""
```

The confirm command can also be run passing in a hash so that instead of doing a test/revert procedure, the image in the secondary partition is directly upgraded to, eg:

```
mcumgr <connection-options> image confirm <hash>
```

**Tip:** The whole test/revert cycle does not need to be done using only the mcumgr command-line tool. A better alternative is to perform a test and allow the new running image to self-confirm after any checks by calling `boot_write_img_confirmed()`.

**Tip:** Building with `CONFIG_MCUMGR_GRP_IMG_VERBOSE_ERR` enables better error messages when failures happen (but increases the application size).

**Statistics Management**

Statistics are used for troubleshooting, maintenance, and usage monitoring; it consists basically of user-defined counters which are tightly connected to mcumgr and can be used to track any information for easy retrieval. The available sub-commands are:

```
mcumgr <connection-options> stat list
mcumgr <connection-options> stat <section-name>
```

Statistics are organized in sections (also called groups), and each section can be individually queried. Defining new statistics sections is done by using macros available under `zephyr/stats/stats.h`. Each section consists of multiple variables (or counters), all with the same size (16, 32 or 64 bits).

To create a new section `my_stats`:

```
STATS_SECT_START(my_stats)
  STATS_SECT_ENTRY(my_stat_counter1)
  STATS_SECT_ENTRY(my_stat_counter2)
  STATS_SECT_ENTRY(my_stat_counter3)
STATS_SECT_END;

STATS_SECT_DECL(my_stats) my_stats;
```

Each entry can be declared with `STATS_SECT_ENTRY` (or the equivalent `STATS_SECT_ENTRY32`, `STATS_SECT_ENTRY16` or `STATS_SECT_ENTRY64`). All statistics in a section must be declared with the same size.

The statistics counters can either have names or not, depending on the setting of the `CONFIG_STATS_NAMES` option. Using names requires an extra declaration step:

```
STATS_NAME_START(my_stats)
  STATS_NAME(my_stats, my_stat_counter1)
  STATS_NAME(my_stats, my_stat_counter2)
  STATS_NAME(my_stats, my_stat_counter3)
STATS_NAME_END(my_stats);
```
Tip: Disabling CONFIG_STATS_NAMES will free resources. When this option is disabled the STATS_NAME macros output nothing, so adding them in the code does not increase the binary size.

Tip: CONFIG_MCUMGR_GRP_STAT_MAX_NAME_LEN sets the maximum length of a section name that can be accepted as parameter for showing the section data, and might require tweaking for long section names.

The final steps to use a statistics section is to initialize and register it:

```
rc = STATS_INIT_AND_REG(my_stats, STATS_SIZE_32, "my_stats");
assert (rc == 0);
```

In the running code a statistics counter can be incremented by 1 using STATS_INC, by N using STATS_INCN or reset with STATS_CLEAR.

Let's suppose we want to increment those counters by 1, 2 and 3 every second. To get a list of stats:

```
$ mcumgr --conn acm0 stat list
stat groups:
  my_stats
```

To get the current value of the counters in my_stats:

```
$ mcumgr --conn acm0 stat my_stats
stat group: my_stats
  13 my_stat_counter1
  26 my_stat_counter2
  39 my_stat_counter3

$ mcumgr --conn acm0 stat my_stats
stat group: my_stats
  16 my_stat_counter1
  32 my_stat_counter2
  48 my_stat_counter3
```

When CONFIG_STATS_NAMES is disabled the output will look like this:

```
$ mcumgr --conn acm0 stat my_stats
stat group: my_stats
  8 s0
  16 s1
  24 s2
```

**Filesystem Management**

The filesystem module is disabled by default due to security concerns: because of a lack of access control by default, every file in the FS will be accessible, including secrets, etc. To enable it CONFIG_MCUMGR_GRP_FS must be set (y). Once enabled the following sub-commands can be used:

```
mcumgr <connection-options> fs download <remote-file> <local-file>
mcumgr <connection-options> fs upload <local-file> <remote-file>
```

Using the fs command, requires CONFIG_FILE_SYSTEM to be enabled, and that some particular filesystem is enabled and properly mounted by the running application, eg for littlefs this
would mean enabling CONFIG_FILE_SYSTEM_LITTLEFS, defining a storage partition Flash map and mounting the filesystem in the startup \( \text{fs\_mount()} \).

Uploading a new file to a littlefs storage, mounted under /lfs, can be done with:

```
$ mcumgr -c acm0 fs upload foo.txt /lfs/foo.txt
25
Done
```

Where 25 is the size of the file.

For downloading a file, let’s first use the fs command (CONFIG_FILE_SYSTEM_SHELL must be enabled) in a remote shell to create a new file:

```
uart:~$ fs write /lfs/bar.txt 41 42 43 44 31 32 33 34 0a
uart:~$ fs read /lfs/bar.txt
File size: 9
00000000 41 42 43 44 31 32 33 34 0A
ABCD1234.
```

Now it can be downloaded using:

```
$ mcumgr -c acm0 fs download /lfs/bar.txt bar.txt
0
9
Done
$ cat bar.txt
ABCD1234
```

Where 0 is the return code, and 9 is the size of the file.

**Warning:** The commands might exhaust the system workqueue, if its size is not large enough, so increasing CONFIG_SYSTEM_WORKQUEUE_STACK_SIZE might be required for correct behavior.

The size of the stack allocated buffer used to store the blocks, while transferring a file can be adjusted with CONFIG_MCUMGR_GRP_FS_DL_CHUNK_SIZE; this allows saving RAM resources.

**Tip:** CONFIG_MCUMGR_GRP_FS_PATH_LEN sets the maximum PATH accepted for a file name. It might require tweaking for longer file names.

**Note:** To add security to the filesystem management group, callbacks for MCUmgr hooks can be registered by a user application when the upload/download functions are ran which allows the application to control if access to a file is allowed or denied. See the MCUmgr Callbacks section for details.

**Bootloader Integration**

The Device Firmware Upgrade subsystem integrates the management subsystem with the bootloader, providing the ability to send and upgrade a Zephyr image to a device.

Currently only the MCUboot bootloader is supported. See MCUboot for more information.

**Discord channel**

Developers welcome!
Discord mcumgr channel: https://discord.com/invite/Ck7jw53nU2

API Reference

group mcumgr_mgmt_api

MCUmgr mgmt API.

Defines

MGMT_CTXTXT_SET_RC_RSN(mc, rsn)
MGMT_CTXTXT_RC_RSN(mc)
MGMT_RETURN_CHECK(ok)

Used at end of MCUmgr handlers to return an error if the message size limit was reached, or OK if it was not.

MGMT_HDR_SIZE

Typedefs

typedef void *(*mgmt_alloc_rsp_fn)(const void *src_buf, void *arg)
Allocates a buffer suitable for holding a response.
If a source buf is provided, its user data is copied into the new buffer.

Param src_buf
An optional source buffer to copy user data from.

Param arg
Optional streamer argument.

Return
Newly-allocated buffer on success NULL on failure.

typedef void (*mgmt_reset_buf_fn)(void *buf, void *arg)
Resets a buffer to a length of 0.
The buffer’s user data remains, but its payload is cleared.

Param buf
The buffer to reset.

Param arg
Optional streamer argument.

typedef int (*mgmt_handler_fn)(struct smp_streamer *ctxt)
Processes a request and writes the corresponding response.
A separate handler is required for each supported op-ID pair.

Param ctxt
The mcumgr context to use.

Return
0 if a response was successfully encoded, mcumgr_err_t code on failure.
Enums

enum mcumgr_op_t
    Opcodes; encoded in first byte of header.
    Values:

    enumerator MGMT_OP_READ = 0
        Read op-code.

    enumerator MGMT_OP_READ_RSP
        Read response op-code.

    enumerator MGMT_OP_WRITE
        Write op-code.

    enumerator MGMT_OP_WRITE_RSP
        Write response op-code.

enum mcumgr_group_t
    MCUmgr groups.
    The first 64 groups are reserved for system level mcumgr commands. Per-user commands are then defined after group 64.
    Values:

    enumerator MGMT_GROUP_ID_OS = 0
        OS (operating system) group.

    enumerator MGMT_GROUP_ID_IMAGE
        Image management group, used for uploading firmware images.

    enumerator MGMT_GROUP_ID_STAT
        Statistic management group, used for retrieving statistics.

    enumerator MGMT_GROUP_ID_SETTINGS
        Settings management (config) group, used for reading/writing settings.

    enumerator MGMT_GROUP_ID_LOG
        Log management group (unused)

    enumerator MGMT_GROUP_ID_CRASH
        Crash group (unused)

    enumerator MGMT_GROUP_ID_SPLIT
        Split image management group (unused)

    enumerator MGMT_GROUP_ID_RUN
        Run group (unused)
enumerator MGMT_GROUP_ID_FS
   FS (file system) group, used for performing file IO operations.

directory MGMT_GROUP_ID_SHELL
   Shell management group, used for executing shell commands.

directory MGMT_GROUP_ID_PERUSER = 64
   User groups defined from 64 onwards.

directory ZEPHYR_MGMT_GRP_BASIC = (MGMT_GROUP_ID_PERUSER - 1)
   Zephyr-specific groups decrease from PERUSER to avoid collision with upstream
   and user-defined groups.
   Zephyr-specific: Basic group

enum mcumgr_err_t
   MCUmgr error codes.
   Values:

   directory MGMT_ERR_EOK = 0
      No error (success).

   directory MGMT_ERR_EUNKNOWN
      Unknown error.

   directory MGMT_ERR_ENOMEM
      Insufficient memory (likely not enough space for CBOR object).

   directory MGMT_ERR_EINVAL
      Error in input value.

   directory MGMT_ERR_ETIMEOUT
      Operation timed out.

   directory MGMT_ERR_ENOENT
      No such file/entry.

   directory MGMT_ERR_EBADSTATE
      Current state disallows command.

   directory MGMT_ERR_EMSGSIZE
      Response too large.

   directory MGMT_ERR_ENOTSUP
      Command not supported.

   directory MGMT_ERR_ECORRUPT
      Corrupt.
enumerator MGMT_ERR_EBUSY
    Command blocked by processing of other command.

eumerator MGMT_ERR_EACCESSDENIED
    Access to specific function, command or resource denied.

enumerator MGMT_ERR_UNSUPPORTED_TOO_OLD
    Requested SMP MCUmgr protocol version is not supported (too old)

enumerator MGMT_ERR_UNSUPPORTED_TOO_NEW
    Requested SMP MCUmgr protocol version is not supported (too new)

enumerator MGMT_ERR_EPERUSER = 256
    User errors defined from 256 onwards.

Functions

void mgmt_register_group(struct mgmt_group *group)
    Registers a full command group.

Parameters
    • group – The group to register.

void mgmt_unregister_group(struct mgmt_group *group)
    Unregisters a full command group.

Parameters
    • group – The group to register.

const struct mgmt_handler *mgmt_find_handler(uint16_t group_id, uint16_t command_id)
    Finds a registered command handler.

Parameters
    • group_id – The group of the command to find.
    • command_id – The ID of the command to find.

Returns
    The requested command handler on success; NULL on failure.

const struct mgmt_group *mgmt_find_group(uint16_t group_id)
    Finds a registered command group.

Parameters
    • group_id – The group id of the command group to find.

Returns
    The requested group on success; NULL on failure.

const struct mgmt_handler *mgmt_get_handler(const struct mgmt_group *group, uint16_t command_id)
    Finds a registered command handler.

Parameters
    • group – The group of the command to find.
- command_id – The ID of the command to find.

**Returns**
The requested command handler on success; NULL on failure.

```c
struct mgmt_handler
#include <mgmt.h> Read handler and write handler for a single command ID.
Set use_custom_payload to true when using a user defined payload type
```

```c
struct mgmt_group
#include <mgmt.h> A collection of handlers for an entire command group.
```

**Public Members**

```c
sys_snodie_t node
Entry list node.
```

```c
const struct mgmt_handler *mg_handlers
Array of handlers; one entry per command ID.
```

```c
uint16_t mg_group_id
The numeric ID of this group.
```

### 4.5.2 MCUmgr handlers

**Overview**

MCUmgr functions by having group handlers which identify a group of functions relating to a specific management area, which is addressed with a 16-bit identification value, `mcumgr_group_t` contains the management groups available in Zephyr with their corresponding group ID values. The group ID is included in SMP headers to identify which group a command belongs to, there is also an 8-bit command ID which identifies the function of that group to execute - see *SMP Protocol Specification* for details on the SMP protocol and header. There can only be one registered group per unique ID.

**Implementation**

MCUmgr handlers can be added externally by application code or by module code, they do not have to reside in the upstream Zephyr tree to be usable. The first step to creating a handler is to create the folder structure for it, the typical Zephyr MCUmgr group layout is as follows:

```
<dir>/grp/<grp_name>_mgmt/
├── CMakeLists.txt
├── Kconfig
├── include
│    └── <grp_name>_mgmt.h
│    └── <grp_name>_mgmt_callbacks.h
└── src
    └── <grp_name>_mgmt.c
```

Note that the header files in upstream Zephyr MCUmgr handlers reside in the `zephyr/include/zephyr/mgmt/mcumgr/ grp/<grp_name>_mgmt` directory to allow the files to be globally included by applications.

**4.5. Device Management**
Initial header `<grp_name>_mgmt.h`  The purpose of the header file is to provide defines which can be used by the MCUmgr handler itself and application code, e.g. to reference the command IDs for executing functions. An example file would look similar to:

```c
/*
 * Copyright (c) 2023 Nordic Semiconductor ASA
 */
#ifndef H_EXAMPLE_MGMT_
#define H_EXAMPLE_MGMT_
#endif

#ifdef __cplusplus
extern "C"
{
#endif

/**
 * Group ID for example management group.
 */
#define MGMT_GROUP_ID_EXAMPLE MGMT_GROUP_ID_PERUSER

/**
 * Command IDs for example management group.
 */
#define EXAMPLE_MGMT_ID_TEST 0
#define EXAMPLE_MGMT_ID_OTHER 1

/**
 * Command result codes for example management group.
 */
enum example_mgmt_err_code_t {
  /** No error, this is implied if there is no ret value in the response */
  EXAMPLE_MGMT_ERR_OK = 0,

  /** Unknown error occurred. */
  EXAMPLE_MGMT_ERR_UNKNOWN,

  /** The provided value is not wanted at this time. */
  EXAMPLE_MGMT_ERR_NOT_WANTED,

  /** The provided value was rejected by a hook. */
  EXAMPLE_MGMT_ERR_REJECTED_BY_HOOK,
};
#endif
```

This provides the defines for 2 command test and other and sets up the SMP version 2 error responses (which have unique error codes per group as opposed to the legacy SMP version 1 error responses that return a `mcumgr_err_t` - there should always be an OK error code with the value 0 and an unknown error code with the value 1. The above example then adds an error code of not wanted with value 2. In addition, the group ID is set to be `MGMT_GROUP_ID_PERUSER`, which is the start group ID for user-defined groups, note that group IDs need to be unique so other custom groups should use different values, a central index header file (as upstream Zephyr has) can be used to distribute group IDs more easily.

Initial header `<grp_name>_mgmt_callbacks.h`  The purpose of the header file is to provide defines which can be used by the MCUmgr handler itself and application code, e.g. to reference
the command IDs for executing functions. An example file would look similar to:

```c
/*
 * Copyright (c) 2023 Nordic Semiconductor ASA
 * SPDX-License-Identifier: Apache-2.0
 */
#ifndef H_MCUMGR_EXAMPLE_MGMT_CALLBACKS_
#define H_MCUMGR_EXAMPLE_MGMT_CALLBACKS_
#include <stdio.h>
#include <zephyr/mgmt/mcumgr/mgmt/callbacks.h>
#ifndef __cplusplus

extern "C"
{
#endif

#define MGMT_EVT_GRP_EXAMPLE MGMT_EVT_GRP_USER_CUSTOM_START
enum example_mgmt_group_events {
    MGMT_EVT_OP_EXAMPLE_OTHER = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_EXAMPLE, 0),
    MGMT_EVT_OP_EXAMPLE_MGMT_ALL = MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_EXAMPLE),
};

/* Structure provided in the #MGMT_EVT_OP_EXAMPLE_OTHER notification callback */
struct example_mgmt_other_data {
    /* Contains the user supplied value */
    uint32_t user_value;
};
#endif __cplusplus
}
#endif
```

This sets up a single event which application (or module) code can register for to receive a callback when the function handler is executed, which allows the flow of the handler to be changed (i.e. to return an error instead of continuing). The event group ID is set to `MGMT_EVT_GRP_USER_CUSTOM_START`, which is the start event ID for user-defined groups, note that event IDs need to be unique so other custom groups should use different values, a central index header file (as upstream Zephyr has) can be used to distribute event IDs more easily.

**Initial source `<grp_name>_mgmt.c** The purpose of this source file is to handle the incoming MCUmgr commands, provide responses, and register the transport with MCUmgr so that commands will be sent to it. An example file would look similar to:

```c
/*
 * Copyright (c) 2023 Nordic Semiconductor ASA
 * SPDX-License-Identifier: Apache-2.0
 */
#include <zephyr/kernel.h>
#include <zephyr/mgmt/mcumgr/mgmt/mgmt.h>
#include <zephyr/mgmt/mcumgr/smp/smp.h>
#include <zephyr/mgmt/mcumgr/mgmt/handlers.h>
/* The below should be updated with the real name of the file */
```

(continues on next page)
include <example_mgmt.h>
#include <zephyr/logging/log.h>
#include <assert.h>
#include <limits.h>
#include <string.h>
#include <stdio.h>
#include <zcbor_common.h>
#include <zcbor_decode.h>
#include <zcbor_encode.h>
#include <mgmt/mcumgr/util/zcbor_bulk.h>

#if defined(CONFIG_MCUMGR_MGMT_NOTIFICATION_HOOKS)
#include <zephyr/mgmt/mcumgr/mgmt/callbacks.h>
#endif

/* The below should be updated with the real name of the file */
#include <example_mgmt_callbacks.h>
#endif

LOG_MODULE_REGISTER(mcumgr_example_grp, CONFIG_MCUMGR_GRP_EXAMPLE_LOG_LEVEL);

/* Example function with "read" command support, requires both parameters are supplied */
static int example_mgmt_test(struct smp_streamer *ctxt)
{
    uint32_t uint_value = 0;
    zcbor_state_t *zse = ctxt->writer->zs;
    zcbor_state_t *zsd = ctxt->reader->zs;
    bool ok;
    struct zcbor_string string_value = { 0 };  
    size_t decoded;
    struct zcbor_map_decode_key_val example_test_decode[] = {
        ZCBOR_MAP_DECODE_KEY_DECODER("uint_key", zcbor_uint32_decode, &uint_value),
        ZCBOR_MAP_DECODE_KEY_DECODER("string_key", zcbor_tstr_decode, &string_value)
    };
    
    LOG_DBG("Example test function called");
    ok = zcbor_map_decode_bulk(zsd, example_test_decode, ARRAY_SIZE(example_test_decode),
                               &decoded) == 0;
    /* Check that both parameters were supplied and that the value of "string_key" is not empty */
    if (!ok || string_value.len == 0 || !zcbor_map_decode_bulk_key_found(
        example_test_decode, ARRAY_SIZE(example_test_decode), "uint_key") ||
        !zcbor_map_decode_bulk_key_found(
        example_test_decode, ARRAY_SIZE(example_test_decode), "string_key") ||
        )
    {
        return MGMT_ERR_EINVAL;
    }
    /* If the value of "uint_key" is over 50, return an error of "not wanted" */
    if (uint_value > 50) {
        ok = smp_add_cmd_err(zse, MGMT_GROUP_ID_EXAMPLE, EXAMPLE_MGMT_ERR_NOT_WANTED);
        goto end;
    }
    /* Otherwise, return an integer value of 4691 */
    ok = zcbor_tstr_put_lit(zse, "return_int") &&
         zcbor_int32_put(zse, 4691);
}

(continues on next page)
end:
   /* If "ok" is false, then there was an error processing the output cbor message,
   * which likely indicates a lack of available memory
   */
   return (ok ? MGMT_ERR_EOK : MGMT_ERR_EMSGSIZE);
}

/* Example function with "write" command support */
static int example_mgmt_other(struct smp_streamer *ctxt)
{
    uint32_t user_value = 0;
    zcbor_state_t *zse = ctxt->writer->zs;
    zcbor_state_t *zsd = ctxt->reader->zs;
    bool ok;
    size_t decoded;
    struct zcbor_map_decode_key_val example_other_decode[] = {
        ZCBOR_MAP_DECODE_KEY_DECODER("user_value", zcbor_uint32_decode, &user_value),
    };

    #if defined(CONFIG_MCUMGR_GRP_EXAMPLE_OTHER_HOOK)
    struct example_mgmt_other_data other_data;
    enum mgmt_cb_return status;
    int32_t err_rc;
    uint16_t err_group;
    #endif

    LOG_DBG("Example other function called");
    ok = zcbor_map_decode_bulk(zsd, example_other_decode, ARRAY_SIZE(example_other_decode),
                                 &decoded) == 0;

    /* The supplied value is optional, therefore do not return an error if it was not
     * provided */
    if (!ok) {
        return MGMT_ERR_EINVAL;
    }

    #if defined(CONFIG_MCUMGR_GRP_EXAMPLE_OTHER_HOOK)
    /* Send request to application to check what to do */
    other_data.user_value = user_value;
    status = mgmt_callback_notify(MGMT_EVT_OP_EXAMPLE_OTHER, &other_data, sizeof(other_data),
                                    &err_rc, &err_group);
    #endif

    if (status != MGMT_CB_OK) {
        /* If a callback returned an RC error, exit out, if it returned a group
         * code, add the error code to the response and return to the calling
         * function to */
        if (status == MGMT_CB_ERROR_RC) {
            return err_rc;
        }
        ok = smp_add_cmd_err(zse, err_group, (uint16_t)err_rc);
    }
    goto end;
}

(continues on next page)
#ifdef CONFIG_MCUMGR_GRP_EXAMPLE_OTHER_HOOK
end:
#endif
/* If "ok" is false, then there was an error processing the output cbor message,...
   which
   * likely indicates a lack of available memory
   */
return (ok ? MGMT_ERR_EOK : MGMT_ERR_EMSGSIZE);
}
#endif

#define CONFIG_MCUMGR_SMP_SUPPORT_ORIGINAL_PROTOCOL
/* This is a lookup function that converts from SMP version 2 group error codes to legacy
 * MCUmgr error codes, it is only included if support for the original protocol is enabled.
 * Note that in SMP version 2, MCUmgr error codes can still be returned, but are to be used
 * only for general SMP/MCUmgr errors. The success/OK error code is not used in translation
 * functions as it is automatically handled by the base SMP code.
 */
static int example_mgmt_translate_error_code(uint16_t err)
{
    int rc = MGMT_ERR_EOK;
    switch (err) {
    case EXAMPLE_MGMT_ERR_NOT_WANTED:
        rc = MGMT_ERR_ENOENT;
        break;
    case EXAMPLE_MGMT_ERR_REJECTED_BY_HOOK:
        rc = MGMT_ERR_EBADSTATE;
        break;
    case EXAMPLE_MGMT_ERR_UNKNOWN:
        default:
            rc = MGMT_ERR_EUNKNOWN;
        break;
    }
    return rc;
}
#endif

static const struct mgmt_handler example_mgmt_handlers[] = {
    [EXAMPLE_MGMT_ID_TEST] = {
        .mh_read = example_mgmt_test,
        .mh_write = NULL,
    },
    [EXAMPLE_MGMT_ID_OTHER] = {
        .mh_read = NULL,
        .mh_write = example_mgmt_other,
    },
};

static struct mgmt_group example_mgmt_group = {
    .mg_handlers = example_mgmt_handlers,
    .mg_handlers_count = ARRAY_SIZE(example_mgmt_handlers),
    .mg_group_id = MGMT_GROUP_ID_EXAMPLE,
    #ifdef CONFIG_MCUMGR_SMP_SUPPORT_ORIGINAL_PROTOCOL
    .mg_translate_error = example_mgmt_translate_error_code,
    #endif
};

(continues on next page)
The above code creates 2 function handlers, test which supports read requests and takes 2 required parameters, and other which supports write requests and takes 1 optional parameter, this function handler has an optional notification callback feature that allows other parts of the code to listen for the event and take any required actions that are necessary or prevent further execution of the function by returning an error; further details on MCUmgr callback functionality can be found on [MCUmgr Callbacks](#).

Note that other code referencing callbacks for custom MCUmgr handlers needs to include both the base Zephyr callback include file and the custom handler callback file, only in-tree Zephyr handler headers are included when including the upstream Zephyr callback header file.

**Initial Kconfig** The purpose of the Kconfig file is to provide options which users can enable or change relating to the functionality of the handler being implemented. An example file would look similar to:

```c
# Copyright Nordic Semiconductor ASA 2023. All rights reserved.
# SPDX-License-Identifier: Apache-2.0
# The Kconfig file is dedicated to example management group of
# of MCUmgr subsystem and provides Kconfig options to configure
# group commands behaviour and other aspects.

# Options defined in this file should be prefixed:
# MCUMGR_GRP_EXAMPLE_ -- general group options;
#
# When adding Kconfig options, that control the same feature,
# try to group them together by the same stem after prefix.
if MCUMGR

menuconfig MCUMGR_GRP_EXAMPLE_APP
  bool "MCUmgr handlers for example management (app)"
  select MCUMGR_SMP_CBOR_MIN_DECODING_LEVEL_2
  default y
  help Enables MCUmgr handlers for example management. This demonstrates the
          file at application-level.

if MCUMGR_GRP_EXAMPLE_APP
config MCUMGR_GRP_EXAMPLE_OTHER_HOOK
  bool "Other hook"
  depends on MCUMGR_MGMT_NOTIFICATION_HOOKS
  help Allows applications to receive callback when the "other" example
          management function is called

module = MCUMGR_GRP_EXAMPLE
```

(continues on next page)
module-str = mcumgr_grp_example
source "subsys/logging/Kconfig.template.log_config"
endif
endif
source "Kconfig.zephyr"

Initial CMakeLists.txt  The CMakeLists.txt file is used by the build system to setup files to compile, include directories to add and specify options that can be changed. A basic file only need to include the source files if the Kconfig options are enabled. An example file would look similar to:

Zephyr module

```cmake
# Copyright (c) 2023 Nordic Semiconductor ASA
# SPDX-License-Identifier: Apache-2.0
if (CONFIG_MCUMGR_GRP_EXAMPLE_MODULE)
  zephyr_library(mgmt_mcumgr_grp_example)
  # The below should be updated with the real name of the file
  zephyr_library_sources(src/example_mgmt.c)
  zephyr_include_directories(include)
endif()
```

Application

```cmake
if (CONFIG_MCUMGR_GRP_EXAMPLE_APP)
  target_sources(app PRIVATE example_as_module/src/example_mgmt.c)
  zephyr_include_directories(example_as_module/include)
endif()
```

Including from application

Application-specific MCUmgr handlers can be added by creating/editing application build files. Example modifications are shown below.

Example CMakeLists.txt  The application CMakeLists.txt file can load the CMake file for the example MCUmgr handler by adding the following:

```cmake
add_subdirectory(mcumgrgrpgrp_name>)
```

Example Kconfig  The application Kconfig file can include the Kconfig file for the example MCUmgr handler by adding the following to the Kconfig file in the application directory (or creating it if it does not exist):

```cmake
rsource "mcumgrgrpgrp_name>/Kconfig"
# Include Zephyr's Kconfig
source "Kconfig.zephyr"
```
Including from Zephyr Module

Zephyr Modules (External projects) can be used to add custom MCUmgr handlers to multiple different applications without needing to duplicate the code in each application's source tree, see Module yaml file description for details on how to set up the module files. Example files are shown below.

Example zephyr/module.yml  This is an example file which can be used to load the Kconfig and CMake files from the root of the module directory, and would be placed at zephyr/module.yml:

```yaml
build:
  kconfig: Kconfig
  cmake: .
```

Example CMakeLists.txt  This is an example CMakeLists.txt file which loads the CMake file for the example MCUmgr handler, and would be placed at CMakeLists.txt:

```cmake
add_subdirectory(mcumgr/grp/<grp_name>)
```

Example Kconfig  This is an example Kconfig file which loads the Kconfig file for the example MCUmgr handler, and would be placed at Kconfig:

```cmake
rsource "mcumgr/grp/<grp_name>/Kconfig"
```

Demonstration handler

There is a demonstration project which includes configuration for both application and zephyr module-MCUmgr handlers which can be used as a basis for created your own in tests/subsys/mgmt/mcumgr/handler_demo/.

4.5.3 MCUmgr Callbacks

Overview

MCUmgr has a customisable callback/notification system that allows application (and module) code to receive callbacks for MCUmgr events that they are interested in and react to them or return a status code to the calling function that provides control over if the action should be allowed or not. An example of this is with the fs_mgmt group, whereby file access can be gated, the callback allows the application to inspect the request path and allow or deny access to said file, or it can rewrite the provided path to a different path for transparent file redirection support.

Implementation

Enabling  The base callback/notification system can be enabled using CONFIG_MCUMGR_MGMT_NOTIFICATION_HOOKS which will compile the registration and notification system into the code. This will not provide any callbacks by default as the callbacks that are supported by a build must also be selected by enabling the Kconfig's for the required callbacks (see Events for further details). A callback function with the mgmt_cb type definition can then be declared and registered by calling mgmt_callback_register() for the desired event inside of a :c:struct'mgmt_callback' structure. Handlers are called in the order that they were registered.

With the system enabled, a basic handler can be set up and defined in application code as per:
#include <zephyr/kernel.h>
#include <zephyr/mgmt/mcumgr/mgmt/mgmt.h>
#include <zephyr/mgmt/mcumgr/mgmt/callbacks.h>

struct mgmt_callback my_callback;

enum mgmt_cb_return my_function(
    uint32_t event, enum mgmt_cb_return prev_status,
    int32_t *rc, uint16_t *group, bool *abort_more,
    void *data, size_t data_size)
{
    if (event == MGMT_EVT_OP_CMD_DONE) {
        /* This is the event we registered for */
    }
    /* Return OK status code to continue with acceptance to underlying handler */
    return MGMT_CB_OK;
}

int main()
{
    my_callback.callback = my_function;
    my_callback.event_id = MGMT_EVT_OP_CMD_DONE;
    mgmt_callback_register(&my_callback);
}

This code registers a handler for the **MGMT_EVT_OP_CMD_DONE** event, which will be called after a MCUmgr command has been processed and output generated, note that this requires that CONFIG_MCUMGR_SMP_COMMAND_STATUS_HOOKS be enabled to receive this callback.

Multiple callbacks can be setup to use a single function as a common callback, and many different functions can be used for each event by registering each group once, or all notifications for a whole group can be enabled by using one of the MGMT_EVT_OP_*_ALL events, alternatively a handler can setup for every notification by using MGMT_EVT_OP_ALL. When setting up handlers, events can be combined that are in the same group only, for example 5 img_mgmt callbacks can be setup with a single registration call, but to also setup a callback for an os_mgmt callback, this must be done as a separate registration. Group IDs are numerical increments, event IDs are bitmask values, hence the restriction.

As an example, the following registration is allowed, which will register for 3 SMP events with a single callback function in a single registration:

```c
my_callback.callback = my_function;
my_callback.event_id = (MGMT_EVT_OP_CMD_RECV | MGMT_EVT_OP_CMD_STATUS | MGMT_EVT_OP_CMD_DONE);
mgmt_callback_register(&my_callback);
```

The following code is not allowed, and will cause undefined operation, because it mixes the IMG management group with the OS management group whereby the group is **not** a bitmask value, only the event is:

```c
my_callback.callback = my_function;
my_callback.event_id = (MGMT_EVT_OP_IMG_MGMT_DFU_STARTED | MGMT_EVT_OP_OS_MGMT_RESET);
mgmt_callback_register(&my_callback);
```

Events  
Events can be selected by enabling their corresponding Kconfig option:

- CONFIG_MCUMGR_SMP_COMMAND_STATUS_HOOKS
  - MCUmgr command status (**MGMT_EVT_OP_CMD_RECV**, **MGMT_EVT_OP_CMD_STATUS**, **MGMT_EVT_OP_CMD_DONE**)
• CONFIG_MCUMGR_GRP_FS_FILE_ACCESS_HOOK
  fs_mgmt file access (MGMT_EVT_OP_FS_MGMT_FILE_ACCESS)

• CONFIG_MCUMGR_GRP_IMG_UPLOAD_CHECK_HOOK
  img_mgmt upload check (MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK)

• CONFIG_MCUMGR_GRP_IMG_STATUS_HOOKS
  img_mgmt upload status
  (MGMT_EVT_OP_IMG_MGMT_DFU_STOPPED,
   MGMT_EVT_OP_IMG_MGMT_DFU_STARTED,
   MGMT_EVT_OP_IMG_MGMT_DFU_PENDING,
   MGMT_EVT_OP_IMG_MGMT_DFU_CONFIRMED)

• CONFIG_MCUMGR_GRP_OS_RESET_HOOK
  os_mgmt reset check (MGMT_EVT_OP_OS_MGMT_RESET)

• CONFIG_MCUMGR_GRP_SETTINGS_ACCESS_HOOK
  settings_mgmt access (MGMT_EVT_OP_SETTINGS_MGMT_ACCESS)

Actions Some callbacks expect a return status to either allow or disallow an operation, an example is the fs_mgmt access hook which allows for access to files to be allowed or denied. With these handlers, the first non-OK error code returned by a handler will be returned to the MCUmgr client.

An example of selectively denying file access:

```c
#include <zephyr/kernel.h>
#include <zephyr/mgmt/mcumgr/mgmt/mgmt.h>
#include <zephyr/mgmt/mcumgr/mgmt/callbacks.h>
#include <string.h>

struct mgmt_callback my_callback;

enum mgmt_cb_return my_function(uint32_t event, enum mgmt_cb_return prev_status, int32_t *rc, uint16_t *group, bool *abort_more, void *data, size_t data_size)
{
    /* Only run this handler if a previous handler has not failed */
    if (event == MGMT_EVT_OP_FS_MGMT_FILE_ACCESS && prev_status == MGMT_CB_OK) {
        struct fs_mgmt_file_access *fs_data = (struct fs_mgmt_file_access *)data;
        /* Check if this is an upload and deny access if it is, otherwise check
         * the path and deny if is matches a name
         */
        if (fs_data->access == FS_MGMT_FILE_ACCESS_WRITE) {
            /* Return an access denied error code to the client and abort calling
             * further handlers
             */
            *abort_more = true;
            *rc = MGMT_ERR_EACCESSDENIED;
            return MGMT_CB_ERROR_RC;
        } else if (strcmp(fs_data->filename, "/lfs1/false_deny.txt") == 0) {
            /* Return a no entry error code to the client, call additional handlers
             * (which will have failed set to true)
             */
            *rc = MGMT_ERR_ENOENT;
            return MGMT_CB_ERROR_RC;
        }
    }
    /* Return OK status code to continue with acceptance to underlying handler */
    return MGMT_CB_OK;
}
```
(continues on next page)
This code registers a handler for the `MGMT_EVT_OP_FS_MGMT_FILE_ACCESS` event, which will be called after a fs_mgmt file read/write command has been received to check if access to the file should be allowed or not, note that this requires that `CONFIG_MCUMGR_GRP_FS_FILE_ACCESS_HOOK` be enabled to receive this callback. Two types of errors can be returned, the `rc` parameter can be set to an `mcumgr_err_t` error code and `MGMT_CB_ERROR_RC` can be returned, or a group error code (introduced with version 2 of the MCUmgr protocol) can be set by setting the group value to the group and `rc` value to the group error code and returning `MGMT_CB_ERROR_ERR`.

**MCUmgr Command Callback Usage/Adding New Event Types**

To add a callback to a MCUmgr command, `mgmt_callback_notify()` can be called with the event ID and, optionally, a data struct to pass to the callback (which can be modified by handlers). If no data needs to be passed back, NULL can be used instead, and size of the data set to 0.

An example MCUmgr command handler:

```c
#include <zephyr/kernel.h>
#include <zcbor_common.h>
#include <zcbor_encode.h>
#include <zephyr/mgmt/mcumgr/smp/smp.h>
#include <zephyr/mgmt/mcumgr/mgmt/mgmt.h>
#include <zephyr/mgmt/mcumgr/mgmt/callbacks.h>

#define MGMT_EVT_GRP_USER_ONE MGMT_EVT_GRP_USER_CUSTOM_START

enum user_one_group_events {
    /** Callback on first post, data is test_struct. */
    MGMT_EVT_OP_USER_ONE_FIRST = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_USER_ONE, 0),

    /** Callback on second post, data is test_struct. */
    MGMT_EVT_OP_USER_ONE_SECOND = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_USER_ONE, 1),

    /** Used to enable all user_one events. */
    MGMT_EVT_OP_USER_ONE_ALL = MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_USER_ONE),
};

struct test_struct {
    uint8_t some_value;
};

static int test_command(struct mgmt_ctxt *ctxt)
{
    int rc;
    int err_rc;
    uint16_t err_group;
    zcbor_state_t *zse = ctxt->cnbe->zs;
    bool ok;
    struct test_struct test_data = {
        .some_value = 8,
    };

    (continues on next page)
If no response is required for the callback, the function call be called and casted to void.

Migration

If there is existing code using the previous callback system(s) in Zephyr 3.2 or earlier, then it will need to be migrated to the new system. To migrate code, the following callback registration functions will need to be migrated to register for callbacks using `mgmt_callback_register()` (note that `CONFIG_MCUMGR_MGMT_NOTIFICATION_HOOKS` will need to be set to enable the new notification system in addition to any migrations):

- **mgmt_evt**
  Using `MGMT_EVT_OP_USER_ONE_FIRST` as drop-in replacements for events of the same name, where the provided data is `mgmt_evt_op_cmd_arg`. `CONFIG_MCUMGR_SMP_COMMAND_STATUS_HOOKS` needs to be set.

- **fs_mgmt_register_evt_cb**
  Using `MGMT_EVT_OP_FS_MGMT_FILE_ACCESS` where the provided data is `fs_mgmt_file_access`. Instead of returning true to allow the action or false to deny, a MCUmgr result code needs to be returned, `MGMT_ERR_EOK` will allow the action, any other return code will disallow it and return that code to the client (`MGMT_ERR_EACCESSDENIED` can be used for an access denied error). `CONFIG_MCUMGR_GRP_IMG_STATUS_HOOKS` needs to be set.

- **img_mgmt_register_callbacks**
  Using `MGMT_EVT_OP_IMG_MGMT_DFU_STARTED` if `dfu_started_cb` was used, `MGMT_EVT_OP_IMG_MGMT_DFU_STOPPED` if `dfu_stopped_cb` was used, `MGMT_EVT_OP_IMG_MGMT_DFU_PENDING` if `dfu_pending_cb` was used or `MGMT_EVT_OP_IMG_MGMT_DFU_CONFIRMED` if `dfu_confirmed_cb` was used. These callbacks do not have any return status. `CONFIG_MCUMGR_GRP_IMG_STATUS_HOOKS` needs to be set.

- **img_mgmt_set_upload_cb**
  Using `MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK` where the provided data is `img_mgmt_upload_check`. Instead of returning true to allow the action or false to deny, a MCUmgr result code needs to be returned, `MGMT_ERR_EOK` will allow
the action, any other return code will disallow it and return that code to the client (`MGMT_ERR_EACCESSDENIED` can be used for an access denied error). `CONFIG_MCUMGR_GRP_IMG_UPLOAD_CHECK_HOOK` needs to be set.

- **os_mgmt_register_reset_evt_cb**
  Using `MGMT_EVT_OP_OS_MGMT_RESET`. Instead of returning true to allow the action or false to deny, a MCUmgr result code needs to be returned, `MGMT_ERR_EOK` will allow the action, any other return code will disallow it and return that code to the client (`MGMT_ERR_EACCESSDENIED` can be used for an access denied error). `CONFIG_MCUMGR_SMP_COMMAND_STATUS_HOOKS` needs to be set.

### API Reference

[group mcumgr_callback_api]

MCUmgr callback API.

#### Defines

- **MGMT_EVT_GET_GROUP** *(event)*  
  Get group from event.

- **MGMT_EVT_GET_ID** *(event)*  
  Get event ID from event.

- **MGMT_CB_ERROR_RET**

#### Typedefs

typedef enum `mgmt_cb_return` {`*mgmt_cb`}(uint32_t *event, enum `mgmt_cb_return` *prev_status, int32_t *rc, uint16_t *group, bool *abort_more, void *data, size_t data_size)

Function to be called on MGMT notification/event.

This callback function is used to notify an application or system about a MCUmgr mgmt event.

- **Param event** `mcumgr_op_t`.

- **Param prev_status** `mgmt_cb_return` of the previous handler calls, if it is an error then it will be the first error that was returned by a handler (i.e. this handler is being called for a notification only, the return code will be ignored).

- **Param rc**

  If `prev_status` is `MGMT_CB_ERROR_RC` then this is the SMP error that was returned by the first handler that failed. If `prev_status` is `MGMT_CB_ERROR_ERR` then this will be the group error `rc` code returned by the first handler that failed. If the handler wishes to raise an SMP error, this must be set to the `mcumgr_err_t` status and `MGMT_CB_ERROR_RC` must be returned by the function, if the handler wishes to raise a ret error, this must be set to the group ret status and `MGMT_CB_ERROR_ERR` must be returned by the function.
**Param group**

If `prev_status` is `MGMT_CB_ERROR_ERR` then this is the group of the ret error that was returned by the first handler that failed. If the handler wishes to raise a ret error, this must be set to the group ret status and `MGMT_CB_ERROR_ERR` must be returned by the function.

**Param abort_more**

Set to true to abort further processing by additional handlers.

**Param data**

Optional event argument.

**Param data_size**

Size of optional event argument (0 if no data is provided).

**Return**

`mgmt_cb_return` indicating the status to return to the calling code (only checked when this is the first failure reported by a handler).

---

** Enums**

```c
enum mgmt_cb_return
{
    MGMT_CB_OK,  // No error.
    MGMT_CB_ERROR_RC,  // SMP protocol error and `err_rc` contains the `mcumgr_err_t` error code.
    MGMT_CB_ERROR_ERR,  // Group (application-level) error and `err_group` contains the group ID that caused the error and `err_rc` contains the error code of that group to return.
}
```

```c
enum mgmt_cb_groups
{
    MGMT_EVT_GRP_ALL,  // 0
    MGMT_EVT_GRP_SMP,
    MGMT_EVT_GRP_OS,
    MGMT_EVT_GRP_IMG,
    MGMT_EVT_GRP_FS,
    MGMT_EVT_GRP_SETTINGS,
}
```
enumerator `MGMT_EVT_GRP_USER_CUSTOM_START` = `MGMT_GROUP_ID_PERUSER`

**enum smp_all_events**

MGMT event opcodes for all command processing.

*Values:*

enumerator `MGMT_EVT_OP_ALL` = `MGMT_DEF_EVT_OP_ALL`(*MGMT_EVT_GRP_ALL*)

Used to enable all events.

**enum smp_group_events**

MGMT event opcodes for base SMP command processing.

*Values:*

enumerator `MGMT_EVT_OP_CMD_RECV` = `MGMT_DEF_EVT_OP_ID`(*MGMT_EVT_GRP_SMP*, 0)

Callback when a command is received, data is `mgmt_evt_op_cmd_arg()`.

enumerator `MGMT_EVT_OP_CMD_STATUS` = `MGMT_DEF_EVT_OP_ID`(*MGMT_EVT_GRP_SMP*, 1)

Callback when a status is updated, data is `mgmt_evt_op_cmd_arg()`.

enumerator `MGMT_EVT_OP_CMD_DONE` = `MGMT_DEF_EVT_OP_ID`(*MGMT_EVT_GRP_SMP*, 2)

Callback when a command has been processed, data is `mgmt_evt_op_cmd_arg()`.

enumerator `MGMT_EVT_OP_CMD_ALL` = `MGMT_DEF_EVT_OP_ALL`(*MGMT_EVT_GRP_SMP*)

Used to enable all smp_group events.

**enum fs_mgmt_group_events**

MGMT event opcodes for filesystem management group.

*Values:*

enumerator `MGMT_EVT_OP_FS_MGMT_FILE_ACCESS` = `MGMT_DEF_EVT_OP_ID`(*MGMT_EVT_GRP_FS*, 0)

Callback when a file has been accessed, data is `fs_mgmt_file_access()`.

enumerator `MGMT_EVT_OP_FS_MGMT_ALL` = `MGMT_DEF_EVT_OP_ALL`(*MGMT_EVT_GRP_FS*)

Used to enable all fs_mgmt_group events.

**enum img_mgmt_group_events**

MGMT event opcodes for image management group.

*Values:*

enumerator `MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK` = `MGMT_DEF_EVT_OP_ID`(*MGMT_EVT_GRP_IMG*, 0)

Callback when a client sends a file upload chunk, data is `img_mgmt_upload_check()`.
enumerator MGMT_EVT_OP_IMG_MGMT_DFU_STOPPED =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 1)
    Callback when a DFU operation is stopped.

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_STARTED =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 2)
    Callback when a DFU operation is started.

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_PENDING =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 3)
    Callback when a DFU operation has finished being transferred.

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_CONFIRMED =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 4)
    Callback when an image has been confirmed.

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK_WRITE_COMPLETE =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 5)
    Callback when an image write command has finished writing to flash.

enumerator MGMT_EVT_OP_IMG_MGMT_ALL =
MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_IMG)
    Used to enable all img_mgmt_group events.

everse os_mgmt_group_events
    MGMT event opcodes for operating system management group.
    Values:

enumerator MGMT_EVT_OP_OS_MGMT_RESET =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_OS, 0)
    Callback when a reset command has been received, data is os_mgmt_reset_data.

enumerator MGMT_EVT_OP_OS_MGMT_INFO_CHECK =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_OS, 1)
    Callback when an info command is processed, data is os_mgmt_info_check.

enumerator MGMT_EVT_OP_OS_MGMT_INFO_APPEND =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_OS, 2)
    Callback when an info command needs to output data, data is os_mgmt_info_append.

enumerator MGMT_EVT_OP_OS_MGMT_DATETIME_GET =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_OS, 3)
    Callback when a datetime get command has been received.

enumerator MGMT_EVT_OP_OS_MGMT_DATETIME_SET =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_OS, 4)
    Callback when a datetime set command has been received, data is struct rtc_time().

enumerator MGMT_EVT_OP_OS_MGMT_ALL =
MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_OS)
    Used to enable all os_mgmt_group events.
enum settings_mgmt_group_events
MGMT event opcodes for settings management group.

Values:

enumerator MGMT_EVT_OP_SETTINGS_MGMT_ACCESS =
MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_SETTINGS, 0)
Callback when a setting is read/written/deleted.

enumerator MGMT_EVT_OP_SETTINGS_MGMT_ALL =
MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_SETTINGS)
Used to enable all settings_mgmt_group events.

Functions

uint8_t mgmt_evt_get_index(uint32_t event)
Get event ID index from event.

Parameters

• event – Event to get ID index from.

Returns

Event index.

enum mgmt_cb_return mgmt_callback_notify(uint32_t event, void *data, size_t data_size, int32_t *err_rc, uint16_t *err_group)
This function is called to notify registered callbacks about mcumgr notifications/events.

Parameters

• event – mcumgr_op_t.
• data – Optional event argument.
• data_size – Size of optional event argument (0 if none).
• err_rc – Pointer to rc value.
• err_group – Pointer to group value.

Returns

mgmt_cb_return either MGMT_CB_OK if all handlers returned it, or MGMT_CB_ERROR_RC if the first failed handler returned an SMP error (in which case err_rc will be updated with the SMP error) or MGMT_CB_ERROR_ERR if the first failed handler returned a ret group and error (in which case err_group will be updated with the failed group ID and err_rc will be updated with the group-specific error code).

void mgmt_callback_register(struct mgmt_callback *callback)
Register event callback function.

Parameters

• callback – Callback struct.

void mgmt_callback_unregister(struct mgmt_callback *callback)
Unregister event callback function.

Parameters

• callback – Callback struct.
struct mgmt_callback
   
#include <callbacks.h> MGMT callback struct.

Public Members

sys_snodet node
   Entry list node.

mgmt_cb callback
   Callback that will be called.

uint32_t event_id
   MGMT_EVT_[...] Event ID for handler to be called on.
   This has special meaning if MGMT_EVT_OP_ALL is used (which will cover all
events for all groups), or MGMT_EVT_OP_*_MGMT_ALL (which will cover all
events for a single group). For events that are part of a single group, they can
be or’d together for this to have one registration trigger on multiple events, please
note that this will only work for a single group, to register for events in different
groups, they must be registered separately.

struct mgmt_evt_op_cmd_arg
   
#include <callbacks.h> Arguments for MGMT_EVT_OP_CMD_RECV,
MGMT_EVT_OP_CMD_STATUS and MGMT_EVT_OP_CMD_DONE.

Public Members

uint16_t group
   mcumgr_group_t

uint8_t id
   Message ID within group.

uint8_t op
   mcumgr_op_t used in MGMT_EVT_OP_CMD_RECV

int err
   mcumgr_err_t, used in MGMT_EVT_OP_CMD_DONE

int status
   img_mgmt_id_upload_t, used in MGMT_EVT_OP_CMD_STATUS
MCUmgr fs_mgmt callback API.

Enums

4.5. Device Management
enum fs_mgmt_file_access_types
    The type of operation that is being requested for a given file access callback.
    Values:

    enumerator FS_MGMT_FILE_ACCESS_READ
        Access to read file (file upload).

    enumerator FS_MGMT_FILE_ACCESS_WRITE
        Access to write file (file download).

    enumerator FS_MGMT_FILE_ACCESS_STATUS
        Access to get status of file.

    enumerator FS_MGMT_FILE_ACCESS_HASH_CHECKSUM
        Access to calculate hash or checksum of file.

struct fs_mgmt_file_access
    #include <fs_mgmt_callbacks.h> Structure provided in the
    MGMT_EVT_OP_FS_MGMT_FILE_ACCESS notification callback: This callback function
    is used to notify the application about a pending file read/write request and to
    authorise or deny it.
    Access will be allowed so long as all notification handlers return MGMT_ERR_EOK, if
    one returns an error then access will be denied.

Public Members

enum fs_mgmt_file_access_types access
    Specifies the type of the operation that is being requested.

char *filename
    Path and filename of file be accesses, note that this can be changed by handlers
    to redirect file access if needed (as long as it does not exceed the maximum path
    string size).

MCUmgr img_mgmt callback API.

struct img_mgmt_upload_check
    #include <img_mgmt_callbacks.h> Structure provided in the
    MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK notification callback: This callback func-
    tion is used to notify the application about a pending firmware upload packet from a
    client and authorise or deny it.
    Upload will be allowed so long as all notification handlers return MGMT_ERR_EOK, if
    one returns an error then the upload will be denied.

Public Members

struct img_mgmt_upload_action *action
    Action to take.
struct img_mgmt_upload_req *req
Upload request information.

MCUmgr os_mgmt callback API.

struct os_mgmt_reset_data
#include <os_mgmt_callbacks.h> Structure provided in the
MGMT_EVT_OP_OS_MGMT_RESET notification callback: This callback function is
used to notify the application about a pending device reboot request and to authorise
or deny it.

Public Members

bool force
Contains the value of the force parameter.

MCUmgr settings_mgmt callback API.

Enums

class settings_mgmt_access_types

enumerator SETTINGS_ACCESS_READ
enumerator SETTINGS_ACCESS_WRITE
enumerator SETTINGS_ACCESS_DELETE
enumerator SETTINGS_ACCESS_COMMIT
enumerator SETTINGS_ACCESS_LOAD
enumerator SETTINGS_ACCESS_SAVE

struct settings_mgmt_access
#include <settings_mgmt_callbacks.h> Structure provided in the
MGMT_EVT_OP_SETTINGS_MGMT_ACCESS notification callback: This call-
back function is used to notify the application about a pending setting
read/write/delete/load/save/commit request and to authorise or deny it.

Access will be allowed so long as no handlers return an error, if one returns an error
then access will be denied.

Public Members

enum settings_mgmt_access_types access
Type of access.
char *name
   Key name for accesses (only set for SETTINGS_ACCESS_READ, SET-
   TINGS_ACCESS_WRITE and SETTINGS_ACCESS_DELETE).

   Note that this can be changed by handlers to redirect settings access if needed
   (as long as it does not exceed the maximum setting string size) if CON-
   FIG_MCUMGR_GRP_SETTINGS_BUFFER_TYPE_STACK is selected, of maximum size
   CONFIG_MCUMGR_GRP_SETTINGS_NAME_LEN.

   Note: This string must be NULL terminated.

const uint8_t *val
   Data provided by the user (only set for SETTINGS_ACCESS_WRITE)

const size_t *val_length
   Length of data provided by the user (only set for SETTINGS_ACCESS_WRITE)

4.5.4 Fixing and backporting fixes to Zephyr v2.7 MCUmgr

The processes described in this document apply to both the zephyr repository itself and the
MCUmgr module defined in west.yml.

**Note:** Currently, the backporting process, described in this document, is required only when
providing changes to Zephyr version 2.7 LTS

There are two different processes: one for issues that have also been fixed in the current version
of Zephyr (backports), and one for issues that are being fixed only in a previous version.

The upstream MCUmgr repository is located in this page. The Zephyr fork used in version 2.7
and earlier is located here. Versions of Zephyr past 2.7 use the MCUmgr library that is part of
the Zephyr code base.

Possible origins of a code change

In Zephyr version 2.7 and earlier, you must first apply the fix to the upstream repository of
MCUmgr and then bring it to Zephyr with snapshot updates.

As such, there are four possible ways to apply a change to the 2.7 branch:

- The fix, done directly to the Zephyr held code of the MCUmgr library, is backported to the
  v2.7-branch.

- The fix, ported to the Zephyr held code from the upstream repository, is backported to the
  v2.7-branch.

- **The fix, done upstream and no longer relevant to the current version, is directly
  backported**
  to the v2.7-branch.

- **The fix, not present upstream and not relevant for the current version of Zephyr, is
directly applied to the v2.7-branch.**

The first three cases are cases of backports, the last one is a case of a new fix and has no corre-
sponding fix in the current version.
Applying fixes to previous versions of MCUmgr

This section indicates how to apply fixes to previous versions of MCUmgr.

Creating a bug report Every proposed fix requires a bug report submitted for the specified version of Zephyr affected by the bug.

In case the reported bug in a previous version has already been fixed in the current version, the description of the bug must be copied with the following:

- Additional references to the bug in the current version
- The PR for the current version
- The SHAs of the commits, if the PR has already been merged

You must also apply the backport v2.7-branch label to the bug report.

Creating the pull request for the fix You can either create a backport pull request or a new-fix pull request.

Creating backport pull requests Backporting a fix means that some or all of the fix commits, as they exist in the current version, are ported to a previous version.

Note: Backporting requires the fix for the current version to be already merged.

To create a backport pull request, do the following:

1. Port the fix commits from the current version to the previous version. Even if some of the commits require changes, keep the commit messages of all the ported commits as close to the ones in the original commits as possible, adding the following line:

```
"Backporting commit <sha>"
```

`<sha>` indicates the SHA of the commit after it has been already merged in the current version.

1. Create the pull request selecting v2.7-branch as the merge target.
2. Update west.yml within Zephyr, creating a pull-request to update the MCUmgr library referenced in Zephyr 2.7.

Creating new-fix pull requests When the fix needed does not have a corresponding fix in the current version, the bug report must follow the ordinary process.

1. Create the pull request selecting v2.7-branch as the merge target.
2. Update west.yml within Zephyr, creating a pull-request to update the MCUmgr library referenced in Zephyr 2.7.

Configuration management

This chapter describes the maintainers’ side of accepting and merging fixes and backports.
Prerequisites  As a maintainer, these are the steps required before proceeding with the merge process:

1. Check if the author has followed the correct steps that are required to apply the fix, as described in *Applying fixes to previous versions of MCUmgr*.

   1. Ensure that the author of the fix has also provided the `west.yml` update for Zephyr 2.7.

The specific merging process depends on where the fix comes from and whether it is a *backport* or a *new fix*.

Merging a backported fix  There are two possible sources of backports:

- The Zephyr code base
- A direct fix from upstream

Both cases are similar and differ only in the branch name.

To merge a backported fix after the pull request for the fix has gone through the review process, as a maintainer, do the following:

1. Create a branch named as follow:

   ```
   backport-<source>-<pr_num>-to_v2.7-branch
   ```

   - `<source>` can be one of the following:
     - `upstream` - if the fix has originally been merged to the upstream repository.
     - `zephyr` - if the fix has been applied to the Zephyr internal MCUmgr library (past 2.7 versions).
   
   - `<pr_num>` is the number of the original pull request that has already been merged.

   For example, a branch named `backport-upstream-137-to-v2.7-branch` indicates a backport of pull request 137, which has already been merged to the upstream repository of MCUmgr.

2. Push the reviewed pull-request branch to the newly created branch and merge the backport branch to `v2.7-branch`.

Merging a new fix  Merging a new fix, that is not a backport of either any upstream or Zephyr fix, does not require any special treatment. Apply the fix directly at the top of `v2.7-branch`.

Merge west.yml  As an MCUmgr maintainer, you may not be able to merge the `west.yml` update, to introduce the fix to Zephyr. However, you are responsible for such a merge to happen as soon as possible after the MCUmgr fixes have been applied to the `v2.7-branch` of the MCUmgr.

4.5.5 SMP Protocol Specification

This is description of Simple Management Protocol, SMP, that is used by MCUmgr to pass requests to devices and receive responses from them.

SMP is an application layer protocol. The underlying transport layer is not in scope of this documentation.

**Note:** SMP in this context refers to SMP for MCUmgr (Simple Management Protocol), it is unrelated to SMP in Bluetooth (Security Manager Protocol), but there is an MCUmgr SMP transport for Bluetooth.
Frame: The envelope

Each frame consists of a header and data. The Data Length field in the header may be used for reassembly purposes if underlying transport layer supports fragmentation. Frames are encoded in “Big Endian” (Network endianness) when fields are more than one byte long, and takes the following form:

<table>
<thead>
<tr>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
<th>7</th>
<th>6</th>
<th>5</th>
<th>4</th>
<th>3</th>
<th>2</th>
<th>1</th>
<th>0</th>
</tr>
</thead>
<tbody>
<tr>
<td>Res</td>
<td>Ver</td>
<td>OP</td>
<td>Flags</td>
<td>Data Length</td>
<td>Group ID</td>
<td>Sequence Num</td>
<td>Command ID</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:** The original specification states that SMP should support receiving both the “Little-endian” and “Big-endian” frames but in reality the MCUmgr library is hardcoded to always treat “Network” side as “Big-endian”.

Data is optional and is not present when Data Length is zero. The encoding of data depends on the target of group/ID.

A description of the various fields and their meaning:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Res</td>
<td>This is reserved, not-used field and must be always set to 0.</td>
</tr>
<tr>
<td>Ver (Version)</td>
<td>This indicates the version of the protocol being used, this should be set to 0b01 to use the newer SMP transport where error codes are more detailed and returned in the map, otherwise left as 0b00 to use the legacy SMP protocol. Versions 0b10 and 0b11 are reserved for future use and should not be used.</td>
</tr>
<tr>
<td>OP</td>
<td><code>mcumgr_op_t</code>, determines whether information is written to a device or requested from it and whether a packet contains request to an SMP server or response from it.</td>
</tr>
<tr>
<td>Flags</td>
<td>Reserved for flags; there are no flags defined yet, the field should be set to 0</td>
</tr>
<tr>
<td>Data Length</td>
<td>Length of the Data field</td>
</tr>
<tr>
<td>Group ID</td>
<td><code>mcumgr_group_t</code>, see Management Group ID's for further details.</td>
</tr>
<tr>
<td>Sequence Num</td>
<td>This is a frame sequence number. The number is increased by one with each request frame. The Sequence Num of a response should match the one in the request.</td>
</tr>
<tr>
<td>Command ID</td>
<td>This is a command, within Group.</td>
</tr>
<tr>
<td>Data</td>
<td>This is data payload of the Data Length size. It is optional as Data Length may be set to zero, which means that no data follows the header.</td>
</tr>
</tbody>
</table>

**Note:** Contents of Data depends on a value of an OP, a Group ID, and a Command ID.

**Management Group ID's** The SMP protocol supports predefined common groups and allows user defined groups. The following table presents a list of common groups:
The payload for above groups, except for user groups (64 and above) is always CBOR encoded. The group 64, and above can define their own scheme for data communication.

**Minimal response**

Regardless of a command issued, as long as there is SMP client on the other side of a request, a response should be issued containing the header followed by CBOR map container. Lack of response is only allowed when there is no SMP service or device is non-responsive.

**Minimal response SMP data**  Minimal response is:

**SMP version 2**

```json
{
  (str)"err" : {
    (str)"group" : (uint)
    (str)"rc" : (uint)
  }
}
```

**SMP version 1 (and non-group SMP version 2)**

```json
{
  (str)"rc" : (int)
}
```

where:

- "err" -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- "group" contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- "rc" mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

Note that in the case of a successful command, an empty map will be returned (rc/err is only returned if there is an error condition, therefore if only an empty map is returned or a response lacks these, the request can be considered as being successful. For SMP version 2, errors relating to SMP itself that are not group specific will still be returned as rc errors, SMP version 2 clients must therefore be able to handle both types of errors.
Specifications of management groups supported by Zephyr

**Default/OS Management Group**  OS management group defines following commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Echo</td>
</tr>
<tr>
<td>1</td>
<td>Console/Terminal echo control; unimplemented by Zephyr</td>
</tr>
<tr>
<td>2</td>
<td>Task Statistics</td>
</tr>
<tr>
<td>3</td>
<td>Memory pool statistics</td>
</tr>
<tr>
<td>4</td>
<td>Date-time string</td>
</tr>
<tr>
<td>5</td>
<td>System reset</td>
</tr>
<tr>
<td>6</td>
<td>MCUMGR parameters</td>
</tr>
<tr>
<td>7</td>
<td>OS/Application info</td>
</tr>
<tr>
<td>8</td>
<td>Bootloader information</td>
</tr>
</tbody>
</table>

**Echo command**  Echo command responses by sending back string that it has received.

**Echo request**  Echo request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0 or 2</td>
<td>0</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```json
{
    (str)"d" : (str)
}
```

where:

“d” string to be replied by echo service.

**Echo response**  Echo response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
<th>Note</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>0</td>
<td>When request OP was 0</td>
</tr>
<tr>
<td>3</td>
<td>0</td>
<td>0</td>
<td>When request OP was 2</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```json
{
    (str)"r" : (str)
}
```

In case of error the CBOR data takes the form:

SMP version 2

```json
{
    (str)"err" : {
        (str)"group" : (uint)
    }
}
```

(continues on next page)
(continued from previous page)

```c
{(str)"rc" : (uint)
}
```

**SMP version 1 (and non-group SMP version 2)**

```c
{(str)"rc" : (int)
}
```

where:

- **"r"** replying echo string.
- **"err"** - `mcumgr_group_t` group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- **"group"** contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- **"rc"** `mcumgr_err_t` only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

---

**Task statistics command**  The command responds with some system statistics.

**Task statistics request**  Task statistics request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data.

**Task statistics response**  Task statistics response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>2</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```c
{
    (str)"tasks" : {
        (str)<task_name> : {
            (str)"prio" : (uint),
            (str)"tid" : (uint),
            (str)"state" : (uint),
            (str)"stkuse" : (uint),
            (str)"stksiz" : (uint),
            (str)"cswcnt" : (uint),
            (str)"runtime" : (uint),
            (str)"last_checkin" : (uint),
            (str)"next_checkin" : (uint)
        }
    ...
}
```
In case of error the CBOR data takes the form:

SMP version 2

```
{  
    (str)"err" : { 
        (str)"group" : (uint) 
        (str)"rc" : (uint) 
    } 
}
```

SMP version 1 (and non-group SMP version 2)

```
{  
    (str)"rc" : (int) 
}
```

where:

- `<task_name>` string identifying task.
- “prio” task priority.
- “tid” numeric task ID.
- “state” numeric task state.
- “stkuse” task’s/thread’s stack usage.
- “stksiz” task’s/thread’s stack size.
- “cswcnt” task’s/thread’s context switches.
- “runtime” task’s/thread’s runtime in “ticks”.
- “last_check” set to 0 by Zephyr.
- “next_check” set to 0 by Zephyr.
- “err” -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- “group” contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- “rc” mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

**Note:** The unit for “stkuse” and “stksiz” is system dependent and in case of Zephyr this is number of 4 byte words.

---

**Memory pool statistics** The command is used to obtain information on memory pools active in running system.

**Memory pool statistic request** Memory pool statistics request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data.

**Memory pool statistics response** Memory pool statistics response header fields:
CBOR data of successful response:

```json
{
    (str)<pool_name> {
        (str)'blksiz' : (int)
        (str)'nblks' : (int)
        (str)'nfree' : (int)
        (str)'min'  : (int)
    }
    ...
}
```

In case of error the CBOR data takes the form:

SMP version 2

```json
{
    (str)'err' : {
        (str)'group' : (uint)
        (str)'rc'   : (uint)
    }
}
```

SMP version 1 (and non-group SMP version 2)

```json
{
    (str)'rc' : (int)
}
```

where:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&lt;pool_name&gt;</td>
<td>string representing the pool name, used as a key for dictionary with pool statistics data.</td>
</tr>
<tr>
<td>“blksiz”</td>
<td>size of the memory block in the pool.</td>
</tr>
<tr>
<td>“nblks”</td>
<td>number of blocks in the pool.</td>
</tr>
<tr>
<td>“nfree”</td>
<td>number of free blocks.</td>
</tr>
<tr>
<td>“min”</td>
<td>lowest number of free blocks the pool reached during run-time.</td>
</tr>
<tr>
<td>“err”</td>
<td>group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
</tr>
<tr>
<td>“group”</td>
<td>contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
<tr>
<td>“rc”</td>
<td>only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
</tbody>
</table>

**Date-time command**  The command allows to obtain string representing current time-date on a device or set a new time to a device. The time format used, by both set and get operations, is:

```
“yyyy-MM-dd'T'HH:mm:ss.SSSSSSZZZZZ”
```

**Date-time get**  The command allows to obtain date-time from a device.
**Date-time get request**  Date-time request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>4</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data.

**Date-time get response**  Date-time get response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>4</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```json
{
  (str)"datetime" : (str)
}
```

In case of error the CBOR data takes the form:

**SMP version 2**

```json
{
  (str)"err" : {
    (str)"group" : (uint)
    (str)"rc" : (uint)
  }
}
```

**SMP version 1 (and non-group SMP version 2)**

```json
{
  (str)"rc" : (int)
}
```

where:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&quot;datetime&quot;</td>
<td>String in format: <code>yyyy-MM-dd'T'HH:mm:ss.SSSSSSZZZZZ</code>.</td>
</tr>
<tr>
<td>&quot;err&quot;</td>
<td><code>mcumgr_group_t</code> group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
</tr>
<tr>
<td>&quot;group&quot;</td>
<td><code>mcumgr_group_t</code> group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
</tr>
<tr>
<td>&quot;err&quot;</td>
<td>Contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
<tr>
<td>&quot;rc&quot;</td>
<td><code>mcumgr_err_t</code> only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.</td>
</tr>
</tbody>
</table>

**Date-time set**  The command allows to set date-time to a device.

**Date-time set request**  Date-time set request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>0</td>
<td>4</td>
</tr>
</tbody>
</table>

4.5. Device Management
CBOR data of response:

```json
{
  "datetime" : (str)
}
```

where:

```text
"datetime" String in format: yyyy-MM-dd'T'HH:mm:ss.SSSSSSZZZZZ.
```

**Date-time set response**  Date-time set response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>0</td>
<td>4</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

**SMP version 2**

```json
{
  "err" : {
    "group" : (uint),
    "rc" : (uint)
  }
}
```

**SMP version 1 (and non-group SMP version 2)**

```json
{
  "rc" : (int)
}
```

where:

```
"err" -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
"group" contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
"rc" mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.
```

**System reset**  Performs reset of system. The device should issue response before resetting so that the SMP client could receive information that the command has been accepted. By default, this command is accepted in all conditions, however if the CONFIG_MCUMGR_GRP_OS_RESET_HOOK is enabled and an application registers a callback, the callback will be called when this command is issued and can be used to perform any necessary tidy operations prior to the module rebooting, or to reject the reset request outright altogether with an error response. For details on this functionality, see ref:'mcumgr_callbacks.

**System reset request**  System reset request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>0</td>
<td>5</td>
</tr>
</tbody>
</table>
Normally the command sends an empty CBOR map as data, but if a previous reset attempt has responded with “rc” equal to `MGMT_ERR_EBUSY` then the following map may be sent to force a reset:

```
{
    (opt)"force" : (int)
}
```

where:

| “force” | Force reset if value > 0, optional if 0. |

**System reset response**  
System reset response header fields

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>0</td>
<td>5</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

**SMP version 2**

```
{
    (str)"err" : {
        (str)"group" : (uint)
        (str)"rc" : (uint)
    }
}
```

**SMP version 1 (and non-group SMP version 2)**

```
{
    (str)"rc" : (int)
}
```

where:

- “err” -> `mcumgr_group_t` group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- “group” contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- “rc”` mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

**MCUmgr Parameters**  
Used to obtain parameters of mcumgr library.

**MCUmgr Parameters Request**  
MCUmgr parameters request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>6</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data.
**MCUmgr Parameters Response**  MCUmgr parameters response header fields

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>6</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```
{
    (str)"buf_size" : (uint)
    (str)"buf_count" : (uint)
}
```

In case of error the CBOR data takes the form:

**SMP version 2**

```
{
    (str)"err" : {
        (str)"group" : (uint)
        (str)"rc"   : (uint)
    }
}
```

**SMP version 1 (and non-group SMP version 2)**

```
{
    (str)"rc"   : (int)
}
```

where:

- **"buf_size"**  Single SMP buffer size, this includes SMP header and CBOR payload.
- **"buf_count"**  Number of SMP buffers supported.
- **"err"**  group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- **"err"**  contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- **"rc"**  `mcumgr_group_t` only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

**OS/Application Info**  Used to obtain information on running image, similar functionality to the `linux uname` command, allowing details such as kernel name, kernel version, build date/time, processor type and application-defined details to be returned. This functionality can be enabled with `CONFIG_MCUMGR_GRP_OS_INFO`.

**OS/Application Info Request**  OS/Application info request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>7</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{
    (str,opt)"format" : (str)
}
```
where:

```
| Format specifier of returned response, fields are appended in their natural ascending index order, not the order of characters that are received by the command. Format specifiers: * s Kernel name * n Node name * r Kernel release * v Kernel version * b Build date and time (requires CONFIG_MCUMGR_GRP_OS_INFO_BUILD_DATE_TIME) * m Machine * p Processor * i Hardware platform * o Operating system * a All fields (shorthand for all above options) If this option is not provided, the s Kernel name option will be used. |
```

### OS/Application Info Response

OS/Application info response header fields

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>7</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```
{
  "output" : (str)
}
```

In case of error the CBOR data takes the form:

**SMP version 2**

```
{
  "err" : {
    "group" : (uint),
    "rc" : (uint)
  }
}
```

**SMP version 1 (and non-group SMP version 2)**

```
{
  "rc" : (int)
}
```

where:

- "output" Text response including requested parameters.
- "err" -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- "group" contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- "rc" mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

### Bootloader Information

Allows retrieving information about the on-board bootloader and its parameters.

### Bootloader Information Request

Bootloader information request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>8</td>
</tr>
</tbody>
</table>

4.5. Device Management
CBOR data of request:

```
{
  (str,opt)"query" : (str)
}
```

where:

- "query" is string representing query for parameters, with no restrictions how the query looks like as processing of query is left for bootloader backend. If there is no query, then response will return string identifying the bootloader.

**Bootloader Information Response**  
Bootloader information response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>8</td>
</tr>
</tbody>
</table>

In case when no “query” has been provided in request, CBOR data of response:

```
{
  (str)"bootloader" : (str)
}
```

where:

- “bootloader” is string representing bootloader name.

In case when “query” is provided:

```
{
  (str,opt)<response> : ()
  ...
}
```

where:

- <response> is response to “query”. This is optional and may be left out in case when query yields no response. SMP version 2 error code of OS_MGMT_ERR_QUERY_YIELDS_NO_ANSWER is expected. Response may have more than one parameter reported back or it may be a map, that is dependent on bootloader backend and query.

  Parameter characteristic information.

Parameter may be accompanied by additional, parameter specific, information keywords with assigned values.

In case of error the CBOR data takes the form:

**SMP version 2**

```
{
  (str)"err" : {
    (str)"group" : (uint)
    (str)"rc" : (uint)
  }
}
```
SMP version 1 (and non-group SMP version 2)

```json
{
    (str)"rc" : (int)
}
```

where:

- “err” -> `mcumgr_group_t` group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- “err” -> contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- “rc” `mcumgr_err_t` only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

**Bootloader Information: MCUboot** In case when MCUboot is application bootloader, empty request will be responded with:

```json
{
    (str)"bootloader" : (str)"MCUboot"
}
```

Currently “MCUboot” supports querying for mode of operation:

```json
{
    (str)"query" : (str)"mode"
}
```

Response to “mode” is:

```json
{
    (str)"mode" : (int)
    (str, opt)"no-downgrade" : (bool)
}
```

where “mode” is one of:

<table>
<thead>
<tr>
<th>Code</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>-1</td>
<td>Unknown mode of MCUboot.</td>
</tr>
<tr>
<td>0</td>
<td>MCUboot is in single application mode.</td>
</tr>
<tr>
<td>1</td>
<td>MCUboot is in swap using scratch partition mode.</td>
</tr>
<tr>
<td>2</td>
<td>MCUboot is in overwrite (upgrade-only) mode.</td>
</tr>
<tr>
<td>3</td>
<td>MCUboot is in swap without scratch mode.</td>
</tr>
<tr>
<td>4</td>
<td>MCUboot is in DirectXIP without revert mode.</td>
</tr>
<tr>
<td>5</td>
<td>MCUboot is in DirectXIP with revert mode.</td>
</tr>
<tr>
<td>6</td>
<td>MCUboot is in RAM loader mode.</td>
</tr>
</tbody>
</table>

The no-downgrade field is a flag, which is always sent when true, indicating that MCUboot has downgrade prevention enabled; downgrade prevention means that if the uploaded image has a lower version than the currently running application, it will not be used for an update by MCUboot.

MCUmgr may reject images with a lower version in this configuration.

**Application/software image management group** Application/software image management group defines following commands:
Notion of “slots” and “images” in Zephyr  
The “slot” and “image” definition comes from mcu-boot where “image” would consist of two “slots”, further named “primary” and “secondary”; the application is supposed to run from the “primary slot” and update is supposed to be uploaded to the “secondary slot”; the mcu-boot is responsible in swapping slots on boot. This means that pair of slots is dedicated to single upgradable application. In case of Zephyr this gets a little bit confusing because DTS will use “slot0_partition” and “slot1_partition”, as label of fixed-partition dedicated to single application, but will name them as “image-0” and “image-1” respectively.

Currently Zephyr supports at most two images, in which case mapping is as follows:

<table>
<thead>
<tr>
<th>Image</th>
<th>Slot labels</th>
<th>Slot Names</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>“slot0_partition” “slot1_partition”</td>
<td>“image-0” “image-1”</td>
</tr>
<tr>
<td>2</td>
<td>“slot2_partition” “slot3_partition”</td>
<td>“image-2” “image-3”</td>
</tr>
</tbody>
</table>

State of images  
The command is used to set state of images and obtain list of images with their current state.

Get state of images request  
Get state of images request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data.

Get state of images response  
Get state of images response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>

Note:  
Below definition of the response contains “image” field that has been marked as optional(opt): the field may not appear in response when target application does not support more than one image. The field is mandatory when application supports more than one application image to allow identifying which image information is listed.

A response will only contain information for valid images, if an image can not be identified as valid it is simply skipped.

CBOR data of successful response:
In case of error the CBOR data takes the form:

SMP version 2

```
{
  (str,"err" : {
    (str,"group" : (uint)
    (str,"rc" : (uint)
  }
}
```

SMP version 1 (and non-group SMP version 2)

```
{
  (str,"rc" : (int)
  (str,opt)"rsn" : (str)
}
```

where:
“image” semi-optional image number; the field is not required when only one image is supported by the running application.

“slot” slot number within “image”; each image has two slots: primary (running one) = 0 and secondary (for DFU dual-bank purposes) = 1.

“version” string representing image version, as set with `imgtool`.

“has” SHA256 hash of the image header and body. Note that this will not be the same as the SHA256 of the whole file, it is the field in the MCUboot TLV section that contains a hash of the data which is used for signature verification purposes. This field is optional but only optional when using MCUboot’s serial recovery feature with one pair of image slots, Kconfig `CONFIG_BOOT_SERIAL_IMG_GRP_HASH` can be disabled to remove support for hashes in this configuration. MCUmgr in applications must support sending hashes.

Note: See `IMAGE_TLV_SHA256` in the MCUboot image format documentation link below.

“bootable” true if image has bootable flag set; this field does not have to be present if false.

“pending” true if image is set for next swap; this field does not have to be present if false.

“confirmed” true if image has been confirmed; this field does not have to be present if false.

“active” true if image is currently active application; this field does not have to be present if false.

“permanent” true if image is to stay in primary slot after the next boot; this does not have to be present if false.

“split Status” states whether loader of split image is compatible with application part; this is unused by Zephyr.

“err” `mcumgr_group_t` group of the group-based error code. Only appears if an error is returned when using SMP version 2.

> “gro” contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.

“rc” `mcumgr_err_t` only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

“rsn” optional string that clarifies reason for an error; specifically useful when `rc` is `MGMT_ERR_EUNKNOWN`.

Note: For more information on how does image/slots function, please refer to the MCUBoot documentation [https://docs.mcuboot.com/design.html#image-slots](https://docs.mcuboot.com/design.html#image-slots) For information on MCUboot image format, please refer to the MCUboot documentation [https://docs.mcuboot.com/design.html#image-format](https://docs.mcuboot.com/design.html#image-format)

**Set state of image request** Set state of image request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:
If “confirm” is false or not provided, an image with the “hash” will be set for test, which means that it will not be marked as permanent and upon hard reset the previous application will be restored to the primary slot. In case when “confirm” is true, the “hash” is optional as the currently running application will be assumed as target for confirmation.

Set state of image response  The response takes the same format as Get state of images response

Image upload  The image upload command allows to update application image.

Image upload request  The image upload request is sent for each chunk of image that is uploaded, until complete image gets uploaded to a device.

Image upload request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of request:

```json
{
  (str,opt)"image" : (uint),
  (str,opt)"len" : (uint),
  (str)"off" : (uint),
  (str,opt)"sha" : (byte str),
  (str)"data" : (byte str),
  (str,opt)"upgrade" : (bool)
}
```

where:

- **“image”** optional image number; it does not have to appear in request at all, in which case it is assumed to be 0. Should only be present when “off” is 0.
- **“len”** optional length of an image. Must appear when “off” is 0.
- **“off”** offset of image chunk the request carries.
- **“sha”** SHA256 hash of an upload; this is used to identify an upload session (e.g. to allow MCUmgr to continue a broken session), and for image verification purposes. This must be a full SHA256 hash of the whole image being uploaded, or not included if the hash is not available (in which case, upload session continuation and image verification functionality will be unavailable). Should only be present when “off” is 0.
- **“data”** image data to write at provided offset.
- **“upgrade”** optional flag that states that only upgrade should be allowed, so if the version of uploaded software is not higher then already on a device, the image upload will be rejected. Zephyr compares major, minor and revision (x.y.z) by default unless CONFIG_MCUMGR_GRP_IMG_VERSION_CMP_USE_BUILD_NUMBER is set, whereby it will compare build numbers too. Should only be present when “off” is 0.

Note: There is no field representing size of chunk that is carried as “data” because that information is embedded within “data” field itself.
Note: It is possible that a server will respond to an upload with “off” of 0, this may happen if an upload on another transport (or outside of MCUmgr entirely) is started, if the device has rebooted or if a packet has been lost. If this happens, a client must re-send all the required and optional fields that it sent in the original first packet so that the upload state can be re-created by the server. If the original fields are not included, the upload will be unable to continue.

The MCUmgr library uses “sha” field to tag ongoing update session, to be able to continue it in case when it gets broken, and for upload verification purposes. If library gets request with “off” equal zero it checks stored “sha” within its state and if it matches it will respond to update client application with offset that it should continue with. If this hash is not available (e.g. because a file is being streamed) then it must not be provided, image verification and upload session continuation features will be unavailable in this case.

Image upload response Image upload response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```json
[
  (str,opt)"off" : (uint),
  (str,opt)"match" : (bool)
]
```

In case of error the CBOR data takes the form:

SMP version 2

```json
{
  (str)"err" : {
    (str)"group" : (uint),
    (str)"rc" : (uint)
  }
}
```

SMP version 1 (and non-group SMP version 2)

```json
{
  (str)"rc" : (int),
  (str,opt)"rsn" : (str)
}
```

where:

- **“off”**: offset of last successfully written byte of update.
- **“match”**: indicates if the uploaded data successfully matches the provided SHA256 hash or not, only sent in the final packet if CONFIG_IMG_ENABLE_IMAGE_CHECK is enabled.
- **“err”** -> **“group”**: mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- **“err”** -> **“rc”**: contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- **“rc”**: mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.
- **“rsn”**: optional string that clarifies reason for an error; specifically useful when rc is MGMT_ERR_EUNKNOWN.
The “off” field is only included in responses to successfully processed requests; if “rc” is negative then “off” may not appear.

**Image erase**  The command is used for erasing image slot on a target device.

**Note:**  This is synchronous command which means that a sender of request will not receive response until the command completes, which can take a long time.

**Image erase request**  Image erase request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>1</td>
<td>5</td>
</tr>
</tbody>
</table>

CBOR data of request:

```json
{
  (str,opt)"slot" : (uint)
}
```

where:

“slot”  optional slot number, it does not have to appear in the request at all, in which case it is assumed to be 1.

**Image erase response**  Image erase response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>1</td>
<td>5</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

**SMP version 2**

```json
{
  (str)"err" : {
    (str)"group" : (uint)
    (str)"rc"  : (uint)
  }
}
```

**SMP version 1 (and non-group SMP version 2)**

```json
{
  (str)"rc"  : (int)
  (str,opt)"rsn" : (str)
}
```

where:
“err” -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
“group”
“err” -> contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
“rc” mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.
“rsn” optional string that clarifies reason for an error; specifically useful when rc is MGMT_ERR_EUNKNOWN.

Note: Response from Zephyr running device may have “rc” value of MGMT_ERR_EBADSTATE, which means that the secondary image has been marked for next boot already and may not be erased.

Statistics management Statistics management allows to obtain data gathered by Statistics sub-system of Zephyr, enabled with CONFIG_STATS.

Statistics management group defines commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Group data</td>
</tr>
<tr>
<td>1</td>
<td>List groups</td>
</tr>
</tbody>
</table>

Statistics: group data The command is used to obtain data for group specified by a name. The name is one of group names as registered, with STATS_INIT_AND_REG macro or stats_init_and_reg() function call, within module that gathers the statistics.

Statistics: group data request Statistics group data request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```json
{
  "name": "(str)
}
```

where:

```
"name": group name.
```

Statistics: group data response Statistics group data response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>2</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of successful response:
In case of error the CBOR data takes the form:

SMP version 2

```
{
    (str)"err" : {
        (str)"group" : (uint)
        (str)"rc" : (uint)
    }
}
```

SMP version 1 (and non-group SMP version 2)

```
{
    (str)"rc" : (int)
}
```

where:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>name</td>
<td>this is name of group the response contains data for.</td>
</tr>
<tr>
<td>fields</td>
<td>this is map of entries within groups that consists of pairs where the entry name is mapped to value it represents in statistics.</td>
</tr>
<tr>
<td>entry_name</td>
<td>single entry to value mapping; value is hardcoded to unsigned integer type, in a CBOR meaning.</td>
</tr>
<tr>
<td>err -&gt; group</td>
<td>mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
</tr>
<tr>
<td>err -&gt; rc</td>
<td>contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
<tr>
<td>rc</td>
<td>mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.</td>
</tr>
</tbody>
</table>

**Statistics: list of groups**  The command is used to obtain list of groups of statistics that are gathered on a device. This is a list of names as given to groups with STATS_INIT_AND_REG macro or stats_init_and_reg() function calls, within module that gathers the statistics; this means that this command may be considered optional as it is known during compilation what groups will be included into build and listing them is not needed prior to issuing a query.

**Statistics: list of groups request**  Statistics group list request header:

```
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2</td>
<td>1</td>
</tr>
</tbody>
</table>
```

The command sends an empty CBOR map as data.

**Statistics: list of groups response**  Statistics group list request header:
CBOR data of successful response:

```json
{
  "stat_list": [
    "<stat_group_name>", ...
  ]
}
```

In case of error the CBOR data takes the form:

**SMP version 2**

```json
{
  "err": {
    "group": (uint),
    "rc": (uint)
  }
}
```

**SMP version 1 (and non-group SMP version 2)**

```json
{
  "rc": (int)
}
```

where:

<table>
<thead>
<tr>
<th>“stat_list”</th>
<th>array of strings representing group names; this array may be empty if there are no groups.</th>
</tr>
</thead>
<tbody>
<tr>
<td>“err” -&gt; “group”</td>
<td><code>mcumgr_group_t</code> group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
</tr>
<tr>
<td>“err” -&gt; “rc”</td>
<td>contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
<tr>
<td>“rc”</td>
<td><code>mcumgr_err_t</code> only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.</td>
</tr>
</tbody>
</table>

### Settings (Config) Management Group

Settings management group (known as Configuration Manager in the original MCUmgr repository) defines the following commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Read/write setting</td>
</tr>
<tr>
<td>1</td>
<td>Delete setting</td>
</tr>
<tr>
<td>2</td>
<td>Commit settings</td>
</tr>
<tr>
<td>3</td>
<td>Load/Save settings</td>
</tr>
</tbody>
</table>

Note that the Zephyr version adds additional commands and features which are not supported by the original upstream version, however, the original client functionality should work for read/write functionality.

**Read/write setting command**  Read/write setting command allows updating a setting entry on a device or getting the current value of a setting from a device.
**Read setting request**  Read setting request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>3</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{
  (str)"name"  : (str),
  (str,opt)"max_size" : (uint)
}
```

where:

- **"name"** — string of the setting to retrieve
- **"max_size"** — optional maximum size of data to return

**Read setting response**  Read setting response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>3</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```
{
  (str)"val"  : (bstr),
  (str,opt)"max_size" : (uint)
}
```

In case of error the CBOR data takes the form:

**SMP version 2**

```
{
  (str)"err" : {
    (str)"group"  : (uint),
    (str)"rc"    : (uint)
  }
}
```

**SMP version 1**

```
{
  (str)"rc"  : (int)
}
```

where:
“val” binary string of the returned data, note that the underlying data type cannot be specified through this and must be known by the client.

“max_size” will be set if the maximum supported data size is smaller than the maximum requested data size, and contains the maximum data size which the device supports, equivalent to kconfig:option:CONFIG_MCUMGR_GRP_SETTINGS_NAME_LEN.

“err” mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.

“err” -> “group” mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.

“err” -> “rc” mcumgr_err_t only appears if non-zero (error condition) when using SMP version 2.

“rc” mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

Write setting request  Write setting request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>3</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{   (str)"name" : (str)   (str)"val" : (bstr)
}
```

where:

<table>
<thead>
<tr>
<th>“name”</th>
<th>string of the setting to update/set</th>
</tr>
</thead>
<tbody>
<tr>
<td>“val”</td>
<td>value to set the setting to</td>
</tr>
</tbody>
</table>

Write setting response  Write setting response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>3</td>
<td>0</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

SMP version 2

```
{   (str)"err" : {       (str)"group" : (uint)       (str)"rc" : (uint)}
}
```

SMP version 1

```
{   (str)"rc" : (int)
}
```
where:

```
"err" -> mcumgr_group_t group of the group-based error code. Only appears if an error is
returned when using SMP version 2.
"err" -> contains the index of the group-based error code. Only appears if non-zero (error
condition) when using SMP version 2.
"rc" mcumgr_err_t only appears if non-zero (error condition) when using SMP version
1 or for SMP errors when using SMP version 2.
```

**Delete setting command**  Delete setting command allows deleting a setting on a device.

**Delete setting request**  Delete setting request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>3</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{
    (str)"name"  : (str)
}
```

where:

```
"name"  string of the setting to delete
```

**Delete setting response**  Delete setting response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>3</td>
<td>1</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data if successful. In case of error the CBOR data
takes the form:

**SMP version 2**

```
{
    (str)"err" : {
        (str)"group"  : (uint)
        (str)"rc"    : (uint)
    }
}
```

**SMP version 1**

```
{
    (str)"rc"    : (int)
}
```

where:
Commit settings command  Commit settings command allows committing all settings that have been set but not yet applied on a device.

Commit settings request  Commit settings request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>3</td>
<td>2</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data.

Commit settings response  Commit settings response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>3</td>
<td>2</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

SMP version 2

```
{
  (str)"err" : {
    (str)"group" : (uint)
    (str)"rc" : (uint)
  }
}
```

SMP version 1

```
[
  (str)"rc" : (int)
]
```

where:

| “err” -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2. |
| “group” |
| “err” -> contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2. |
| “rc” |
| “rc” only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2. |

Load/Save settings command  Load/Save settings command allows loading/saving all serialized items from/to persistent storage on a device.
Load settings request  Load settings request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>3</td>
<td>3</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data.

Load settings response  Load settings response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>3</td>
<td>3</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

**SMP version 2**

```json
{
    (str)"err" : {
        (str)"group" : (uint)
        (str)"rc"  : (uint)
    }
}
```

**SMP version 1**

```json
[
    (str)"rc"  : (int)
]
```

where:

- "err" -> *mcumgr_group_t* group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- "group" -> contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- "rc" -> *mcumgr_err_t* only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

Save settings request  Save settings request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>3</td>
<td>3</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data.

Save settings response  Save settings response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>3</td>
<td>3</td>
</tr>
</tbody>
</table>
The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

SMP version 2

```plaintext
{
    (str)"err" : {
        (str)"group" : (uint)
        (str)"rc" : (uint)
    }
}
```

SMP version 1

```plaintext
{
    (str)"rc" : (int)
}
```

where:

- **“err”** -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- **“group”** contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- **“rc”** mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

**Settings access callback** There is a settings access MCUmgr callback available (see [MCUmgr Callbacks](MCUmgr%20Callbacks) for details on callbacks) which allows for applications/modules to know when settings management commands are used and, optionally, block access (for example through the use of a security mechanism). This callback can be enabled with `CONFIG_MCUMGR_GRP_SETTINGS_ACCESS_HOOK`, registered with the event `MGMT_EVT_OP_SETTINGS_MGMT_ACCESS`, whereby the supplied callback data is `settings_mgmt_access`.

**File management** The file management group provides commands that allow to upload and download files to/from a device.

File management group defines following commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>File download/upload</td>
</tr>
<tr>
<td>1</td>
<td>File status</td>
</tr>
<tr>
<td>2</td>
<td>File hash/checksum</td>
</tr>
<tr>
<td>3</td>
<td>Supported file hash/checksum types</td>
</tr>
<tr>
<td>4</td>
<td>File close</td>
</tr>
</tbody>
</table>

**File download** Command allows to download contents of an existing file from specified path of a target device. Client applications must keep track of data they have already downloaded and where their position in the file is (MCUmgr will cache these also), and issue subsequent requests, with modified offset, to gather the entire file. Request does not carry size of requested chunk, the size is specified by application itself. Note that file handles will remain open for consecutive requests (as long as an idle timeout has not been reached and another transport does not make use of uploading/downloading files using `fs_mgmt`), but files are not exclusively
owned by MCUmgr, for the time of download session, and may change between requests or even be removed.

**Note:** By default, all file upload/download requests are unconditionally allowed. However, if the Kconfig option CONFIG_MCUMGR_GRP_FS_FILE_ACCESS_HOOK is enabled, then an application can register a callback handler for `MGMT_EVT_OP_FS_MGMT_FILE_ACCESS` (see `MCUmgr callbacks`), which allows for allowing or declining access to reading/writing a particular file, or for rewriting the path supplied by the client.

**File download request**  File download request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{
        (str)"off" : (uint)
        (str)"name" : (str)
    }
```

where:

- **"off"** offset to start download at
- **"name"** absolute path to a file

**File download response**  File download response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```
{
        (str)"off" : (uint)
        (str)"data" : (byte str)
        (str,opt)"len" : (uint)
    }
```

In case of error the CBOR data takes the form:

SMP version 2

```
{
        (str)"err" : {
            (str)"group" : (uint)
            (str)"rc" : (uint)
        }
    }
```

SMP version 1 (and non-group SMP version 2)
where:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>“off”</td>
<td>offset the response is for.</td>
</tr>
<tr>
<td>“data”</td>
<td>chunk of data read from file; it is CBOR encoded stream of bytes with embedded size; “data” appears only in responses where “rc” is 0.</td>
</tr>
<tr>
<td>“len”</td>
<td>length of file, this field is only mandatory when “off” is 0.</td>
</tr>
<tr>
<td>“err”</td>
<td>contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
<tr>
<td>“group”</td>
<td><code>mcumgr_group_t</code> group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
</tr>
<tr>
<td>“rc”</td>
<td><code>mcumgr_err_t</code> only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
</tbody>
</table>

**File upload**  Allows to upload a file to a specified location. Command will automatically overwrite existing file or create a new one if it does not exist at specified path. The protocol supports stateless upload where each requests carries different chunk of a file and it is client side responsibility to track progress of upload.

Note that file handles will remain open for consecutive requests (as long as an idle timeout has not been reached, but files are not exclusively owned by MCUmgr, for the time of download session, and may change between requests or even be removed. Note that file handles will remain open for consecutive requests (as long as an idle timeout has not been reached and another transport does not make use of uploading/downloading files using fs_mgmt), but files are not exclusively owned by MCUmgr, for the time of download session, and may change between requests or even be removed.

**Note:** Weedly, the current Zephyr implementation is half-stateless as is able to hold single upload context, holding information on ongoing upload, that consists of bool flag indicating in-progress upload, last successfully uploaded offset and total length only.

**Note:** By default, all file upload/download requests are unconditionally allowed. However, if the Kconfig option `CONFIG_MCUMGR_GRP_FS_FILE_ACCESS_HOOK` is enabled, then an application can register a callback handler for `MGMT_EVT_OP_FS_MGMT_FILE_ACCESS` (see `MCUmgr callbacks`), which allows for allowing or declining access to reading/writing a particular file, or for rewriting the path supplied by the client.

**File upload request**  File upload request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>8</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{
  "off" : (uint),
  "data" : (str),
  "name" : (str)
}
```
File upload response  

File upload response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>8</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```
{
    (str)"off" : (uint)
}
```

In case of error the CBOR data takes the form:

where:

```
"off"   offset of last successfully written data.
"err"   -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
"err"   -> contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
"rc"    mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.
```

File status  

Command allows to retrieve status of an existing file from specified path of a target device.

File status request  

File status request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{
    (str)"name" : (str)
}
```

where:

```
"name" absolute path to a file.
```
File status response  File status response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```json
{
  (str)"len" : (uint)
}
```

In case of error the CBOR data takes form:

SMP version 2

```json
{
  (str)"err" : {
    (str)"group" : (uint),
    (str)"rc" : (uint)
  }
}
```

SMP version 1 (and non-group SMP version 2)

```json
{
  (str)"rc" : (int)
}
```

where:

- "len" length of file (in bytes).
- "err" -> mcumgr_group_t group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- "err" -> contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- "rc" mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

File hash/checksum  Command allows to generate a hash/checksum of an existing file at a specified path on a target device. Note that kernel heap memory is required for buffers to be allocated for this to function, and large stack memory buffers are required for generation of the output hash/checksum. Requires CONFIG_MCUMGR_GRP_FS_CHECKSUM_HASH to be enabled for the base functionality, supported hash/checksum are opt-in with CONFIG_MCUMGR_GRP_FS_CHECKSUM_IEEE_CRC32 or CONFIG_MCUMGR_GRP_FS_CHECKSUM_SHA256.

File hash/checksum request  File hash/checksum request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8</td>
<td>2</td>
</tr>
</tbody>
</table>

CBOR data of request:
where:

| “name”  | absolute path to a file. |
| “type”  | type of hash/checksum to perform Hash/checksum types or omit to use default. |
| “off”   | offset to start hash/checksum calculation at (optional, 0 if not provided). |
| “len”   | maximum length of data to read from file to generate hash/checksum with (optional, full file size if not provided). |

### Hash/checksum types

<table>
<thead>
<tr>
<th>String name</th>
<th>Hash/checksum</th>
<th>Byte string</th>
<th>Size (bytes)</th>
</tr>
</thead>
<tbody>
<tr>
<td>crc32</td>
<td>IEEE CRC32 checksum</td>
<td>No</td>
<td>4</td>
</tr>
<tr>
<td>sha256</td>
<td>SHA256 (Secure Hash Algorithm)</td>
<td>Yes</td>
<td>32</td>
</tr>
</tbody>
</table>

Note that the default type will be crc32 if it is enabled, or sha256 if crc32 is not enabled.

#### File hash/checksum response

File hash/checksum response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8</td>
<td>2</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```json
[
  (str)"type" : (str),
  (str,opt)"off" : (uint),
  (str)"len" : (uint),
  (str)"output" : (uint or bstr)
]
```

In case of error the CBOR data takes the form:

**SMP version 2**

```json
[
  (str)"err" : {
    (str)"group" : (uint),
    (str)"rc" : (uint)
  }
]
```

**SMP version 1 (and non-group SMP version 2)**

```json
[
  (str)"rc" : (int)
]
```
where:

<table>
<thead>
<tr>
<th>“type”</th>
<th>type of hash/checksum that was performed</th>
</tr>
</thead>
<tbody>
<tr>
<td>“off”</td>
<td>offset that hash/checksum calculation started at (only present if not 0).</td>
</tr>
<tr>
<td>“len”</td>
<td>length of input data used for hash/checksum generation (in bytes).</td>
</tr>
<tr>
<td>“output”</td>
<td>output hash/checksum.</td>
</tr>
<tr>
<td>“err” -&gt;</td>
<td><code>mcumgr_group_t</code> group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
</tr>
<tr>
<td>“err” -&gt;</td>
<td>contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
<tr>
<td>“rc”</td>
<td><code>mcumgr_err_t</code> only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.</td>
</tr>
</tbody>
</table>

**Supported file hash/checksum types** Command allows listing which hash and checksum types are available on a device. Requires Kconfig `CONFIG_MCUMGR_GRP_FS_CHECKSUM_HASH_SUPPORTED_CMD` to be enabled.

**Supported file hash/checksum types request** Supported file hash/checksum types request header:

```
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8</td>
<td>3</td>
</tr>
</tbody>
</table>
```

The command sends empty CBOR map as data.

**Supported file hash/checksum types response** Supported file hash/checksum types response header:

```
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8</td>
<td>3</td>
</tr>
</tbody>
</table>
```

CBOR data of successful response:

```
{
  (str)"types" : {
    (str)<hash_checksum_name> : {
      (str)"format" : (uint)
      (str)"size" : (uint)
    }
  ...
}
```

In case of error the CBOR data takes form:

**SMP version 2**

```
{
  (str)"err" : {
    (str)"group" : (uint)
    (str)"rc" : (uint)
  }
}
```
SMP version 1 (and non-group SMP version 2)

```
{
  (str)"rc" : (int)
}
```

where:

<table>
<thead>
<tr>
<th>&lt;hash_checksum&gt;</th>
<th>name of the hash/checksum type</th>
<th>Hash/checksum types</th>
</tr>
</thead>
<tbody>
<tr>
<td>&quot;format&quot;</td>
<td>format that the hash/checksum returns where 0 is for numerical and 1 is for byte array.</td>
<td></td>
</tr>
<tr>
<td>&quot;size&quot;</td>
<td>size (in bytes) of output hash/checksum response.</td>
<td></td>
</tr>
<tr>
<td>&quot;err&quot; -&gt; mcumgr_group_t</td>
<td>group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
<td></td>
</tr>
<tr>
<td>&quot;err&quot; -&gt; &quot;rc&quot;</td>
<td>contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
<td></td>
</tr>
<tr>
<td>&quot;rc&quot;</td>
<td>mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.</td>
<td></td>
</tr>
</tbody>
</table>

**File close** Command allows closing any open file handles held by fs_mgmt upload/download requests that might have stalled or be incomplete.

**File close request** File close request header:

```
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>8</td>
<td>4</td>
</tr>
</tbody>
</table>
```

The command sends empty CBOR map as data.

**File close response** File close response header:

```
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>8</td>
<td>4</td>
</tr>
</tbody>
</table>
```

The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

**SMP version 2**

```
{
  (str)"err" : {
    (str)"group" : (uint)
    (str)"rc" : (uint)
  }
}
```

**SMP version 1 (and non-group SMP version 2)**

```
{
  (str)"rc" : (int)
}
```
where:

<table>
<thead>
<tr>
<th>“err” -&gt;</th>
<th>mcumgr_group_t</th>
<th>group of the group-based error code. Only appears if an error is returned when using SMP version 2.</th>
</tr>
</thead>
<tbody>
<tr>
<td>“err” -&gt;</td>
<td></td>
<td>contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
<tr>
<td>“rc” -&gt;</td>
<td>mcumgr_err_t</td>
<td>only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.</td>
</tr>
</tbody>
</table>

**Shell management** Shell management allows passing commands to the shell subsystem over the SMP protocol.

Shell management group defines following commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Shell command line execute</td>
</tr>
</tbody>
</table>

**Shell command line execute** The command allows to execute command line in a similar way to typing it into a shell, but both a request and a response are transported over SMP.

**Shell command line execute request** Execute command request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>9</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{  
    (str)"argv" : [  
        (str)<cmd>  
        (str,opt)<arg>  
        ...  
    ]  
}
```

where:

<table>
<thead>
<tr>
<th>“argv”</th>
<th>array consisting of strings representing command and its arguments.</th>
</tr>
</thead>
<tbody>
<tr>
<td>&lt;cmd&gt;</td>
<td>command to be executed.</td>
</tr>
<tr>
<td>&lt;arg&gt;</td>
<td>optional arguments to command.</td>
</tr>
</tbody>
</table>

**Shell command line execute response** Command line execute response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>9</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of successful response:
In case of error the CBOR data takes the form:

SMP version 2

```json
{
    "err": {
        "group": (uint),
        "rc": (uint)
    }
}
```

SMP version 1 (and non-group SMP version 2)

```json
{
    "rc": (int)
}
```

where:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&quot;o&quot;</td>
<td>command output.</td>
</tr>
<tr>
<td>&quot;ret&quot;</td>
<td>return code from shell command execution.</td>
</tr>
<tr>
<td>&quot;err&quot;</td>
<td>return code from shell command execution.</td>
</tr>
<tr>
<td>&quot;group&quot;</td>
<td><code>mcumgr_group_t</code> group of the group-based error code. Only appears if an error is returned when using SMP version 2.</td>
</tr>
<tr>
<td>&quot;rc&quot;</td>
<td>contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.</td>
</tr>
</tbody>
</table>

**Note:** In older versions of Zephyr, "rc" was used for both the mcumgr status code and shell command execution return code, this legacy behaviour can be restored by enabling `CONFIG_MCUMGR_GRP_SHELL_LEGACY_RC_RETURN_CODE`

### 4.5.6 SMP Transport Specification

The documents specifies information needed for implementing server and client side SMP transports.

**BLE (Bluetooth Low Energy)**

MCUmgr Clients need to use following BLE Characteristics, when implementing SMP client:

- **Service UUID**: `8D53DC1D-1DB7-4CD3-868B-8A527460AA84`
- **Characteristic UUID**: `DA2E7828-FBCE-4E01-AE9E-261174997C48`

All SMP communication utilizes a single GATT characteristic. An SMP request is sent via a GATT Write Without Response command. An SMP response is sent in the form of a GATT Notification. If an SMP request or response is too large to fit in a single GATT command, the sender fragments it across several packets. No additional framing is introduced when a request or response is fragmented; the payload is simply split among several packets. Since GATT guarantees ordered
delivery of packets, the SMP header in the first fragment contains sufficient information for re-
assembly.

UART/serial and console

SMP protocol specification by MCUmgr subsystem of Zephyr uses basic framing of data to allow 
multiplexing of UART channel. Multiplexing requires prefixing each frame with two byte marker 
and terminating it with newline. Currently MCUmgr imposes a 127 byte limit on frame size, 
although there are no real protocol constraints that require that limit. The limit includes the 
prefix and the newline character, so the allowed payload size is actually 124 bytes.

Although no such transport exists in Zephyr, it is possible to implement MCUmgr client/server 
over UART transport that does not have framing at all, or uses hardware serial port control, or 
other means of framing.

Frame fragmenting  SMP protocol over serial is fragmented into MTU size frames; each frame 
consists of two byte start marker, body and terminating newline character.

There are four types of types of frames: initial, partial, partial-final and initial-final; each frame 
type differs by start marker and/or body contents.

Frame formats  Initial frame requires to be followed by optional sequence of partial frames 
and finally by partial-final frame. Body is always Base64 encoded, so the body size, here de-
scribed as MTU - 3, is able to actually carry N = (MTU - 3) / 4 * 3 bytes of raw data.

Body of initial frame is preceded by two byte total packet length, encoded in Big Endian, and 
equals size of a raw body plus two bytes, size of CRC16; this means that actual body size allowed 
into an initial frame is N - 2.

If a body size is smaller than N - 4, than it is possible to carry entire body with preceding length 
and following it CRC in a single frame, here called initial-final; for the description of initial-final 
frame look below.

Initial frame format:

<table>
<thead>
<tr>
<th>Content</th>
<th>Size</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0x06 0x09</td>
<td>2 bytes</td>
<td>Frame start marker</td>
</tr>
<tr>
<td>&lt;base64-i&gt;</td>
<td>no more than MTU - 3 bytes</td>
<td>Base64 encoded body</td>
</tr>
<tr>
<td>0x0a</td>
<td>1 byte</td>
<td>Frame termination</td>
</tr>
</tbody>
</table>

<base64-i> is Base64 encoded body of format:

<table>
<thead>
<tr>
<th>Content</th>
<th>Size</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>total length</td>
<td>2 bytes</td>
<td>Big endian 16-bit value representing total length of body + 2 bytes for CRC16; note that size of total length field is not added to total length value.</td>
</tr>
<tr>
<td>body</td>
<td>no more than MTU - 5</td>
<td>Raw body data fragment</td>
</tr>
</tbody>
</table>

Initial-final frame format is similar to initial frame format, but differs by <base64-i> definition.

<base64-i> of initial-final frame, is Base64 encoded data taking form:
Partial frame is continuation after previous initial or other partial frame. Partial frame takes form:

<table>
<thead>
<tr>
<th>Content</th>
<th>Size</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>total</td>
<td>2 bytes</td>
<td>Big endian 16-bit value representing total length of body + 2 bytes for CRC16; note that size of total length field is not added to total length value.</td>
</tr>
<tr>
<td>body</td>
<td>no more than MTU - 7</td>
<td>Raw body data fragment</td>
</tr>
<tr>
<td>crc16</td>
<td>2 bytes</td>
<td>CRC16 of entire packet body, preceding length not included.</td>
</tr>
</tbody>
</table>

The base64-i of partial frame is Base64 encoding of data, taking form:

<table>
<thead>
<tr>
<th>Content</th>
<th>Size</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>body</td>
<td>no more than MTU - 3</td>
<td>Raw body data fragment</td>
</tr>
</tbody>
</table>

The base64-i of partial-final frame is Base64 encoding of data, taking form:

<table>
<thead>
<tr>
<th>Content</th>
<th>Size</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>body</td>
<td>no more than MTU - 3</td>
<td>Raw body data fragment</td>
</tr>
<tr>
<td>crc16</td>
<td>2 bytes</td>
<td>CRC16 of entire packet body, preceding length not included.</td>
</tr>
</tbody>
</table>

**CRC Details** The CRC16 included in final type frames is calculated over only raw data and does not include packet length. CRC16 polynomial is 0x1021 and initial value is 0.

**API Reference**

**group mcumgr_transport_smp**

MCUmgr transport SMP API.

**Typedefs**

```c
typedef int (*smp_transport_out_fn)(struct net_buf *nb)
```

SMP transmit callback for transport.

The supplied *net_buf* is always consumed, regardless of return code.

**Param nb**

The *net_buf* to transmit.
typedef uint16_t (*smp_transport_get_mtu_fn)(const struct net_buf *nb)
SMP MTU query callback for transport.

The supplied `net_buf` should contain a request received from the peer whose MTU is being queried. This function takes a `net_buf` parameter because some transports store connection-specific information in the `net_buf` user header (e.g., the BLE transport stores the peer address).

**Param nb**
Contains a request from the relevant peer.

**Return**
The transport's MTU; 0 if transmission is currently not possible.

typedef int (*smp_transport_ud_copy_fn)(struct net_buf *dst, const struct net_buf *src)
SMP copy user_data callback.

The supplied src `net_buf` should contain a user_data that cannot be copied using regular memcpy function (e.g., the BLE transport `net_buf` user_data stores the connection reference that has to be incremented when is going to be used by another buffer).

**Param dst**
Source buffer user_data pointer.

**Param src**
Destination buffer user_data pointer.

**Return**
0 on success, `mcumgr_err_t` code on failure.

typedef void (*smp_transport_ud_free_fn)(void *ud)
SMP free user_data callback.

This function frees `net_buf` user data, because some transports store connection-specific information in the `net_buf` user data (e.g., the BLE transport stores the connection reference that has to be decreased).

**Param ud**
Contains a user_data pointer to be freed.

typedef bool (*smp_transport_query_valid_check_fn)(struct net_buf *nb, void *arg)
Function for checking if queued data is still valid.

This function is used to check if queued SMP data is still valid e.g. on a remote device disconnecting, this is triggered when `smp_rx_remove_invalid()` is called.

**Param nb**
net buf containing queued request.

**Param arg**
Argument provided when calling `smp_rx_remove_invalid()` function.

**Return**
false if data is no longer valid/should be freed, true otherwise.

**Enums**
enum smp_transport_type
    SMP transport type for client registration.
    Values:
    enumerator SMP_SERIAL_TRANSPORT = 0  
        SMP serial.
    enumerator SMP_BLUETOOTH_TRANSPORT 
        SMP bluetooth.
    enumerator SMP_SHELL_TRANSPORT 
        SMP shell.
    enumerator SMP_UDP_IPV4_TRANSPORT 
        SMP UDP IPv4.
    enumerator SMP_UDP_IPV6_TRANSPORT 
        SMP UDP IPv6.
    enumerator SMP_USER_DEFINED_TRANSPORT 
        SMP user defined type.

Functions

int smp_transport_init(struct smp_transport *smpt)
    Initializes a Zephyr SMP transport object.
    Parameters
    • smpt – The transport to construct.
    Returns
    0 If successful
    Returns
    Negative errno code if failure.

void smp_rx_remove_invalid(struct smp_transport *zst, void *arg)
    Used to remove queued requests for an SMP transport that are no longer valid.
    A smp_transport_query_valid_check_fn() function must be registered for this to function. If the smp_transport_query_valid_check_fn() function returns false during a callback, the queried command will classed as invalid and dropped.
    Parameters
    • zst – The transport to use.
    • arg – Argument provided to callback smp_transport_query_valid_check_fn() function.

void smp_rx_clear(struct smp_transport *zst)
    Used to clear pending queued requests for an SMP transport.
    Parameters
    • zst – The transport to use.
void smp_client_transport_register(struct smp_client_transport_entry *entry)
    Register a Zephyr SMP transport object for client.

    Parameters
    • entry – The transport to construct.

struct smp_transport *smp_client_transport_get(int smpt_type)
    Discover a registered SMP transport client object.

    Parameters
    • smpt_type – Type of transport

    Returns
    Pointer to registered object. Unknown type return NULL.

struct smp_transport_api_t
    #include <smp.h> Function pointers of SMP transport functions, if a handler is NULL
    then it is not supported/implemented.

Public Members

smp_transport_out_fn output
    Transport's send function.

smp_transport_get_mtu_fn get_mtu
    Transport's get-MTU function.

smp_transport_ud_copy_fn ud_copy
    Transport buffer user_data copy function.

smp_transport_ud_free_fn ud_free
    Transport buffer user_data free function.

smp_transport_query_valid_check_fn query_valid_check
    Transport's check function for if a query is valid.

struct smp_transport
    #include <smp.h> SMP transport object for sending SMP responses.

struct smp_client_transport_entry
    #include <smp.h> SMP Client transport structure.

Public Members

struct smp_transport *smpt
    Transport structure pointer.

int smpt_type
    Transport type.
4.5.7 Device Firmware Upgrade

Overview

The Device Firmware Upgrade subsystem provides the necessary frameworks to upgrade the image of a Zephyr-based application at run time. It currently consists of two different modules:

- `subsys/dfu/boot/`: Interface code to bootloaders
- `subsys/dfu/img_util/`: Image management code

The DFU subsystem deals with image management, but not with the transport or management protocols themselves required to send the image to the target device. For information on these protocols and frameworks please refer to the Device Management section.

Flash Image The flash image API as part of the Device Firmware Upgrade (DFU) subsystem provides an abstraction on top of Flash Stream to simplify writing firmware image chunks to flash.

API Reference

group flash_img_api

Abstraction layer to write firmware images to flash.

Functions

`int flash_img_init_id(struct flash_img_context *ctx, uint8_t area_id)`

Initialize context needed for writing the image to the flash.

**Parameters**

- `ctx` – context to be initialized
- `area_id` – flash area id of partition where the image should be written

**Returns**

0 on success, negative errno code on fail

`int flash_img_init(struct flash_img_context *ctx)`

Initialize context needed for writing the image to the flash.

**Parameters**

- `ctx` – context to be initialized

**Returns**

0 on success, negative errno code on fail

`size_t flash_img_bytes_written(struct flash_img_context *ctx)`

Read number of bytes of the image written to the flash.

**Parameters**

- `ctx` – context

**Returns**

Number of bytes written to the image flash.
int flash_img_buffered_write(struct flash_img_context *ctx, const uint8_t *data, size_t len, bool flush)

Process input buffers to be written to the image slot 1.
flash memory in single blocks. Will store remainder between calls.
A final call to this function with flush set to true will write out the remaining block buffer to flash. Since flash is written to in blocks, the contents of flash from the last byte written up to the next multiple of CONFIG_IMG_BLOCK_BUF_SIZE is padded with 0xff.

Parameters
- ctx – context
- data – data to write
- len – Number of bytes to write
- flush – when true this forces any buffered data to be written to flash

Returns
0 on success, negative errno code on fail

int flash_img_check(struct flash_img_context *ctx, const struct flash_img_check *fic, uint8_t area_id)

Verify flash memory length bytes integrity from a flash area.
The start point is indicated by an offset value.
The function is enabled via CONFIG_IMG_ENABLE_IMAGE_CHECK Kconfig options.

Parameters
- area_id – [in] flash area id of partition where the image should be verified.

Returns
0 on success, negative errno code on fail

struct flash_img_context
#include <flash_img.h>

struct flash_img_check
#include <flash_img.h> Structure for verify flash region integrity.
Match vector length is fixed and depends on size from hash algorithm used to verify flash integrity. The current available algorithm is SHA-256.

Public Members

size_t clen
Match vector data.

MCUBoot API The MCUboot API is provided to get version information and boot status of application images. It allows to select application image and boot type for the next boot.
API Reference

**group mcuboot_api**

MCUboot public API for MCUboot control of image boot process.

**Defines**

- **BOOT_SWAP_TYPE_NONE**
  
  Attempt to boot the contents of slot 0.

- **BOOT_SWAP_TYPE_TEST**
  
  Swap to slot 1.
  
  Absent a confirm command, revert back on next boot.

- **BOOT_SWAP_TYPE_PERM**
  
  Swap to slot 1, and permanently switch to booting its contents.

- **BOOT_SWAP_TYPE_REVERT**
  
  Swap back to alternate slot.
  
  A confirm changes this state to NONE.

- **BOOT_SWAP_TYPE_FAIL**
  
  Swap failed because image to be run is not valid.

- **BOOT_IMG_VER_STRLEN_MAX**

- **BOOT_UPGRADE_TEST**
  
  Boot upgrade request modes.

- **BOOT_UPGRADE_PERMANENT**

**Functions**

```c
int boot_read_bank_header(uint8_t area_id, struct mcuboot_img_header *header, size_t header_size)
```

Read the MCUboot image header information from an image bank.

This attempts to parse the image header, From the start of the *area_id* image.

**Parameters**

- **area_id** – *flash_area* ID of image bank which stores the image.
- **header** – On success, the returned header information is available in this structure.
- **header_size** – Size of the header structure passed by the caller. If this is not large enough to contain all of the necessary information, an error is returned.

**Returns**

Zero on success, a negative value on error.
bool boot_is_img_confirmed(void)
    Check if the currently running image is confirmed as OK.
    MCUboot can perform “test” upgrades. When these occur, a new firmware image is
    installed and booted, but the old version will be reverted at the next reset unless the
    new image explicitly marks itself OK.
    This routine can be used to check if the currently running image has been marked as
    OK.

See also:
    boot_write_img_confirmed()

Returns
    True if the image is confirmed as OK, false otherwise.

int boot_write_img_confirmed(void)
    Marks the currently running image as confirmed.
    This routine attempts to mark the currently running firmware image as OK, which will
    install it permanently, preventing MCUboot from reverting it for an older image at the
    next reset.
    This routine is safe to call if the current image has already been confirmed. It will
    return a successful result in this case.

Returns
    0 on success, negative errno code on fail.

int boot_write_img_confirmed_multi(int image_index)
    Marks the image with the given index in the primary slot as confirmed.
    This routine attempts to mark the firmware image in the primary slot as OK, which
    will install it permanently, preventing MCUboot from reverting it for an older image
    at the next reset.
    This routine is safe to call if the current image has already been confirmed. It will
    return a successful result in this case.

Parameters
    • image_index – Image pair index.

Returns
    0 on success, negative errno code on fail.

int mcuboot_swap_type(void)
    Determines the action, if any, that mcuboot will take on the next reboot.

Returns
    a BOOT_SWAP_TYPE_[...] constant on success, negative errno code on fail.

int mcuboot_swap_type_multi(int image_index)
    Determines the action, if any, that mcuboot will take on the next reboot.

Parameters
    • image_index – Image pair index.

Returns
    a BOOT_SWAP_TYPE_[...] constant on success, negative errno code on fail.
int boot_request_upgrade(int permanent)
Marks the image in slot 1 as pending.
On the next reboot, the system will perform a boot of the slot 1 image.

Parameters
• permanent – Whether the image should be used permanently or only
tested once: BOOT_UPGRADE_TEST=run image once, then confirm or re-
vert. BOOT_UPGRADE_PERMANENT=run image forever.

Returns
0 on success, negative errno code on fail.

int boot_request_upgrade_multi(int image_index, int permanent)
Marks the image with the given index in the secondary slot as pending.
On the next reboot, the system will perform a boot of the secondary slot image.

Parameters
• image_index – Image pair index.
• permanent – Whether the image should be used permanently or only
tested once: BOOT_UPGRADE_TEST=run image once, then confirm or re-
vert. BOOT_UPGRADE_PERMANENT=run image forever.

Returns
0 on success, negative errno code on fail.

int boot_erase_img_bank(uint8_t area_id)
Erase the image Bank.

Parameters
• area_id – flash_area ID of image bank to be erased.

Returns
0 on success, negative errno code on fail.

ssize_t boot_get_area_trailer_status_offset(uint8_t area_id)
Get the offset of the status in the image bank.

Parameters
• area_id – flash_area ID of image bank to get the status offset

Returns
a positive offset on success, negative errno code on fail

ssize_t boot_get_trailer_status_offset(size_t area_size)
Get the offset of the status from an image bank size.

Parameters
• area_size – size of image bank

Returns
offset of the status. When negative the status will not fit the given size

struct mcuboot_img_sem_ver
#include <mcuboot.h> MCUboot image header representation for image version.
The header for an MCUboot firmware image contains an embedded version number,
in semantic versioning format. This structure represents the information it contains.
struct mcuboot_img_header_v1

#include <mcuboot.h> Model for the MCUboot image header as of version 1.
This represents the data present in the image header, in version 1 of the header format.
Some information present in the header but not currently relevant to applications is omitted.

Public Members

uint32_t image_size
    The size of the image, in bytes.

struct mcuboot_img_sem_ver sem_ver
    The image version.

struct mcuboot_img_header

#include <mcuboot.h> Model for the MCUBoot image header.
This contains the decoded image header, along with the major version of MCUboot that
the header was built for.
(The MCUboot project guarantees that incompatible changes to the image header will
result in major version changes to the bootloader itself, and will be detectable in the
persistent representation of the header.)

Public Members

uint32_t mcuboot_version
    The version of MCUboot the header is built for.
    The value 1 corresponds to MCUboot versions 1.x.y.

struct mcuboot_img_header_v1 v1
    Header information for MCUboot version 1.

union mcuboot_img_header h
    The header information.
    It is only valid to access fields in the union member corresponding to the mcu-
    boot_version field above.

Bootloaders

MCUboot  Zephyr is directly compatible with the open source, cross-RTOS MCUboot boot loader.
It interfaces with MCUboot and is aware of the image format required by it, so that Device
Firmware Upgrade is available when MCUboot is the boot loader used with Zephyr. The source
code itself is hosted in the MCUboot GitHub Project page.

In order to use MCUboot with Zephyr you need to take the following into account:

1. You will need to define the flash partitions required by MCUboot; see Flash map for details.
2. You will have to specify your flash partition as the chosen code partition
3. Your application’s .conf file needs to enable the `CONFIG_BOOTLOADER_MCUBOOT` Kconfig option in order for Zephyr to be built in an MCUboot-compatible manner.

4. You need to build and flash MCUboot itself on your device.

5. You might need to take precautions to avoid mass erasing the flash and also to flash the Zephyr application image at the correct offset (right after the bootloader).

More detailed information regarding the use of MCUboot with Zephyr can be found in the [MCUboot with Zephyr documentation page on the MCUboot website](#).

### 4.5.8 Over-the-Air Update

**Overview**

Over-the-Air (OTA) Update is a method for delivering firmware updates to remote devices using a network connection. Although the name implies a wireless connection, updates received over a wired connection (such as Ethernet) are still commonly referred to as OTA updates. This approach requires server infrastructure to host the firmware binary and implement a method of signaling when an update is available. Security is a concern with OTA updates; firmware binaries should be cryptographically signed and verified before upgrading.

The [Device Firmware Upgrade section](#) discusses upgrading Zephyr firmware using MCUboot. The same method can be used as part of OTA. The binary is first downloaded into an unoccupied code partition, usually named `slot1_partition`, then upgraded using the `MCUboot` process.

**Examples of OTA**

- **Golioth**
  - Golioth is an IoT management platform that includes OTA updates. Devices are configured to observe your available firmware revisions on the Golioth Cloud. When a new version is available, the device downloads and flashes the binary. In this implementation, the connection between cloud and device is secured using TLS/DTLS, and the signed firmware binary is confirmed by MCUboot before the upgrade occurs.
  - 1. A working sample can be found on the [Golioth Firmware SDK repository](#)
  - 2. The [Golioth OTA documentation](#) includes complete information about the versioning process

- **Eclipse hawkBit™**
  - Eclipse hawkBit™ is an update server framework that uses polling on a REST api to detect firmware updates. When a new update is detected, the binary is downloaded and installed. MCUboot can be used to verify the signature before upgrading the firmware.
  - There is a hawkbit-api sample included in the Zephyr mgmt-samples section.

- **UpdateHub**
  - UpdateHub is a platform for remotely updating embedded devices. Updates can be manually triggered or monitored via polling. When a new update is detected, the binary is downloaded and installed. MCUboot can be used to verify the signature before upgrading the firmware.
  - There is an updatehub-fota sample included in the Zephyr mgmt-samples section.
SMP Server  A Simple Management Protocol (SMP) server can be used to update firmware via Bluetooth Low Energy (BLE) or UDP. MCUmgr is used to send a signed firmware binary to the remote device where it is verified by MCUboot before the upgrade occurs. There is an smp-svr sample included in the Zephyr mgmt-samples section.

Lightweight M2M (LWM2M)  The Lightweight M2M (LWM2M) protocol includes support for firmware update via CONFIG_LWM2M_FIRMWARE_UPDATE_OBJ_SUPPORT. Devices securely connect to an LwM2M server using DTLS. A lwm2m-client sample is available but it does not demonstrate the firmware update feature.

4.5.9 EC Host Command

Overview

The host command protocol defines the interface for a host, or application processor, to communicate with a target embedded controller (EC). The EC Host command subsystem implements the target side of the protocol, generating responses to commands sent by the host. The host command protocol interface supports multiple versions, but this subsystem implementation only support protocol version 3.

Architecture

The Host Command subsystem contains a few components:

- Backend
- General handler
- Command handler

The backend is a layer between a peripheral driver and the general handler. It is responsible for sending and receiving commands via chosen peripheral.

The general handler validates data from the backend e.g. check sizes, checksum, etc. If the command is valid and the user has provided a handler for a received command id, the command handler is called.
SHI (Serial Host Interface) is different to this because it is used only for communication with a host. SHI does not have API itself, thus the backend and peripheral driver layers are combined into one backend layer.
Another case is SPI. Unfortunately, the current SPI API can’t be used to handle the host commands communication. The main issues are unknown command size sent by the host (the SPI transaction sends/receives specific number of bytes) and need to constant sending status byte (the SPI module is enabled and disabled per transaction). It forces implementing the SPI driver within a backend, as it is done for SHI. That means a SPI backend has to be implemented per chip family. However, it can be changed in the future once the SPI API is extended to host command needs. Please check the discussion.

That approach requires configuring the SPI dts node in a special way. The main compatible string of a SPI node has changed to use the Host Command version of a SPI driver. The rest of the properties should be configured as usual. Example of the SPI node for STM32:

```c
&spi1 {
    /* Change the compatible string to use the Host Command version of the
     * STM32 SPI driver */
    compatible = "st,stm32-spi-host-cmd";
    status = "okay";
    dmas = <&dma2 3 0x38440 0x03>,
           <&dma2 0 0x38480 0x03>;
    dma-names = "tx", "rx";
    /* This field is used to point at our CS pin */
    cs-gpios = <&gpioa 4 (GPIO_ACTIVE_LOW | GPIO_PULL_UP)>;
};
```
The STM32 SPI host command backend driver supports the \texttt{st,stm32h7-spi} and \texttt{st,stm32-spi-fifo} variant implementations. To enable these variants, append the corresponding compatible string. For example, to enable FIFO support and support for the STM32H7 SoCs, modify the compatible string as shown.

```
&spi1 {
  compatible = "st,stm32h7-spi", "st,stm32-spi-fifo", "st,stm32-spi-host-cmd";
  ...
};
```

The chip that runs Zephyr is a SPI slave and the \texttt{cs-gpios} property is used to point our CS pin. For the SPI, it is required to set the backend chosen node \texttt{zephyr,host-cmd-spi-backend}.

The supported backend and peripheral drivers:

- Simulator
- SHI - ITE and NPCX
- eSPI - any eSPI slave driver that support \texttt{CONFIG_ESPI_PERIPHERAL_EC_HOST_CMD} and \texttt{CONFIG_ESPI_PERIPHERAL_CUSTOM_OPCODE}
- UART - any UART driver that supports the asynchronous API
- SPI - STM32

**Initialization**

If the application configures one of the following backend chosen nodes and \texttt{CONFIG_EC_HOST_CMD_INITIALIZE_AT_BOOT} is set, then the corresponding backend initializes the host command subsystem by calling \texttt{ec_host_cmd_init()}:

- \texttt{zephyr,host-cmd-espi-backend}
- \texttt{zephyr,host-cmd-shi-backend}
- \texttt{zephyr,host-cmd-uart-backend}
- \texttt{zephyr,host-cmd-spi-backend}

If no backend chosen node is configured, the application must call the \texttt{ec_host_cmd_init()} function directly. This way of initialization is useful if a backend is chosen in runtime based on e.g. GPIO state.

**Buffers**

The host command communication requires buffers for rx and tx. The buffers are be provided by the general handler if \texttt{CONFIG_EC_HOST_CMD_HANDLER_RX_BUFFER_SIZE > 0} for rx buffer and \texttt{CONFIG_EC_HOST_CMD_HANDLER_TX_BUFFER_SIZE > 0} for the tx buffer. The shared buffers are useful for applications that use multiple backends. Defining separate buffers by every backend would increase the memory usage. However, some buffers can be defined by a peripheral driver e.g. eSPI. These ones should be reused as much as possible.

**Logging**

The host command has an embedded logging system of the ongoing communication. There are a few logging levels:

- \texttt{LOG_INF} is used to log a command id of a new command and not success responses. Repeats of the same command are not logged
- \texttt{LOG_DBG} logs every command, even repeats
• LOG_DBG + CONFIG_EC_HOST_CMD_LOG_DBG_BUFFERS logs every command and responses with the data buffers

API Reference

group ec_host_cmd_interface

   EC Host Command Interface.

Defines

EC_HOST_CMD_HANDLER(_id, _function, _version_mask, _request_type, _response_type)

Statically define and register a host command handler. Helper macro to statically define and register a host command handler that has a compile-time-fixed sizes for its both request and response structures.

Parameters

• _id – Id of host command to handle request for.
• _function – Name of handler function.
• _version_mask – The bitfield of all versions that the _function supports. E.g. BIT(0) corresponds to version 0.
• _request_type – The datatype of the request parameters for _function.
• _response_type – The datatype of the response parameters for _function.

EC_HOST_CMD_HANDLER_UNBOUND(_id, _function, _version_mask)

Statically define and register a host command handler without sizes. Helper macro to statically define and register a host command handler whose request or response structure size is not known as compile time.

Parameters

• _id – Id of host command to handle request for.
• _function – Name of handler function.
• _version_mask – The bitfield of all versions that the _function supports. E.g. BIT(0) corresponds to version 0.

Typedefs

typedef int (*ec_host_cmd_backend_api_init)(const struct ec_host_cmd_backend *backend, struct ec_host_cmd_rx_ctx *rx_ctx, struct ec_host_cmd_tx_buf *tx)

Initialize a host command backend. This routine initializes a host command backend. It includes initialization a device used to communication and setting up buffers. This function is called by the ec_host_cmd_init function.

Param backend
   [in] Pointer to the backend structure for the driver instance.

Param rx_ctx
   [inout] Pointer to the receive context object. These objects are used to receive data from the driver when the host sends data. The buf member can be assigned by the backend.
**Param tx**
[inout] Pointer to the transmit buffer object. The buf and len_max members can be assigned by the backend. These objects are used to send data by the backend with the `ec_host_cmd_backend_api_send` function.

**Retval 0** if successful

typedef int (*`ec_host_cmd_backend_api_send`)(const struct `ec_host_cmd_backend` *backend)

Sends data to the host.
Sends data from tx buf that was passed via `ec_host_cmd_backend_api_init` function.

**Param backend**
Pointer to the backed to send data.

**Retval 0** if successful.

typedef void (*`ec_host_cmd_user_cb_t`)(const struct `ec_host_cmd_rx_ctx` *rx_ctx, void *user_data)

typedef enum `ec_host_cmd_status` (*`ec_host_cmd_in_progress_cb_t`)(void *user_data)

typedef enum `ec_host_cmd_status` (*`ec_host_cmd_handler_cb`)(struct `ec_host_cmd_handler_args` *args)

**Enums**

enum `ec_host_cmd_status`
Host command response codes (16-bit).

*Values:*

enumerator `EC_HOST_CMD_SUCCESS` = 0
Host command was successful.

enumerator `EC_HOST_CMD_INVALID_COMMAND` = 1
The specified command id is not recognized or supported.

enumerator `EC_HOST_CMD_ERROR` = 2
Generic Error.

enumerator `EC_HOST_CMD_INVALID_PARAM` = 3
One of more of the input request parameters is invalid.

enumerator `EC_HOST_CMD_ACCESS_DENIED` = 4
Host command is not permitted.

enumerator `EC_HOST_CMD_INVALID_RESPONSE` = 5
Response was invalid (e.g. not version 3 of header).
enumerator EC_HOST_CMD_INVALID_VERSION = 6
    Host command id version unsupported.

enumerator EC_HOST_CMD_INVALID_CHECKSUM = 7
    Checksum did not match.

enumerator EC_HOST_CMD_IN_PROGRESS = 8
    A host command is currently being processed.

enumerator EC_HOST_CMD_UNAVAILABLE = 9
    Requested information is currently unavailable.

enumerator EC_HOST_CMD_TIMEOUT = 10
    Timeout during processing.

enumerator EC_HOST_CMD_OVERFLOW = 11
    Data or table overflow.

enumerator EC_HOST_CMD_INVALID_HEADER = 12
    Header is invalid or unsupported (e.g. not version 3 of header).

enumerator EC_HOST_CMD_REQUEST_TRUNCATED = 13
    Did not receive all expected request data.

enumerator EC_HOST_CMD_RESPONSE_TOO_BIG = 14
    Response was too big to send within one response packet.

enumerator EC_HOST_CMD_BUS_ERROR = 15
    Error on underlying communication bus.

enumerator EC_HOST_CMD_BUSY = 16
    System busy.
    Should retry later.

enumerator EC_HOST_CMD_INVALID_HEADER_VERSION = 17
    Header version invalid.

enumerator EC_HOST_CMD_INVALID_HEADER_CRC = 18
    Header CRC invalid.

enumerator EC_HOST_CMD_INVALID_DATA_CRC = 19
    Data CRC invalid.

enumerator EC_HOST_CMD_DUP_UNAVAILABLE = 20
    Can’t resend response.

enumerator EC_HOST_CMD_MAX = UINT16_MAX
enum ec_host_cmd_log_level

Values:

enumerator EC_HOST_CMD_DEBUG_OFF
enumerator EC_HOST_CMD_DEBUG_NORMAL
enumerator EC_HOST_CMD_DEBUG_EVERY
enumerator EC_HOST_CMD_DEBUG_PARAMS
enumerator EC_HOST_CMD_DEBUG_MODES

Functions

struct ec_host_cmd_backend *ec_host_cmd_backend_get_espi(const struct device *dev)
Get the eSPI Host Command backend pointer.
Get the eSPI pointer backend and pass a pointer to eSPI device instance that will be used for the Host Command communication.

Parameters

- dev – Pointer to eSPI device instance.

Return values
The – eSPI backend pointer.

struct ec_host_cmd_backend *ec_host_cmd_backend_get_shi_npcx(void)
Get the SHI NPCX Host Command backend pointer.

Return values
the – SHI NPCX backend pointer

struct ec_host_cmd_backend *ec_host_cmd_backend_get_shi_ite(void)
Get the SHI ITE Host Command backend pointer.

Return values
the – SHI ITE backend pointer

struct ec_host_cmd_backend *ec_host_cmd_backend_get_uart(const struct device *dev)
Get the UART Host Command backend pointer.
Get the UART pointer backend and pass a pointer to UART device instance that will be used for the Host Command communication.

Parameters

- dev – Pointer to UART device instance.

Return values
The – UART backend pointer.

struct ec_host_cmd_backend *ec_host_cmd_backend_get_spi(struct gpio_dt_spec *cs)
Get the SPI Host Command backend pointer.
Get the SPI pointer backend and pass a chip select pin that will be used for the Host Command communication.

Parameters

4.5. Device Management
Return values

The – SPI backend pointer.

int ec_host_cmd_init(struct ec_host_cmd_backend *backend)

Initialize the host command subsystem.

This routine initializes the host command subsystem. It includes initialization of a backend and the handler. When the application configures the zephyr:host-cmd-espi-backend/zephyr:host-cmd-shi-backend/ zephyr:host-cmd-uart-backend chosen node and CONFIG_EC_HOST_CMD_INITIALIZE_AT_BOOT is set, the chosen backend automatically calls this routine at CONFIG_EC_HOST_CMD_INIT_PRIORITY. Applications that require a run-time selection of the backend must set CONFIG_EC_HOST_CMD_INITIALIZE_AT_BOOT to n and must explicitly call this routine.

Parameters

• backend – [in] Pointer to the backend structure to initialize.

Return values

0 – if successful

int ec_host_cmd_send_response(enum ec_host_cmd_status status, const struct ec_host_cmd_handler_args *args)

Send the host command response.

This routine sends the host command response. It should be used to send IN_PROGRESS status or if the host command handler doesn't return e.g. reboot command.

Parameters

• status – [in] Host command status to be sent.
• args – [in] Pointer of a structure passed to the handler.

Return values

0 – if successful.

void ec_host_cmd_rx_notify(void)

Signal a new host command.

Signal that a new host command has been received. The function should be called by a backend after copying data to the rx buffer and setting the length.

void ec_host_cmd_set_user_cb(ec_host_cmd_user_cb_t cb, void *user_data)

Install a user callback for receiving a host command.

It allows installing a custom procedure needed by a user after receiving a command.

Parameters

• cb – [in] A callback to be installed.
• user_data – [in] User data to be passed to the callback.

const struct ec_host_cmd *ec_host_cmd_get_hc(void)

Get the main ec host command structure.

This routine returns a pointer to the main host command structure. It allows the application code to get inside information for any reason e.g. the host command thread id.

Return values

A – pointer to the main host command structure
FUNC_NORETURN void ec_host_cmd_task(void)
    The thread function for Host Command subsystem.
    This routine calls the Host Command thread entry function. If CON-
    FIG_EC_HOST_CMD_DEDICATED_THREAD is not defined, a new thread is not created,
    and this function has to be called by application code. It doesn't return.

int ec_host_cmd_add_suppressed(uint16_t cmd_id)
    Add a suppressed command.
    Suppressed commands are not logged. Add a command to be suppressed.
    Parameters
        • cmd_id – [in] A command id to be suppressed.
    Return values
        0 – if successful, -EIO if exceeded max number of suppressed commands.

struct ec_host_cmd_rx_ctx
    #include <backend.h> Context for host command backend and handler to pass rx data.

    Public Members

    uint8_t *buf
        Buffer to hold received data.
        The buffer is provided by the handler if CON-
        FIG_EC_HOST_CMD_HANDLER_RX_BUFFER_SIZE > 0. Otherwise, the backend
        should provide the buffer on its own and overwrites buf pointer and len_max in
        the init function.

    size_t len
        Number of bytes written to buf by backend.

    size_t len_max
        Maximum number of bytes to receive with one request packet.

struct ec_host_cmd_tx_buf
    #include <backend.h> Context for host command backend and handler to pass tx data.

    Public Members

    void *buf
        Data to write to the host. The buffer is provided by the handler if CON-
        FIG_EC_HOST_CMD_HANDLER_TX_BUFFER_SIZE > 0.
        Otherwise, the backend should provide the buffer on its own and overwrites buf
        pointer and len_max in the init function.

    size_t len
        Number of bytes to write from buf.
size_t len_max
   Maximum number of bytes to send with one response packet.

struct ec_host_cmd_backend_api
   #include <backend.h>

struct ec_host_cmd
   #include <ec_host_cmd.h>

Public Members

struct k_sem rx_ready
   The backend gives rx_ready (by calling the ec_host_cmd_send_receive function),
   when data in rx_ctx are ready.
   The handler takes rx_ready to read data in rx_ctx.

enum ec_host_cmd_status rx_status
   Status of the rx data checked in the ec_host_cmd_send_received function.

ec_host_cmd_user_cb_t user_cb
   User callback after receiving a command.
   It is called by the ec_host_cmd_send_received function.

struct ec_host_cmd_handler_args
   #include <ec_host_cmd.h> Arguments passed into every installed host command han-
   dler.

Public Members

void *reserved
   Reserved for compatibility.

uint16_t command
   Command identifier.

uint8_t version
   The version of the host command that is being requested.
   This will be a value that has been static registered as valid for the handler.

const void *input_buf
   The incoming data that can be cast to the handlers request type.

uint16_t input_buf_size
   The number of valid bytes that can be read from input_buf.
void *output_buf
    The data written to this buffer will be sent to the host.

uint16_t output_buf_max
    Maximum number of bytes that can be written to the output_buf.

uint16_t output_buf_size
    Number of bytes of output_buf to send to the host.

struct ec_host_cmd_handler
    #include <ec_host_cmd.h> Structure use for statically registering host command handlers.

Public Members

ec_host_cmd_handler_cb handler
    Callback routine to process commands that match id.

uint16_t id
    The numerical command id used as the lookup for commands.

uint16_t version_mask
    The bitfield of all versions that the handler supports, where each bit value represents that the handler supports that version.
    E.g. BIT(0) corresponds to version 0.

uint16_t min_rqtsize
    The minimum input_buf_size enforced by the framework before passing to the handler.

uint16_t min_rsp_size
    The minimum output_buf_size enforced by the framework before passing to the handler.

struct ec_host_cmd_request_header
    #include <ec_host_cmd.h> Header for requests from host to embedded controller.
    Represent the over-the-wire header in LE format for host command requests. This represent version 3 of the host command header. The requests are always sent from host to embedded controller.

Public Members

uint8_t prtcl_ver
    Should be 3.
    The EC will return EC_HOST_CMD_INVALID_HEADER if it receives a header with a version it doesn't know how to parse.
uint8_t checksum
    Checksum of response and data; sum of all bytes including checksum.
    Should total to 0.

uint16_t cmd_id
    Id of command that is being sent.

uint8_t cmd_ver
    Version of the specific cmd_id being requested.
    Valid versions start at 0.

uint8_t reserved
    Unused byte in current protocol version; set to 0.

uint16_t data_len
    Length of data which follows this header.

struct ec_host_cmd_response_header
    
    #include <ec_host_cmd.h> Header for responses from embedded controller to host.
    
    Represent the over-the-wire header in LE format for host command responses. This
    represent version 3 of the host command header. Responses are always sent from
    embedded controller to host.

Public Members

uint8_t prtcl_ver
    Should be 3.

uint8_t checksum
    Checksum of response and data; sum of all bytes including checksum.
    Should total to 0.

uint16_t result
    A ec_host_cmd_status response code for specific command.

uint16_t data_len
    Length of data which follows this header.

uint16_t reserved
    Unused bytes in current protocol version; set to 0.

4.5.10 SMP Groups

Zephyr Management Group

Zephyr management group defines the following commands:
**Erase storage command**  Erase storage command allows clearing the storage partition flash partition on a device, generally this is used when switching to a new application build if the application uses storage that should be cleared (application dependent).

**Erase storage request**  Erase storage request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>63</td>
<td>0</td>
</tr>
</tbody>
</table>

The command sends sends empty CBOR map as data.

**Erase storage response**  Read setting response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>63</td>
<td>0</td>
</tr>
</tbody>
</table>

The command sends an empty CBOR map as data if successful. In case of error the CBOR data takes the form:

SMP version 2

```
{
  (str)"err" : {
    (str)"group" : (uint)
    (str)"rc"   : (uint)
  }
}
```

SMP version 1

```
{
  (str)"rc"   : (int)
}
```

where:

- “err”  →  *mcumgr_group_t* group of the group-based error code. Only appears if an error is returned when using SMP version 2.
- “group”  contains the index of the group-based error code. Only appears if non-zero (error condition) when using SMP version 2.
- “rc”  mcumgr_err_t only appears if non-zero (error condition) when using SMP version 1 or for SMP errors when using SMP version 2.

## 4.6  Digital Signal Processing (DSP)
The DSP API provides an architecture agnostic way for signal processing. Currently, the API will work on any architecture but will likely not be optimized. The status of the various architectures can be found below:

<table>
<thead>
<tr>
<th>Architecture</th>
<th>Status</th>
</tr>
</thead>
<tbody>
<tr>
<td>ARC</td>
<td>Optimized</td>
</tr>
<tr>
<td>ARM</td>
<td>Optimized</td>
</tr>
<tr>
<td>ARM64</td>
<td>Optimized</td>
</tr>
<tr>
<td>MIPS</td>
<td>Unoptimized</td>
</tr>
<tr>
<td>NIOS2</td>
<td>Unoptimized</td>
</tr>
<tr>
<td>POSIX</td>
<td>Unoptimized</td>
</tr>
<tr>
<td>RISCV</td>
<td>Unoptimized</td>
</tr>
<tr>
<td>RISCV64</td>
<td>Unoptimized</td>
</tr>
<tr>
<td>SPARC</td>
<td>Unoptimized</td>
</tr>
<tr>
<td>X86</td>
<td>Unoptimized</td>
</tr>
<tr>
<td>XTENSA</td>
<td>Unoptimized</td>
</tr>
</tbody>
</table>

### 4.6.1 Using zDSP

zDSP provides various backend options which are selected automatically for the application. By default, including the CMSIS module will enable all architectures to use the zDSP APIs. This can be done by setting:

```c
CONFIG_CMSIS_DSP=y
```

If your application requires some additional customization, it's possible to enable CONFIG_DSP_BACKEND_CUSTOM which means that the application is responsible for providing the implementation of the zDSP library.

### 4.6.2 Optimizing for your architecture

If your architecture is showing as Unoptimized, it's possible to add a new zDSP backend to better support it. To do that, a new Kconfig option should be added to subsys/dsp/Kconfig along with the required dependencies and the default set for DSP_BACKEND Kconfig choice.

Next, the implementation should be added at subsys/dsp/<backend>/ and linked in at subsys/dsp/CMakeLists.txt. To add architecture-specific attributes, its corresponding Kconfig option should be added to subsys/dsp/Kconfig and use them to update DSP_DATA and DSP_STATIC_DATA in include/zephyr/dsp/dsp.h.

### 4.6.3 API Reference

```c
group math_dsp
    DSP Interface.
```
Typedefs

typedef int8_t q7_t
   8-bit fractional data type in 1.7 format.

typedef int16_t q15_t
   16-bit fractional data type in 1.15 format.

typedef int32_t q31_t
   32-bit fractional data type in 1.31 format.

typedef int64_t q63_t
   64-bit fractional data type in 1.63 format.

typedef __fp16 float16_t
   16-bit floating point type definition.

typedef float float32_t
   32-bit floating-point type definition.

typedef double float64_t
   64-bit floating-point type definition.

4.7 File Systems

Zephyr RTOS Virtual Filesystem Switch (VFS) allows applications to mount multiple file systems at different mount points (e.g., /fatfs and /lfs). The mount point data structure contains all the necessary information required to instantiate, mount, and operate on a file system. The File system Switch decouples the applications from directly accessing an individual file system's specific API or internal functions by introducing file system registration mechanisms.

In Zephyr, any file system implementation or library can be plugged into or pulled out through a file system registration API. Each file system implementation must have a globally unique integer identifier; use FS_TYPE_EXTERNAL_BASE to avoid clashes with in-tree identifiers.

```c
int fs_register(int type, const struct fs_file_system_t *fs);
int fs_unregister(int type, const struct fs_file_system_t *fs);
```

Zephyr RTOS supports multiple instances of a file system by making use of the mount point as the disk volume name, which is used by the file system library while formatting or mounting a disk.

A file system is declared as:

```c
static struct fs_mount_t mp = {
   .type = FS_FATFS,
   .mnt_point = FATFS_MNTP,
   .fs_data = &fat_fs,
};
```

where

- FS_FATFS is the file system type like FATFS or LittleFS.
• FATFS_MNTP is the mount point where the file system will be mounted.
• fat_fs is the file system data which will be used by fs_mount() API.

4.7.1 Samples

Samples for the VFS are mainly supplied in samples/subsys/fs, although various examples of the VFS usage are provided as important functionalities in samples for different subsystems. Here is the list of samples worth looking at:

- samples/subsys/fs/fat_fs is an example of FAT file system usage with SDHC media;
- samples/subsys/shell/fs is an example of Shell fs subsystem, using internal flash partition formatted to LittleFS;
- samples/subsys/usb/mass/ example of USB Mass Storage device that uses FAT FS driver with RAM or SPI connected FLASH, or LittleFS in flash, depending on the sample configuration.

4.7.2 API Reference

Related code samples

File system manipulation
Use file system API with various filesystems and storage devices.

File system shell
Access a LittleFS file system partition in flash using the file system shell.

Format filesystem
Format different storage devices for different file systems.

LittleFS filesystem
Use file system API over LittleFS.

USB Mass Storage
Expose board's RAM or FLASH as a USB disk using USB Mass Storage driver.

**group file_system_api**

File System APIs.

**fs_open open and creation mode flags**

**FS_O_READ**
Open for read flag.

**FS_O_WRITE**
Open for write flag.

**FS_O_RDWR**
Open for read-write flag combination.
FS_O_MODE_MASK
   Bitmask for read and write flags.

FS_O_CREATE
   Create file if it does not exist.

FS_O_APPEND
   Open/create file for append.

FS_O_FLAGS_MASK
   Bitmask for open/create flags.

FS_O_MASK
   Bitmask for open flags.

fs_seek whence parameter values

FS_SEEK_SET
   Seek from the beginning of file.

FS_SEEK_CUR
   Seek from a current position.

FS_SEEK_END
   Seek from the end of file.

Defines

FS_MOUNT_FLAG_NO_FORMAT
   Flag prevents formatting device if requested file system not found.

FS_MOUNT_FLAG_READ_ONLY
   Flag makes mounted file system read-only.

FS_MOUNT_FLAG_AUTOMOUNT
   Flag used in pre-defined mount structures that are to be mounted on startup.
   This flag has no impact in user-defined mount structures.

FS_MOUNT_FLAG_USE_DISK_ACCESS
   Flag requests file system driver to use Disk Access API.
   When the flag is set to the fs_mount_t.flags prior to fs_mount call, a file system needs to use the Disk Access API, otherwise mount callback for the driver should return -ENOSUP; when the flag is not set the file system driver should use Flash API by default, unless it only supports Disc Access API. When file system will use Disk Access API and the flag is not set, the mount callback for the file system should set the flag on success.
FSTAB_ENTRY_DT_MOUNT_FLAGS(node_id)
Get the common mount flags for an fstab entry.

**Parameters**
- node_id – the node identifier for a child entry in a zephyr fstab node.

**Returns**
a value suitable for initializing an fs_mount_t flags member.

FS_FSTAB_ENTRY(node_id)
The name under which a zephyr fstab entry mount structure is defined.

**Parameters**
- node_id – the node identifier for a child entry in a zephyr fstab node.

FS_FSTAB_DECLARE_ENTRY(node_id)
Generate a declaration for the externally defined fstab entry.
This will evaluate to the name of a struct fs_mount_t object.

**Parameters**
- node_id – the node identifier for a child entry in a zephyr fstab node.

**Enums**

enum fs_dir_entry_type
Enumeration for directory entry types.

**Values:**

enumerator FS_DIR_ENTRY_FILE = 0
Identifier for file entry.

enumerator FS_DIR_ENTRY_DIR
Identifier for directory entry.

Enumeration to uniquely identify file system types.
Zephyr supports in-tree file systems and external ones. Each requires a unique identifier used to register the file system implementation and to associate a mount point with the file system type. This anonymous enum defines global identifiers for the in-tree file systems.

External file systems should be registered using unique identifiers starting at FS_TYPE_EXTERNAL_BASE. It is the responsibility of applications that use external file systems to ensure that these identifiers are unique if multiple file system implementations are used by the application.

**Values:**

enumerator FS_FATFS = 0
Identifier for in-tree FatFS file system.

enumerator FS_LITTLEFS
Identifier for in-tree LittleFS file system.
enumerator FS_EXT2
Identifier for in-tree Ext2 file system.

enumerator FS_TYPE_EXTERNAL_BASE
Base identifier for external file systems.

Functions

static inline void fs_file_t_init(struct fs_file_t *zfp)
Initialize fs_file_t object.

Initializes the fs_file_t object; the function needs to be invoked on object before first use with fs_open.

Parameters
• zfp – Pointer to file object

static inline void fs_dir_t_init(struct fs_dir_t *zdp)
Initialize fs_dir_t object.

Initializes the fs_dir_t object; the function needs to be invoked on object before first use with fs_opendir.

Parameters
• zdp – Pointer to file object

int fs_open(struct fs_file_t *zfp, const char *file_name, fs_mode_t flags)
Open or create file.

Opens or possibly creates a file and associates a stream with it. Successfully opened file, when no longer in use, should be closed with fs_close().

flags can be 0 or a binary combination of one or more of the following identifiers:
• FS_O_READ open for read
• FS_O_WRITE open for write
• FS_O_RDWR open for read/write (FS_O_READ | FS_O_WRITE)
• FS_O_CREATE create file if it does not exist
• FS_O_APPEND move to end of file before each write

Warning: If flags are set to 0 the function will open file, if it exists and is accessible, but you will have no read/write access to it.

Parameters
• zfp – Pointer to a file object
• file_name – The name of a file to open
• flags – The mode flags

Return values
• 0 – on success;
• -EBUSY – when zfp is already used;
• -EINVAL – when a bad file name is given;
• -EROFS – when opening read-only file for write, or attempting to create a file on a system that has been mounted with the FS_MOUNT_FLAG_READ_ONLY flag;
• -ENOENT – when the file does not exist at the path;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code, depending on a file system back-end.

int fs_close(struct fs_file_t *zfp)
Close file.
Flushes the associated stream and closes the file.

Parameters
• zfp – Pointer to the file object

Return values
• 0 – on success;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – a negative errno code on error.

int fs_unlink(const char *path)
Unlink file.
Deletes the specified file or directory

Parameters
• path – Path to the file or directory to delete

Return values
• 0 – on success;
• -EINVAL – when a bad file name is given;
• -EROFS – if file is read-only, or when file system has been mounted with the FS_MOUNT_FLAG_READ_ONLY flag;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code on error.

int fs_rename(const char *from, const char *to)
Rename file or directory.
Performs a rename and / or move of the specified source path to the specified destination. The source path can refer to either a file or a directory. All intermediate directories in the destination path must already exist. If the source path refers to a file, the destination path must contain a full filename path, rather than just the new parent directory. If an object already exists at the specified destination path, this function causes it to be unlinked prior to the rename (i.e., the destination gets clobbered).

Note: Current implementation does not allow moving files between mount points.

Parameters
• from – The source path
• to – The destination path

Return values
• 0 – on success;
• -EINVAL – when a bad file name is given, or when rename would cause move between mount points;
• -EROFS – if file is read-only, or when file system has been mounted with the FS_MOUNT_FLAG_READ_ONLY flag;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code on error.

ssize_t fs_read(struct fs_file_t *zfp, void *ptr, size_t size)
Read file.
Reads up to size bytes of data to ptr pointed buffer, returns number of bytes read. A returned value may be lower than size if there were fewer bytes available than requested.

Parameters
• zfp – Pointer to the file object
• ptr – Pointer to the data buffer
• size – Number of bytes to be read

Return values
• >=0 – a number of bytes read, on success;
• -EBADF – when invoked on zfp that represents unopened/closed file;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – a negative errno code on error.

ssize_t fs_write(struct fs_file_t *zfp, const void *ptr, size_t size)
Write file.
Attempts to write size number of bytes to the specified file. If a negative value is returned from the function, the file pointer has not been advanced. If the function returns a non-negative number that is lower than size, the global errno variable should be checked for an error code, as the device may have no free space for data.

Parameters
• zfp – Pointer to the file object
• ptr – Pointer to the data buffer
• size – Number of bytes to be written

Return values
• >=0 – a number of bytes written, on success;
• -EBADF – when invoked on zfp that represents unopened/closed file;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code on error.

int fs_seek(struct fs_file_t *zfp, off_t offset, int whence)
Seek file.
Moves the file position to a new location in the file. The offset is added to file position based on the whence parameter.

Parameters
• zfp – Pointer to the file object
offset – Relative location to move the file pointer to
whence – Relative location from where offset is to be calculated.
- FS_SEEK_SET for the beginning of the file;
- FS_SEEK_CUR for the current position;
- FS_SEEK_END for the end of the file.

Return values
- 0 – on success;
- -EBADF – when invoked on zfp that represents unopened/closed file;
- -ENOTSUP – if not supported by underlying file system driver;
- <0 – an other negative errno code on error.

off_t fs.tell(struct fs_file_t *zfp)
Get current file position.

Retrieves and returns the current position in the file stream.

The current revision does not validate the file object.

Parameters
- zfp – Pointer to the file object

Return values
- >= 0 a current position in file;
- -EBADF – when invoked on zfp that represents unopened/closed file;
- -ENOTSUP – if not supported by underlying file system driver;
- <0 – an other negative errno code on error.

int fs_truncate(struct fs_file_t *zfp, off_t length)
Truncate or extend an open file to a given size.

Truncates the file to the new length if it is shorter than the current size of the file. Expands the file if the new length is greater than the current size of the file. The expanded region would be filled with zeroes.

Note: In the case of expansion, if the volume got full during the expansion process, the function will expand to the maximum possible length and return success. Caller should check if the expanded size matches the requested length.

Parameters
- zfp – Pointer to the file object
- length – New size of the file in bytes

Return values
- 0 – on success;
- -EBADF – when invoked on zfp that represents unopened/closed file;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – an other negative errno code on error.
int fs_sync(struct fs_file_t *zfp)
Flush cached write data buffers of an open file.

The function flushes the cache of an open file; it can be invoked to ensure data gets written to the storage media immediately, e.g. to avoid data loss in case if power is removed unexpectedly.

**Note:** Closing a file will cause caches to be flushed correctly so the function need not be called when the file is being closed.

**Parameters**
- zfp – Pointer to the file object

**Return values**
- 0 – on success;
- -EBADF – when invoked on zfp that represents unopened/closed file;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – a negative errno code on error.

int fs_mkdir(const char *path)
Directory create.

Creates a new directory using specified path.

**Parameters**
- path – Path to the directory to create

**Return values**
- 0 – on success;
- -EEXIST – if entry of given name exists;
- -EROFS – if path is within read-only directory, or when file system has been mounted with the FS_MOUNT_FLAG_READ_ONLY flag;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – an other negative errno code on error

int fs_opendir(struct fs_dir_t *zdp, const char *path)
Directory open.

Opens an existing directory specified by the path.

**Parameters**
- zdp – Pointer to the directory object
- path – Path to the directory to open

**Return values**
- 0 – on success;
- -EINVAL – when a bad directory path is given;
- -EBUSY – when zdp is already used;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – a negative errno code on error.
int fs_readdir(struct fs_dir_t *zdp, struct fs_dirent *entry)

Directory read entry.

Reads directory entries of an open directory. In end-of-dir condition, the function will return 0 and set the entry->name[0] to 0.

Note: Most existing underlying file systems do not generate POSIX special directory entries “.” or “..”. For consistency the abstraction layer will remove these from lower layer results so higher layers see consistent results.

Parameters

• zdp – Pointer to the directory object
• entry – Pointer to zfs_dirent structure to read the entry into

Return values

• 0 – on success or end-of-dir;
• -EN0ENT – when no such directory found;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – a negative errno code on error.

int fs_closedir(struct fs_dir_t *zdp)

Directory close.

Closes an open directory.

Parameters

• zdp – Pointer to the directory object

Return values

• 0 – on success;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – a negative errno code on error.

int fs_mount(struct fs_mount_t *mp)

Mount filesystem.

Perform steps needed for mounting a file system like calling the file system specific mount function and adding the mount point to mounted file system list.

Note: Current implementation of ELM FAT driver allows only following mount points: “/RAM:”, “/NAND:”, “/CF:”, “/SD:”, “/SD2:”, “/USB:”, “/USB2:”, “/USB3:” or mount points that consist of single digit, e.g: “/0:”, “/1:” and so forth.

Parameters

• mp – Pointer to the fs_mount_t structure. Referenced object is not changed if the mount operation failed. A reference is captured in the fs infrastructure if the mount operation succeeds, and the application must not mutate the structure contents until fsUnmount is successfully invoked on the same pointer.

Return values

• 0 – on success;
• -ENOENT – when file system type has not been registered;
• -ENOTSUP – when not supported by underlying file system driver; when
  FS_MOUNT_FLAG_USE_DISK_ACCESS is set but driver does not support it.
• -EROFS – if system requires formatting but FS_MOUNT_FLAG_READ_ONLY has
  been set;
• <0 – an other negative errno code on error.

int fs_unmount(struct fs_mount_t *mp)
Unmount filesystem.
Perform steps needed to unmount a file system like calling the file system specific un-
mount function and removing the mount point from mounted file system list.

Parameters
• mp – Pointer to the fs_mount_t structure

Return values
• 0 – on success;
• -EINVAL – if no system has been mounted at given mount point;
• -ENOTSUP – when not supported by underlying file system driver;
• <0 – an other negative errno code on error.

int fs_readmount(int *index, const char **name)
Get path of mount point at index.
This function iterates through the list of mount points and returns the directory name
of the mount point at the given index. On success index is incremented and name is
set to the mount directory name. If a mount point with the given index does not exist,
name will be set to NULL.

Parameters
• index – Pointer to mount point index
• name – Pointer to pointer to path name

Return values
• 0 – on success;
• -ENOENT – if there is no mount point with given index.

int fs_stat(const char *path, struct fs_dirent *entry)
File or directory status.
Checks the status of a file or directory specified by the path.

Note: The file on a storage device may not be updated until it is closed.

Parameters
• path – Path to the file or directory
• entry – Pointer to the zfs_dirent structure to fill if the file or directory
  exists.

Return values
• 0 – on success;
• -EINVAL – when a bad directory or file name is given;
• -ENOENT – when no such directory or file is found;
• -ENOTSUP – when not supported by underlying file system driver;
• <0 – negative errno code on error.

int fs_statvfs(const char *path, struct fs_statvfs *stat)
Retrieves statistics of the file system volume.
Returns the total and available space in the file system volume.

Parameters
• path – Path to the mounted directory
• stat – Pointer to the zfs_statvfs structure to receive the fs statistics.

Return values
• 0 – on success;
• -EINVAL – when a bad path to a directory, or a file, is given;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code on error.

int fs_mkfs(int fs_type, uintptr_t dev_id, void *cfg, int flags)
Create fresh file system.

Parameters
• fs_type – Type of file system to create.
• dev_id – Id of storage device.
• cfg – Backend dependent init object. If NULL then default configuration
  is used.
• flags – Additional flags for file system implementation.

Return values
• 0 – on success;
• <0 – negative errno code on error.

int fs_register(int type, const struct fs_file_system_t *fs)
Register a file system.
Register file system with virtual file system. Number of allowed file system types to be
registered is controlled with the CONFIG_FILE_SYSTEM_MAX_TYPES Kconfig option.

Parameters
• type – Type of file system (ex: FS_FATFS)
• fs – Pointer to File system

Return values
• 0 – on success;
• -EALREADY – when a file system of a given type has already been regis-
  tered;
• -ENOSCP – when there is no space left, in file system registry, to add this
  file system type.
int fs_unregister(int type, const struct fs_file_system_t *fs)

Unregister a file system.

Unregister file system from virtual file system.

**Parameters**

- `type` – Type of file system (ex: FS_FATFS)
- `fs` – Pointer to File system

**Return values**

- 0 – on success;
- -EINVAL – when file system of a given type has not been registered.

```c
struct fs_mount_t
#include <fs.h> File system mount info structure.
```

**Public Members**

```c
sys_dnode_t node
Entry for the fs_mount_list list.
```

```c
int type
File system type.
```

```c
const char *mnt_point
Mount point directory name (ex: “/fatfs”)```

```c
void *fs_data
Pointer to file system specific data.
```

```c
void *storage_dev
Pointer to backend storage device.
```

```c
size_t mountp_len
Length of Mount point string.
```

```c
const struct fs_file_system_t *fs
Pointer to File system interface of the mount point.
```

```c
uint8_t flags
Mount flags.
```

```c
struct fs_dirent
#include <fs.h> Structure to receive file or directory information.
Used in functions that read the directory entries to get file or directory information.
```

**4.7. File Systems**
Public Members

enum fs_dir_entry_type type
    File/directory type (FS_DIR_ENTRY_FILE or FS_DIR_ENTRY_DIR)

char name[MAX_FILE_NAME + 1]
    Name of file or directory.

size_t size
    Size of file (0 if directory).

struct fs_statvfs
    #include <fs.h> Structure to receive volume statistics.
    Used to retrieve information about total and available space in the volume.

Public Members

unsigned long f_bsize
    Optimal transfer block size.

unsigned long f_frsize
    Allocation unit size.

unsigned long f_blocks
    Size of FS in f_frsize units.

unsigned long f_bfree
    Number of free blocks.

struct fs_file_t
    #include <fs_interface.h> File object representing an open file.
    The object needs to be initialized with fs_file_t_init().

Public Members

void *filep
    Pointer to file object structure.

const struct fs_mount_t *mp
    Pointer to mount point structure.

fs_mode_t flags
    Open/create flags.

struct fs_dir_t
    #include <fs_interface.h> Directory object representing an open directory.
    The object needs to be initialized with fs_dir_t_init().
Public Members

void *dirp
   Pointer to directory object structure.

const struct fs_mount_t *mp
   Pointer to mount point structure.

struct fs_file_system_t
   #include <fs_sys.h> File System interface structure.

File operations

int (*open)(struct fs_file_t *filp, const char *fs_path, fs_mode_t flags)
   Opens or creates a file, depending on flags given.
   Param filp   File to open/create.
   Param fs_path Path to the file.
   Param flags   Flags for opening/creating the file.
   Return   0 on success, negative errno code on fail.

ssize_t (*read)(struct fs_file_t *filp, void *dest, size_t nbytes)
   Reads nbytes number of bytes.
   Param filp   File to read from.
   Param dest   Destination buffer.
   Param nbytes Number of bytes to read.
   Return   Number of bytes read on success, negative errno code on fail.

ssize_t (*write)(struct fs_file_t *filp, const void *src, size_t nbytes)
   Writes nbytes number of bytes.
   Param filp   File to write to.
   Param src    Source buffer.
   Param nbytes Number of bytes to write.
   Return   Number of bytes written on success, negative errno code on fail.

int (*lseek)(struct fs_file_t *filp, off_t off, int whence)
   Moves the file position to a new location in the file.
   Param filp   File to move.
   Param off    Relative offset from the position specified by whence.
**Param whence**
Position in the file. Possible values: SEEK_CUR, SEEK_SET, SEEK_END.

**Return**
New position in the file or negative errno code on fail.

```c
off_t (*tell)(struct fs_file_t *filp)
```
Retrieves the current position in the file.

- **Param filp**
File to get the current position from.

- **Return**
Current position in the file or negative errno code on fail.

```c
int (*truncate)(struct fs_file_t *filp, off_t length)
```
Truncates/expands the file to the new length.

- **Param filp**
File to truncate/expand.

- **Param length**
New length of the file.

- **Return**
0 on success, negative errno code on fail.

```c
int (*sync)(struct fs_file_t *filp)
```
Flushes the cache of an open file.

- **Param filp**
File to flush.

- **Return**
0 on success, negative errno code on fail.

```c
int (*close)(struct fs_file_t *filp)
```
Flushes the associated stream and closes the file.

- **Param filp**
File to close.

- **Return**
0 on success, negative errno code on fail.

**Directory operations**

```c
int (*opendir)(struct fs_dir_t *dirp, const char *fs_path)
```
Opens an existing directory specified by the path.

- **Param dirp**
Directory to open.

- **Param fs_path**
Path to the directory.

- **Return**
0 on success, negative errno code on fail.

```c
int (*readdir)(struct fs_dir_t *dirp, struct fs_dirent *entry)
```
Reads directory entries of an open directory.

- **Param dirp**
Directory to read from.

- **Param entry**
Next directory entry in the dirp directory.

- **Return**
0 on success, negative errno code on fail.
int (*closedir)(struct fs_dir_t *dirp)
   Closes an open directory.
   **Param dirp**
   Directory to close.
   **Return**
   0 on success, negative errno code on fail.

**File system level operations**

int (*mount)(struct fs_mount_t *mountp)
   Mounts a file system.
   **Param mountp**
   Mount point.
   **Return**
   0 on success, negative errno code on fail.

int (*unmount)(struct fs_mount_t *mountp)
   Unmounts a file system.
   **Param mountp**
   Mount point.
   **Return**
   0 on success, negative errno code on fail.

int (*unlink)(struct fs_mount_t *mountp, const char *name)
   Deletes the specified file or directory.
   **Param mountp**
   Mount point.
   **Param name**
   Path to the file or directory to delete.
   **Return**
   0 on success, negative errno code on fail.

int (*rename)(struct fs_mount_t *mountp, const char *from, const char *to)
   Renames a file or directory.
   **Param mountp**
   Mount point.
   **Param from**
   Path to the file or directory to rename.
   **Param to**
   New name of the file or directory.
   **Return**
   0 on success, negative errno code on fail.

int (*mkdir)(struct fs_mount_t *mountp, const char *name)
   Creates a new directory using specified path.
   **Param mountp**
   Mount point.
   **Param name**
   Path to the directory to create.
   **Return**
   0 on success, negative errno code on fail.
int (*stat)(struct fs_mount_t *mountp, const char *path, struct fs_dirent *entry)

Checks the status of a file or directory specified by the path.

**Param mountp**
Mount point.

**Param path**
Path to the file or directory.

**Param entry**
Directory entry.

**Return**
0 on success, negative errno code on fail.

int (*statvfs)(struct fs_mount_t *mountp, const char *path, struct fs_statvfs *stat)

Returns the total and available space on the file system volume.

**Param mountp**
Mount point.

**Param path**
Path to the file or directory.

**Param stat**
File system statistics.

**Return**
0 on success, negative errno code on fail.

int (*mkfs)(uintptr_t dev_id, void *cfg, int flags)

Formats a device to specified file system type.

Available only if CONFIG_FILE_SYSTEM_MKFS is enabled.

**Note:** This operation destroys existing data on the target device.

**Param dev_id**
Device identifier.

**Param cfg**
File system configuration.

**Param flags**
Formatting flags.

**Return**
0 on success, negative errno code on fail.

### 4.8 Formatted Output

Applications as well as Zephyr itself requires infrastructure to format values for user consumption. The standard C99 library `printf()` functionality fulfills this need for streaming output devices or memory buffers, but in an embedded system devices may not accept streamed data and memory may not be available to store the formatted output.

Internal Zephyr API traditionally provided this both for `printf()` and for Zephyr's internal minimal libc, but with separate internal interfaces. Logging, tracing, shell, and other applications made use of either these APIs or standard libc routines based on build options.

The `cbprintf()` public APIs convert C99 format strings and arguments, providing output produced one character at a time through a callback mechanism, replacing the original internal functions and providing support for almost all C99 format specifications. Existing use of `sprintf()` C libraries in Zephyr can be converted to `snprintfcb()` to avoid pulling in libc implementations.
Several Kconfig options control the set of features that are enabled, allowing some control over features and memory usage:

- CONFIG_CBPRINTF_FULL_INTEGRAL or CONFIG_CBPRINTF_REduced_INTEGRAL
- CONFIG_CBPRINTF_FP_SUPPORT
- CONFIG_CBPRINTF_FP_A_SUPPORT
- CONFIG_CBPRINTF_FP_ALWAYS_A
- CONFIG_CBPRINTF_N_SPECIFIER

CONFIG_CBPRINTF_LIBC_SUBSTS can be used to provide functions that behave like standard libc functions but use the selected cbprintf formatter rather than pulling in another formatter from libc.

In addition CONFIG_CBPRINTF_NANO can be used to revert back to the very space-optimized but limited formatter used for printk() before this capability was added.

### 4.8.1 Cbprintf Packaging

Typically, strings are formatted synchronously when a function from printf family is called. However, there are cases when it is beneficial that formatting is deferred. In that case, a state (format string and arguments) must be captured. Such state forms a self-contained package which contains format string and arguments. Additionally, package may contain copies of strings which are part of a format string (format string or any %s argument). Package primary content resembles va_list stack frame thus standard formatting functions are used to process a package. Since package contains data which is processed as va_list frame, strict alignment must be maintained. Due to required padding, size of the package depends on alignment. When package is copied, it should be copied to a memory block with the same alignment as origin.

Package can have following variants:

- **Self-contained** - non read-only strings appended to the package. String can be formatted from such package as long as there is access to read-only string locations. Package may contain information where read-only strings are located within the package. That information can be used to convert packet to fully self-contained package.

- **Fully self-contained** - all strings are appended to the package. String can be formatted from such package without any external data.

- **Transient** - only arguments are stored. Package contain information where pointers to non read-only strings are located within the package. Optionally, it may contain read-only string location information. String can be formatted from such package as long as non read-only strings are still valid and read-only strings are accessible. Alternatively, package can be converted to **self-contained** package or **fully self-contained** if information about read-only string locations is present in the package.

Package can be created using two methods:

- **runtime** - using cbprintf_package() or cbvprintf_package(). This method scans format string and based on detected format specifiers builds the package.

- **static** - types of arguments are detected at compile time by the preprocessor and package is created as simple assignments to a provided memory. This method is significantly faster than runtime (more than 15 times) but has following limitations: requires _Generic keyword (C11 feature) to be supported by the compiler and cannot distinguish between %p and %s if char pointer is used. It treats all (unsigned) char pointers as %s thus it will attempt to append string to a package. It can be handled correctly during conversion from transient package to self-contained package using CBPRINTF_PACKAGE_CONVERT_PTR_CHECK flag. However, it requires access to the format string and it is not always possible thus it is
recommended to cast char pointers used for %p to void *. There is a logging warning generated by \texttt{cbprintf\_package\_convert()} called with \texttt{CBPRINTF\_PACKAGE\_CONVERT\_PTR\_CHECK} flag when char pointer is used with %p.

Several \texttt{Kconfig} options control behavior of the packaging:

- \texttt{CONFIG\_CBPRINTF\_PACKAGE\_LONGDOUBLE}
- \texttt{CONFIG\_CBPRINTF\_STATIC\_PACKAGE\_CHECK\_ALIGNMENT}

\textbf{Cbprintf package conversion}

It is possible to convert package to a variant which contains more information, e.g \texttt{transient} package can be converted to \texttt{self-contained}. Conversion to \texttt{fully self-contained} package is possible if \texttt{CBPRINTF\_PACKAGE\_ADD\_RO\_STR\_POS} flag was used when package was created.

\texttt{cbprintf\_package\_copy()} is used to calculate space needed for the new package and to copy and convert a package.

\textbf{Cbprintf package format}

Format of the package contains paddings which are platform specific. Package consists of header which contains size of package (excluding appended strings) and number of appended strings. It is followed by the arguments which contains alignment paddings and resembles \texttt{va\_list} stack frame. It is followed by data associated with character pointer arguments used by the string which are not appended to the string (but may be appended later by \texttt{cbprintf\_package\_convert()}). Finally, package, optionally, contains appended strings. Each string contains 1 byte header which contains index of the location where address argument is stored. During packaging address is set to null and before string formatting it is updated to point to the current string location within the package. Updating address argument must happen just before string formatting since address changes whenever package is copied.

<table>
<thead>
<tr>
<th>Header sizeof(\texttt{void *} )</th>
<th>1 byte: Argument list size including header and \texttt{fmt} (in 32 bit words)</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>1 byte: Number of strings appended to the package</td>
</tr>
<tr>
<td></td>
<td>1 byte: Number of read-only string argument locations</td>
</tr>
<tr>
<td></td>
<td>1 byte: Number of transient string argument locations</td>
</tr>
<tr>
<td></td>
<td>platform specific padding to sizeof(\texttt{void *} )</td>
</tr>
<tr>
<td>Arguments</td>
<td>Pointer to \texttt{fmt} (or null if \texttt{fmt} is appended to the package)</td>
</tr>
<tr>
<td></td>
<td>(optional padding for platform specific alignment)</td>
</tr>
<tr>
<td></td>
<td>argument 0</td>
</tr>
<tr>
<td></td>
<td>(optional padding for platform specific alignment)</td>
</tr>
<tr>
<td></td>
<td>argument 1</td>
</tr>
<tr>
<td>String location information</td>
<td>Indexes of words within the package where read-only strings are located</td>
</tr>
<tr>
<td>(optional)</td>
<td>Pairs of argument index and argument location index where transient strings are located</td>
</tr>
<tr>
<td>Appended strings (optional)</td>
<td>1 byte: Index within the package to the location of associated argument</td>
</tr>
<tr>
<td></td>
<td>Null terminated string</td>
</tr>
</tbody>
</table>

\textbf{Warning:} If \texttt{CONFIG\_MINIMAL\_LIBC} is selected in combination with \texttt{CONFIG\_CBPRINTF\_NANO} formatting with C standard library functions like \texttt{printf} or \texttt{snprintf} is limited. Among other
things the %n specifier, most format flags, precision control, and floating point are not supported.

Limitations and recommendations

- C11 _Generic support is required by the compiler to use static (fast) packaging.
- It is recommended to cast any character pointer used with %p format specifier to other pointer type (e.g., void *). If format string is not accessible then only static packaging is possible and it will append all detected strings. Character pointer used for %p will be considered as string pointer. Copying from unexpected location can have serious consequences (e.g., memory fault or security violation).

4.8.2 API Reference

_group cbprintf_apis

Defines

CBPRINTF_PACKAGE_ALIGNMENT
Required alignment of the buffer used for packaging.

CBPRINTF_MUST_RUNTIME_PACKAGE(flags, ...)
Determine if string must be packaged in run time.
Static packaging can be applied if size of the package can be determined at compile time. In general, package size can be determined at compile time if there are no string arguments which might be copied into package body if they are considered transient.

Note: By default any char pointers are considered to be pointing at transient strings. This can be narrowed down to non const pointers by using CBPRINTF_PACKAGE_CONST_CHAR_RO.

Parameters
- ... – String with arguments.
- flags – option flags. See Package flags.

Return values
- 1 – if string must be packaged in run time.
- 0 – string can be statically packaged.

CBPRINTF_STATIC_PACKAGE(packaged, inlen, outlen, align_offset, flags, ...)
Statically package string.
Build string package from formatted string. It assumes that formatted string is in the read only memory.
If _Generic is not supported then runtime packaging is performed.

Parameters
• **packaged** – pointer to where the packaged data can be stored. Pass a null pointer to skip packaging but still calculate the total space required. The data stored here is relocatable, that is it can be moved to another contiguous block of memory. It must be aligned to the size of the longest argument. It is recommended to use CBPRINTF_PACKAGE_ALIGNMENT for alignment.

• **inlen** – set to the number of bytes available at `packaged`. If `packaged` is `NULL` the value is ignored.

• **outlen** – variable updated to the number of bytes required to completely store the packed information. If input buffer was too small it is set to -ENOSPC.

• **align_offset** – input buffer alignment offset in bytes. Where offset 0 means that buffer is aligned to CBPRINTF_PACKAGE_ALIGNMENT. Xtensa requires that `packaged` is aligned to CBPRINTF_PACKAGE_ALIGNMENT so it must be multiply of CBPRINTF_PACKAGE_ALIGNMENT or 0.

• **flags** – option flags. See Package flags.

• **...** – formatted string with arguments. Format string must be constant.

**Typedefs**

typedef int (*cbprintf_cb)()

Signature for a cbprintf callback function.

This function expects two parameters:

• c a character to output. The output behavior should be as if this was cast to an unsigned char.

• ctx a pointer to an object that provides context for the output operation.

The declaration does not specify the parameter types. This allows a function like `fputc` to be used without requiring all context pointers to be to a FILE object.

**Return**

the value of `c` cast to an unsigned char then back to int, or a negative error code that will be returned from `cbprintf()`.

typedef int (*cbprintf_convert_cb)(const void *buf, size_t len, void *ctx)

Signature for a cbprintf multibyte callback function.

return Amount of copied data or negative error code.

**Param buf**

data.

**Param len**

data length.

**Param ctx**

a pointer to an object that provides context for the operation.
typedef int (*cbvprintf_external_formatter_func)(cbprintf_cb out, void *ctx, const char *fmt, va_list ap)

Signature for a external formatter function identical to cbvprintf.

This function expects the following parameters:

**Param out**
the function used to emit each generated character.

**Param ctx**
a pointer to an object that provides context for the external formatter.

**Param fmt**
a standard ISO C format string with characters and conversion specifications.

**Param ap**
captured stack arguments corresponding to the conversion specifications found within fmt.

**Return**
printf like return values: the number of characters printed, or a negative error value returned from external formatter.

**Functions**

int cbprintf_package(void *packaged, size_t len, uint32_t flags, const char *format, ...)
Capture state required to output formatted data later.

Like cbprintf() but instead of processing the arguments and emitting the formatted results immediately all arguments are captured so this can be done in a different context, e.g. when the output function can block.

In addition to the values extracted from arguments this will ensure that copies are made of the necessary portions of any string parameters that are not confirmed to be stored in read-only memory (hence assumed to be safe to refer to directly later).

**Parameters**

- **packaged** – pointer to where the packaged data can be stored. Pass a null pointer to store nothing but still calculate the total space required. The data stored here is relocatable, that is it can be moved to another contiguous block of memory. However, under condition that alignment is maintained. It must be aligned to at least the size of a pointer.

- **len** – this must be set to the number of bytes available at packaged if it is not null. If packaged is null then it indicates hypothetical buffer alignment offset in bytes compared to CBPRINTF_PACKAGE_ALIGNMENT alignment. Buffer alignment offset impacts returned size of the package. Xtensa requires that buffer is always aligned to CBPRINTF_PACKAGE_ALIGNMENT so it must be multiple of CBPRINTF_PACKAGE_ALIGNMENT or 0 when packaged is null.

- **flags** – option flags. See Package flags.

- **format** – a standard ISO C format string with characters and conversion specifications.

- **...** – arguments corresponding to the conversion specifications found within format.

**Return values**
Zephyr Project Documentation, Release 3.6.0-rc3

- **nonnegative** – the number of bytes successfully stored at `packaged`. This will not exceed `len`.
- `-EINVAL` – if `format` is not acceptable
- `-EFAULT` – if `packaged` alignment is not acceptable
- `-ENOSPC` – if `packaged` was not null and the space required to store exceed `len`.

```c
int cbvprintf_package(void *packaged, size_t len, uint32_t flags, const char *format, va_list ap)
```

Capture state required to output formatted data later.

Like `cbprintf()` but instead of processing the arguments and emitting the formatted results immediately all arguments are captured so this can be done in a different context, e.g. when the output function can block.

In addition to the values extracted from arguments this will ensure that copies are made of the necessary portions of any string parameters that are not confirmed to be stored in read-only memory (hence assumed to be safe to refer to directly later).

**Parameters**

- **`packaged`** – pointer to where the packaged data can be stored. Pass a null pointer to store nothing but still calculate the total space required. The data stored here is relocatable, that is it can be moved to another contiguous block of memory. The pointer must be aligned to a multiple of the largest element in the argument list.
- **`len`** – this must be set to the number of bytes available at `packaged`. Ignored if `packaged` is NULL.
- **`flags`** – option flags. See Package flags.
- **`format`** – a standard ISO C format string with characters and conversion specifications.
- **`ap`** – captured stack arguments corresponding to the conversion specifications found within `format`.

**Return values**

- **nonnegative** – the number of bytes successfully stored at `packaged`. This will not exceed `len`.
- `-EINVAL` – if `format` is not acceptable
- `-ENOSPC` – if `packaged` was not null and the space required to store exceed `len`.

```c
int cbprintf_package_convert(void *in_packaged, size_t in_len, cbprintf_convert_cb cb, 
                             void *ctx, uint32_t flags, uint16_t *strl, size_t strl_len)
```

Convert a package.

Converting may include appending strings used in the package to the package body. If input package was created with CBPRINTF_PACKAGE_ADD_RO_STR_POS or CBPRINTF_PACKAGE_ADD_RW_STR_POS, it contains information where strings are located within the package. This information can be used to copy strings during the conversion.

`cb` is called with portions of the output package. At the end of the conversion `cb` is called with null buffer.

**Parameters**

- **`in_packaged`** – Input package.
• **in_len** – Input package length. If 0 package length will be retrieved from the `in_package`.

• **cb** – callback called with portions of the converted package. If null only length of the output package is calculated.

• **ctx** – Context provided to the `cb`.

• **flags** – Flags. See Package convert flags.

• **strl** – [inout] if `packaged` is null, it is a pointer to the array where `strl_len` first string lengths will be stored. If `packaged` is not null, it contains lengths of first `strl_len` strings. It can be used to optimize copying so that string length is calculated only once (at length calculation phase when `packaged` is null.)

• **strl_len** – Number of elements in `strl` array.

**Return values**

• **Positive** – output package size.

• **-ENOSPC** – if `packaged` was not null and the space required to store exceed `len`.

```c
static inline int cbprintf_package_copy(void *in_package, size_t in_len, void *packaged, size_t len, uint32_t flags, uint16_t *strl, size_t strl_len)
```

Copy package with optional appending of strings.

`cbprintf_package_convert` is used to convert and store converted package in the new location.

**Parameters**

• **in_package** – Input package.

• **in_len** – Input package length. If 0 package length will be retrieved from the `in_package`.

• **packaged** – [out] Output package. If null only length of the output package is calculated.

• **len** – Available space in the location pointed by `packaged`. Not used when `packaged` is null.

• **flags** – Flags. See Package convert flags.

• **strl** – [inout] if `packaged` is null, it is a pointer to the array where `strl_len` first string lengths will be stored. If `packaged` is not null, it contains lengths of first `strl_len` strings. It can be used to optimize copying so that string length is calculated only once (at length calculation phase when `packaged` is null.)

• **strl_len** – Number of elements in `strl` array.

**Return values**

• **Positive** – Output package size.

• **-ENOSPC** – if `packaged` was not null and the space required to store exceed `len`.

```c
static inline int cbprintf_fsc_package(void *in_package, size_t in_len, void *packaged, size_t len)
```

Convert package to fully self-contained (fsc) package.

Package may not be self contain since strings by default are stored by address. Package may be partially self-contained when transient (not read only) strings are appended to
the package. Such package can be decoded only when there is an access to read-only
strings.

Fully self-contained has (fsc) contains all strings used in the package. A package can be
converted to fsc package if it was create with CBPRINTF_PACKAGE_ADD_RO_STR_POS
flag. Such package will contain necessary data to find read only strings in the package
and copy them into the package body.

Parameters

• in_packaged – pointer to original package created with
  CBPRINTF_PACKAGE_ADD_RO_STR_POS.
• in_len – in_packaged length.
• packaged – pointer to location where fully self-contained version of the
  input package will be written. Pass a null pointer to calculate space re-
  quired.
• len – must be set to the number of bytes available at packaged. Not used
  if packaged is null.

Return values

• nonegative – the number of bytes successfully stored at packaged. This
  will not exceed len. If packaged is null, calculated length.
• -ENOSPC – if packaged was not null and the space required to store exceed
  len.
• -EINVAL – if in_packaged is null.

int cbprintf_external(cbprintf_cb out, cbvprintf_external_formatter_func formatter, void
  *
  ctx, void *packaged)

Generate the output for a previously captured format operation using an external for-
matter.

Note: Memory indicated by packaged will be modified in a non-destructive way,
meaning that it could still be reused with this function again.

Parameters

• out – the function used to emit each generated character.
• formatter – external formatter function.
• ctx – a pointer to an object that provides context for the external format-
  ter.
• packaged – the data required to generate the formatted output, as cap-
  tured by cbprintf_package() or cbvprintf_package(). The alignment re-
  quirement on this data is the same as when it was initially created.

Returns

printf like return values: the number of characters printed, or a negative
error value returned from external formatter.

int cbprintf(cbprintf_cb out, void *ctx, const char *format, ...)

*printf-like output through a callback.

This is essentially printf() except the output is generated character-by-character using
the provided out function. This allows formatting text of unbounded length without
incurring the cost of a temporary buffer.
All formatting specifiers of C99 are recognized, and most are supported if the functionality is enabled.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

**Parameters**
- **out** – the function used to emit each generated character.
- **ctx** – context provided when invoking out
- **format** – a standard ISO C format string with characters and conversion specifications.
- **...** – arguments corresponding to the conversion specifications found within format.

**Returns**
the number of characters printed, or a negative error value returned from invoking out.

```c
static inline int cbvprintf(cbprintf_cb out, void *ctx, const char *format, va_list ap)
```

varargs-aware *printf-like output through a callback.

This is essentially vsprintf() except the output is generated character-by-character using the provided out function. This allows formatting text of unbounded length without incurring the cost of a temporary buffer.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

**Parameters**
- **out** – the function used to emit each generated character.
- **ctx** – context provided when invoking out
- **format** – a standard ISO C format string with characters and conversion specifications.
- **ap** – a reference to the values to be converted.

**Returns**
the number of characters generated, or a negative error value returned from invoking out.

```c
static inline int cbvprintf_tagged_args(cbprintf_cb out, void *ctx, const char *format, va_list ap)
```

varargs-aware *printf-like output through a callback with tagged arguments.

This is essentially vsprintf() except the output is generated character-by-character using the provided out function. This allows formatting text of unbounded length without incurring the cost of a temporary buffer.

Note that the argument list ap are tagged.
Parameters

- `out` – the function used to emit each generated character.
- `ctx` – context provided when invoking `out`
- `format` – a standard ISO C format string with characters and conversion specifications.
- `ap` – a reference to the values to be converted.

Returns

the number of characters generated, or a negative error value returned from invoking `out`.

static inline int `cbpprint`(cbprintf_cb `out`, void *`ctx`, void *`packaged`)

Generate the output for a previously captured format operation.

Parameters

- `out` – the function used to emit each generated character.
- `ctx` – context provided when invoking `out`
- `packaged` – the data required to generate the formatted output, as captured by `cbprintf_package()` or `cbvprintf_package()`. The alignment requirement on this data is the same as when it was initially created.

Returns

the number of characters printed, or a negative error value returned from invoking `out`.

int `fprintfcb`(FILE *`stream`, const char *`format`, ...)

fprintf using Zephyrs cbprintf infrastructure.

return The number of characters printed.

Note: This function is available only when CONFIG_CBPRINTF_LIBC_SUBSTS is selected.

Note: The functionality of this function is significantly reduced when CONFIG_CBPRINTF_NANO is selected.
- **format** – a standard ISO C format string with characters and conversion specifications.
- ... – arguments corresponding to the conversion specifications found within format.

```c
int vfprintfcb(FILE *stream, const char *format, va_list ap)
```

vfprintf using Zephyrs cbprintf infrastructure.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

**Parameters**
- **stream** – the stream to which the output should be written.
- **format** – a standard ISO C format string with characters and conversion specifications.
- **ap** – a reference to the values to be converted.

**Returns**
The number of characters printed.

```c
int printfcb(const char *format, ...)
```

printf using Zephyrs cbprintf infrastructure.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

**Parameters**
- **format** – a standard ISO C format string with characters and conversion specifications.
- ... – arguments corresponding to the conversion specifications found within format.

**Returns**
The number of characters printed.

```c
int vprintfcb(const char *format, va_list ap)
```

vprintf using Zephyrs cbprintf infrastructure.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.
Parameters

- **format** – a standard ISO C format string with characters and conversion specifications.
- **ap** – a reference to the values to be converted.

Returns

The number of characters printed.

```c
int snprintfcb(char *str, size_t size, const char *format, ...)
```

snprintf using Zephyrs cbprintf infrastructure.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

Parameters

- **str** – where the formatted content should be written
- **size** – maximum number of characters for the formatted output, including the terminating null byte.
- **format** – a standard ISO C format string with characters and conversion specifications.
- **...** – arguments corresponding to the conversion specifications found within `format`.

Returns

The number of characters that would have been written to `str`, excluding the terminating null byte. This is greater than the number actually written if `size` is too small.

```c
int vsnprintfcb(char *str, size_t size, const char *format, va_list ap)
```

vsnprintf using Zephyrs cbprintf infrastructure.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

Parameters

- **str** – where the formatted content should be written
- **size** – maximum number of characters for the formatted output, including the terminating null byte.
- **format** – a standard ISO C format string with characters and conversion specifications.
- **ap** – a reference to the values to be converted.
4.9 Input

The input subsystem provides an API for dispatching input events from input devices to the application.

4.9.1 Input Events

The subsystem is built around the `input_event` structure. An input event represents a change in an individual event entity, for example the state of a single button, or a movement in a single axis.

The `input_event` structure describes the specific event, and includes a synchronization bit to indicate that the device reached a stable state, for example when the events corresponding to multiple axes of a multi-axis device have been reported.

4.9.2 Input Devices

An input device can report input events directly using `input_report()` or any related function; for example buttons or other on-off input entities would use `input_report_key()`.

Complex devices may use a combination of multiple events, and set the `sync` bit once the output is stable.

The `input_report*` functions take a `device` pointer, which is used to indicate which device reported the event and can be used by subscribers to only receive events from a specific device. If there's no actual device associated with the event, it can be set to `NULL`, in which case only subscribers with no device filter will receive the event.

4.9.3 Application API

An application can register a callback using the `INPUT_CALLBACK_DEFINE` macro. If a device node is specified, the callback is only invoked for events from the specific device, otherwise the callback will receive all the events in the system. This is the only type of filtering supported, any more complex filtering logic has to be implemented in the callback itself.

The subsystem can operate synchronously or by using an event queue, depending on the `CONFIG_INPUT_MODE` option. If the input thread is used, all the events are added to a queue and executed in a common input thread. If the thread is not used, the callback are invoked directly in the input driver context.

The synchronous mode can be used in a simple application to keep a minimal footprint, or in a complex application with an existing event model, where the callback is just a wrapper to pipe back the event in a more complex application specific event system.

4.9.4 HID code mapping

A common use case for input devices is to use them to generate HID reports. For this purpose, the `input_to_hid_code()` and `input_to_hid_modifier()` functions can be used to map input codes to HID codes and modifiers.
4.9.5 Kscan Compatibility

Input devices generating X/Y/Touch events can be used in existing applications based on the Keyboard Scan API by enabling both CONFIG_INPUT and CONFIG_KSCAN, defining a zephyr, kscan-input node as a child node of the corresponding input device and pointing the zephyr, keyboard-scan chosen node to the compatibility device node, for example:

```c
chosen {
    zephyr,keyboard-scan = &kscan_input;
};

ft5336@38 {
    kscan_input: kscan-input {
        compatible = "zephyr,kscan-input";
    };
};
```

4.9.6 Driver Documentation

GPIO Keyboard Matrix

The gpio-kbd-matrix driver supports a large variety of keyboard matrix hardware configurations and has numerous options to change its behavior. This is an overview of some common setups and how they can be supported by the driver.

The conventional configuration for all of these is that the driver reads on the row GPIOs (inputs) and selects on the columns GPIOs (output).

**Base use case, no isolation diodes, interrupt capable GPIOs**  This is the common configuration found on consumer keyboards with membrane switches and flexible circuit boards, no isolation diodes, requires ghosting detection (which is enabled by default).

```
fig. 1: A 3x3 matrix, no diodes

The system must support GPIO interrupts, and the interrupt can be enabled on all row GPIOs at the same time.

```

```c
kbd-matrix {
    compatible = "gpio-kbd-matrix";
    row-gpios = <&gpio0 0 (GPIO_PULL_UP | GPIO_ACTIVE_LOW)>,
                <&gpio0 1 (GPIO_PULL_UP | GPIO_ACTIVE_LOW)>,
                <&gpio0 2 (GPIO_PULL_UP | GPIO_ACTIVE_LOW)>;
```
In this configuration the matrix scanning library enters idle mode once all keys are released, and
the keyboard matrix thread only wakes up when a key has been pressed.

GPIOs for columns that are not currently selected are configured in high impedance mode. This
means that the row state may need some time to settle to avoid misreading the key state from
a column to the following one. The settle time can be tweaked by changing the settle-time-us
property.

**Isolation diodes**  If the matrix has isolation diodes for every key, then it’s possible to:

- disable ghosting detection, allowing any key combination to be detected
- configuring the driver to drive unselected columns GPIO to inactive state rather than high
  impedance, this allows to reduce the settle time (potentially down to 0), and use the more
  efficient port wide GPIO read APIs (happens automatically if the GPIO pins are sequential)

Matrixes with diodes going from rows to columns must use pull-ups on rows and active low
columns.

![3x3 matrix with row to column isolation diodes](image)

Fig. 2: A 3x3 matrix with row to column isolation diodes.
Matrixes with diodes going from columns to rows must use pull-downs on rows and active high columns.

![A 3x3 matrix with column to row isolation diodes.](image)

**Fig. 3:** A 3x3 matrix with column to row isolation diodes.

```c
kbd-matrix {
    compatible = "gpio-kbd-matrix";
    row-gpios = <&gpio0 0 (GPIO_PULL_DOWN | GPIO_ACTIVE_HIGH)>,
        <&gpio0 1 (GPIO_PULL_DOWN | GPIO_ACTIVE_HIGH)>,
        <&gpio0 2 (GPIO_PULL_DOWN | GPIO_ACTIVE_HIGH)>;
    col-gpios = <&gpio0 3 GPIO_ACTIVE_HIGH>,
        <&gpio0 4 GPIO_ACTIVE_HIGH>,
        <&gpio0 5 GPIO_ACTIVE_HIGH>;
    col-drive-inactive;
    settle-time-us = <0>;
    no-ghostkey-check;
};
```

**GPIO with no interrupt support** Some GPIO controllers have limitations on GPIO interrupts, and may not support enabling interrupts on all row GPIOs at the same time.

In this case, the driver can be configured to not use interrupt at all, and instead idle by selecting all columns and keep polling on the row GPIOs, which is a single GPIO API operation if the pins are sequential.

This configuration can be enabled by setting the idle-mode property to poll:

```c
kbd-matrix {
    compatible = "gpio-kbd-matrix";
    idle-mode = "poll";
};
```

**GPIO multiplexer** In more extreme cases, such as if the columns are using a multiplexer and it's impossible to select all of them at the same time, the driver can be configured to scan continuously.

This can be done by setting idle-mode to scan and poll-timeout-ms to 0.
### Row and column GPIO selection

If the row GPIOs are sequential and on the same GPIO controller, the driver automatically switches API to read from the whole GPIO port rather than the individual pins. This is particularly useful if the GPIOs are not memory mapped, for example on an I2C or SPI port expander, as this significantly reduces the number of transactions on the corresponding bus.

The same is true for column GPIOs, but only if the matrix is configured for `col-drive-inactive`, so that is only usable for matrices with isolation diodes.

### 16-bit row support

The driver uses an 8-bit datatype to store the row state by default, which limits the matrix row size to 8. This can be increased to 16 by enabling the `CONFIG_INPUT_KBD_MATRIX_16_BIT_ROW` option.

### Actual key mask configuration

If the key matrix is not complete, a map of the keys that are actually populated can be specified using the `actual-key-mask` property. This allows the matrix state to be filtered to remove keys that are not present before ghosting detection, potentially allowing key combinations that would otherwise be blocked by it.

For example for a 3x3 matrix missing a key:

```c
kbd-matrix {
    compatible = "gpio-kbd-matrix";
    ...actual-key-mask = <0x07 0x05 0x07>;
};
```

This would allow, for example, to detect pressing SW1, SW2 and SW4 at the same time without triggering anti ghosting.

The actual key mask can be changed at runtime by enabling `CONFIG_INPUT_KBD_ACTUAL_KEY_MASK_DYNAMIC` and using the `inputkbd_matrix_actual_key_mask_set()` API.
**Keymap configuration**  Keyboard matrix devices report a series of x/y/touch events. These can be mapped to normal key events using the `input-keymap` driver.

For example, the following would setup a keymap device that take the x/y/touch events as an input and generate corresponding key events as an output:

```c
kbd {
  ...
  keymap {
    compatible = "input-keymap";
    keymap = <
      MATRIX_KEY(0, 0, INPUT_KEY_1)
      MATRIX_KEY(0, 1, INPUT_KEY_2)
      MATRIX_KEY(0, 2, INPUT_KEY_3)
      MATRIX_KEY(1, 0, INPUT_KEY_4)
      MATRIX_KEY(1, 1, INPUT_KEY_5)
      MATRIX_KEY(1, 2, INPUT_KEY_6)
      MATRIX_KEY(2, 0, INPUT_KEY_7)
      MATRIX_KEY(2, 1, INPUT_KEY_8)
      MATRIX_KEY(2, 2, INPUT_KEY_9)
    >;
    row-size = <3>;
    col-size = <3>;
  }
};
```

**Keyboard matrix shell commands**  The shell command `kbd_matrix_state_dump` can be used to test the functionality of any keyboard matrix driver implemented using the keyboard matrix library. Once enabled it logs the state of the matrix every time it changes, and once disabled it prints an or-mask of any key that has been detected, which can be used to set the `actual-key-mask` property.

The command can be enabled using the `CONFIG_INPUT_SHELL_KBD_MATRIX_STATE`.

Example usage:

```bash
uart:~$ device list
devices:
- kbd-matrix (READY)

uart:~$ input kbd_matrix_state_dump kbd-matrix
Keyboard state logging enabled for kbd-matrix
[00:01:41.678,466] <inf> input: kbd-matrix state [01 -- -- --] (1)
[00:01:41.784,912] <inf> input: kbd-matrix state [-- -- -- --] (0)
...
press more buttons...

uart:~$ input kbd_matrix_state_dump off
Keyboard state logging disabled
[00:01:47.967,651] <inf> input: kbd-matrix key-mask [07 05 07 --] (8)
```

**Keyboard matrix library**  The GPIO keyboard matrix driver is based on a generic keyboard matrix library, which implements the core functionalities such as scanning delays, debouncing, idle mode etc. This can be reused to implement other keyboard matrix drivers, potentially application specific.

`group input_kbd_matrix`

Keyboard Matrix API.
**Defines**

`INPUT_KBD_MATRIX_COLUMN_DRIVE_NONE`

Special drive_column argument for not driving any column.

`INPUT_KBD_MATRIX_COLUMN_DRIVE_ALL`

Special drive_column argument for driving all the columns.

`INPUT_KBD_MATRIX_SCAN_OCURRENCES`

Number of tracked scan cycles.

`PRIkbdrow`

`INPUT_KBD_ACTUAL_KEY_MASK_CONST`

`INPUT_KBD_MATRIX_ROW_BITS`

Maximum number of rows.

`INPUT_KBD_MATRIX_DATA_NAME(node_id, name)`

`INPUT_KBD_MATRIX_DT_DEFINE_ROW_COL(node_id, _row_size, _col_size)`

Defines the common keyboard matrix support data from devicetree, specify row and col count.

`INPUT_KBD_MATRIX_DT_DEFINE(node_id)`

Defines the common keyboard matrix support data from devicetree.

`INPUT_KBD_MATRIX_DT_INST_DEFINE_ROW_COL(inst, row_size, col_size)`

Defines the common keyboard matrix support data from devicetree instance, specify row and col count.

**Parameters**

- `inst` – Instance.
- `row_size` – The matrix row count.
- `col_size` – The matrix column count.

`INPUT_KBD_MATRIX_DT_INST_DEFINE(inst)`

Defines the common keyboard matrix support data from devicetree instance.

**Parameters**

- `inst` – Instance.

`INPUT_KBD_MATRIX_DT_COMMON_CONFIG_INIT_ROW_COL(node_id, _api, _row_size, _col_size)`

Initialize common keyboard matrix config from devicetree, specify row and col count.

**Parameters**

- `node_id` – The devicetree node identifier.
- `_api` – Pointer to a `input_kbd_matrix_api` structure.
- `row_size` – The matrix row count.
- `col_size` – The matrix column count.
**INPUT_KBD_MATRIX_DT_COMMON_CONFIG_INIT**(node_id, api)

Initialize common keyboard matrix config from devicetree.

**Parameters**
- **node_id** – The devicetree node identifier.
- **api** – Pointer to a `input_kbd_matrix_api` structure.

**INPUT_KBD_MATRIX_DT_INST_COMMON_CONFIG_INIT_ROW_COL**(inst, api, row_size, col_size)

Initialize common keyboard matrix config from devicetree instance, specify row and col count.

**Parameters**
- **inst** – Instance.
- **api** – Pointer to a `input_kbd_matrix_api` structure.
- **row_size** – The matrix row count.
- **col_size** – The matrix column count.

**INPUT_KBD_MATRIX_DT_INST_COMMON_CONFIG_INIT**(inst, api)

Initialize common keyboard matrix config from devicetree instance.

**Parameters**
- **inst** – Instance.
- **api** – Pointer to a `input_kbd_matrix_api` structure.

**INPUT_KBD_STRUCT_CHECK**(config, data)

Validate the offset of the common data structures.

**Parameters**
- **config** – Name of the config structure.
- **data** – Name of the data structure.

**Typedefs**

```c
typedef uint8_t kbd_row_t
```

Row entry data type.

**Functions**

```c
int input_kbd_matrix_actual_key_mask_set(const struct device *dev, uint8_t row, uint8_t col, bool enabled)
```

Enables or disables a specific row, column combination in the actual key mask.

This allows enabling or disabling specific row, column combination in the actual key mask in runtime. It can be useful if some of the keys are not present in some configuration, and the specific configuration is determined in runtime. Requires `CONFIG_INPUT_KBD_ACTUAL_KEY_MASK_DYNAMIC` to be enabled.

**Parameters**
- **dev** – Pointer to the keyboard matrix device.
- **row** – The matrix row to enable or disable.
- **col** – The matrix column to enable or disable.
- **enabled** – Whether the specified row, col has to be enabled or disabled.

**Return values**
- 0 – If the change is successful.
- -errno – Negative errno if row or col are out of range for the device.

```c
void input_kbd_matrix_poll_start(const struct device *dev)
```
Starts the keyboard matrix scanning cycle, this should be called in reaction of a press event, after the device has been put in detect mode.

**Parameters**
- dev – Keyboard matrix device instance.

```c
void input_kbd_matrix_drive_column_hook(const struct device *dev, int col)
```
Drive column hook.
This can be implemented by the application to handle column selection quirks. Called after the driver specific drive_column function. Requires CONFIG_INPUT_KBD_DRIVE_COLUMN_HOOK to be enabled.

**Parameters**
- dev – Keyboard matrix device instance.
- col – The column to drive, or `INPUT_KBD_MATRIX_COLUMN_DRIVE_NONE` or `INPUT_KBD_MATRIX_COLUMN_DRIVE_ALL`.

```c
int input_kbd_matrix_common_init(const struct device *dev)
```
Common function to initialize a keyboard matrix device at init time.
This function must be called at the end of the device init function.

**Parameters**
- dev – Keyboard matrix device instance.

**Return values**
- 0 – If initialized successfully.
- -errno – Negative errno in case of failure.

```c
struct input_kbd_matrix_api
#include <input_kbd_matrix.h> Keyboard matrix internal APIs.
```

**Public Members**

```c
void (*drive_column)(const struct device *dev, int col)
```
Request to drive a specific column.
Request to drive a specific matrix column, or none, or all.

**Param dev**
- Pointer to the keyboard matrix device.

**Param col**
- The column to drive, or `INPUT_KBD_MATRIX_COLUMN_DRIVE_NONE` or `INPUT_KBD_MATRIX_COLUMN_DRIVE_ALL`. 4.9. Input 817
**kbd_row_t** (*read_row*) (const struct device *dev)

Read the matrix row.

**Param dev**
Pointer to the keyboard matrix device.

void (*set_detect_mode*) (const struct device *dev, bool enabled)

Request to put the matrix in detection mode.

Request to put the driver in detection mode, this is called after a request to drive all the column and typically involves reenabling interrupts row pin changes.

**Param dev**
Pointer to the keyboard matrix device.

**Param enable**
Whether detection mode has to be enabled or disabled.

```c
#include <input_kbd_matrix.h>
```

This structure **must** be placed first in the driver's config structure.

```c
#include <input_kbd_matrix.h>
```

This structure **must** be placed first in the driver's data structure.

### 4.9.7 API Reference

**Related code samples**

**LVGL basic sample**
Display a "Hello World" and react to user input using LVGL.

**USB HID and CDC ACM**
Expose multiple USB HID and CDC ACM instances.

**USB HID mouse**
Implement a basic HID mouse device.

```c
#include <input_kbd_matrix.h>
```

This structure **must** be placed first in the driver's config structure.

```c
#include <input_kbd_matrix.h>
```

This structure **must** be placed first in the driver's data structure.

---

**group input_interface**
Input Interface.

**Defines**

```c
INPUT_CALLBACK_DEFINE(_dev, _callback)
```

Register a callback structure for input events.

The _dev field can be used to only invoke callback for events generated by a specific device. Setting dev to NULL causes callback to be invoked for every event.

**Parameters**

- _dev – device pointer or NULL.
- _callback – The callback function.
Functions

int input_report(const struct device *dev, uint8_t type, uint16_t code, int32_t value, bool sync, k_timeout_t timeout)

Report a new input event.
This causes all the listeners for the specified device to be triggered, either synchronously or through the input thread if utilized.

Parameters

• dev – Device generating the event or NULL.
• type – Event type (see INPUT_EV_CODES).
• value – Event value.
• sync – Set the synchronization bit for the event.
• timeout – Timeout for reporting the event, ignored if CONFIG_INPUT_MODE_SYNCHRONOUS is used.

Return values

• 0 – if the message has been processed.
• negative – if CONFIG_INPUT_MODE_THREAD is enabled and the message failed to be enqueued.

static inline int input_report_key(const struct device *dev, uint16_t code, int32_t value, bool sync, k_timeout_t timeout)

Report a new INPUT_EV_KEY input event, note that value is converted to either 0 or 1.

See also:
input_report() for more details.

static inline int input_report_rel(const struct device *dev, uint16_t code, int32_t value, bool sync, k_timeout_t timeout)

Report a new INPUT_EV_REL input event.

See also:
input_report() for more details.

static inline int input_report_abs(const struct device *dev, uint16_t code, int32_t value, bool sync, k_timeout_t timeout)

Report a new INPUT_EV_ABS input event.

See also:
input_report() for more details.

bool input_queue_empty(void)

Returns true if the input queue is empty.

This can be used to batch input event processing until the whole queue has been emptied. Always returns true if CONFIG_INPUT_MODE_SYNCHRONOUS is enabled.
int16_t input_to_hid_code(uint16_t input_code)

Convert an input code to HID code.

Takes an input code as input and returns the corresponding HID code as output. The return value is -1 if the code is not found, if found it can safely be casted to a uint8_t type.

**Parameters**

- **input_code** – Event code (see INPUT_KEY_CODES).

**Return values**

- **the** – HID code corresponding to the input code.
- **-1** – if there's no HID code for the specified input code.

uint8_t input_to_hid_modifier(uint16_t input_code)

Convert an input code to HID modifier.

Takes an input code as input and returns the corresponding HID modifier as output or 0.

**Parameters**

- **input_code** – Event code (see INPUT_KEY_CODES).

**Return values**

- **the** – HID modifier corresponding to the input code.
- **0** – if there's no HID modifier for the specified input code.

struct input_event

`#include <input.h>` Input event structure.

This structure represents a single input event, for example a key or button press for a single button, or an absolute or relative coordinate for a single axis.

**Public Members**

const struct *device dev

Device generating the event or NULL.

uint8_t sync

Sync flag.

uint8_t type

Event type (see INPUT_EV_CODES).

uint16_t code


int32_t value

Event value.

struct input_listener

`#include <input.h>` Input listener callback structure.
Public Members

const struct device *dev
device pointer or NULL.

void (*callback)(struct input_event *evt)
The callback function.

4.9.8 Input Event Definitions

Related code samples

Input dump
Print all input events.

group input_events

Input event types.

INPUT_EV_KEY
Key event.

INPUT_EV_REL
Relative coordinate event.

INPUT_EV_ABS
Absolute coordinate event.

INPUT_EV_MSC
Miscellaneous event.

INPUT_EV_VENDOR_START
Vendor specific event start.

INPUT_EV_VENDOR_STOP
Vendor specific event stop.

Input event KEY codes.

INPUT_KEY_RESERVED
Reserved, do not use.
INPUT_KEY_0
  0 Key

INPUT_KEY_1
  1 Key

INPUT_KEY_2
  2 Key

INPUT_KEY_3
  3 Key

INPUT_KEY_4
  4 Key

INPUT_KEY_5
  5 Key

INPUT_KEY_6
  6 Key

INPUT_KEY_7
  7 Key

INPUT_KEY_8
  8 Key

INPUT_KEY_9
  9 Key

INPUT_KEY_A
  A Key.

INPUT_KEY_APOSTROPHE
  Apostrophe Key.

INPUT_KEY_B
  B Key.

INPUT_KEY_BACK
  Back Key.

INPUT_KEY_BACKSLASH
  Backslash Key.

INPUT_KEY_BACKSPACE
  Backspace Key.
INPUT_KEY_Bluetooth
Bluetooth Key.

INPUT_KEY_BrightnessDown
Brightness Up Key.

INPUT_KEY_BrightnessUp
Brightness Down Key.

INPUT_KEY_C
C Key.

INPUT_KEY_CapsLock
Caps Lock Key.

INPUT_KEY_Coffee
Screen Saver Key.

INPUT_KEY_Comma
Comma Key.

INPUT_KEY_Compose
Compose Key.

INPUT_KEY_Connect
Connect Key.

INPUT_KEY_D
D Key.

INPUT_KEY_Delete
Delete Key.

INPUT_KEY_Dot
Dot Key.

INPUT_KEY_Down
Down Key.

INPUT_KEY_E
E Key.

INPUT_KEY_End
End Key.

INPUT_KEY_Enter
Enter Key.
INPUT_KEY_EQUAL
   Equal Key.

INPUT_KEY_ESC
   Escape Key.

INPUT_KEY_F
   F Key.

INPUT_KEY_F1
   F1 Key.

INPUT_KEY_F10
   F10 Key.

INPUT_KEY_F11
   F11 Key.

INPUT_KEY_F12
   F12 Key.

INPUT_KEY_F13
   F13 Key.

INPUT_KEY_F14
   F14 Key.

INPUT_KEY_F15
   F15 Key.

INPUT_KEY_F16
   F16 Key.

INPUT_KEY_F17
   F17 Key.

INPUT_KEY_F18
   F18 Key.

INPUT_KEY_F19
   F19 Key.

INPUT_KEY_F2
   F2 Key.

INPUT_KEY_F20
   F20 Key.
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INPUT_KEY_F21
F21 Key.

INPUT_KEY_F22
F22 Key.

INPUT_KEY_F23
F23 Key.

INPUT_KEY_F24
F24 Key.

INPUT_KEY_F3
F3 Key.

INPUT_KEY_F4
F4 Key.

INPUT_KEY_F5
F5 Key.

INPUT_KEY_F6
F6 Key.

INPUT_KEY_F7
F7 Key.

INPUT_KEY_F8
F8 Key.

INPUT_KEY_F9
F9 Key.

INPUT_KEY_FASTFORWARD
Fast Forward Key.

INPUT_KEY_FORWARD
Forward Key.

INPUT_KEY_G
G Key.

INPUT_KEY_GRAVE
Grave (backtick) Key.

INPUT_KEY_H
H Key.
INPUT_KEY_HOME
  Home Key.

INPUT_KEY_I
  I Key.

INPUT_KEY_INSERT
  Insert Key.

INPUT_KEY_J
  J Key.

INPUT_KEY_K
  K Key.

INPUT_KEY_KP0
  Keypad 0 Key.

INPUT_KEY_KP1
  Keypad 1 Key.

INPUT_KEY_KP2
  Keypad 2 Key.

INPUT_KEY_KP3
  Keypad 3 Key.

INPUT_KEY_KP4
  Keypad 4 Key.

INPUT_KEY_KP5
  Keypad 5 Key.

INPUT_KEY_KP6
  Keypad 6 Key.

INPUT_KEY_KP7
  Keypad 7 Key.

INPUT_KEY_KP8
  Keypad 8 Key.

INPUT_KEY_KP9
  Keypad 9 Key.

INPUT_KEY_KPASTERISK
  Keypad Asterisk Key.
INPUT_KEY_KPCOMMA
Keypad Comma Key.

INPUT_KEY_KPDOT
Keypad Dot Key.

INPUT_KEY_KPENTER
Keypad Enter Key.

INPUT_KEY_KPEQUAL
Keypad Equal Key.

INPUT_KEY_KPMINUS
Keypad Minus Key.

INPUT_KEY_KPPLUS
Keypad Plus Key.

INPUT_KEY_KPPLUSMINUS
Keypad Plus Key.

INPUT_KEY_KPSLASH
Keypad Slash Key.

INPUT_KEY_L
L Key.

INPUT_KEY_LEFT
Left Key.

INPUT_KEY_LEFTALT
Left Alt Key.

INPUT_KEY_LEFTBRACE
Left Brace Key.

INPUT_KEY_LEFTCTRL
Left Ctrl Key.

INPUT_KEY_LEFTMETA
Left Meta Key.

INPUT_KEY_LEFTSHIFT
Left Shift Key.

INPUT_KEY_M
M Key.

4.9. Input
INPUT_KEY_MENU
Menu Key.

INPUT_KEY_MINUS
Minus Key.

INPUT_KEY_MUTE
Mute Key.

INPUT_KEY_N
N Key.

INPUT_KEY_NUMLOCK
Num Lock Key.

INPUT_KEY_O
O Key.

INPUT_KEY_P
P Key.

INPUT_KEY_PAGEDOWN
Page Down Key.

INPUT_KEY_PAGEUP
Page UpKey.

INPUT_KEY_PAUSE
Pause Key.

INPUT_KEY_PLAY
Play Key.

INPUT_KEY_POWER
Power Key.

INPUT_KEY_PRINT
Print Key.

INPUT_KEY_Q
Q Key.

INPUT_KEY_R
R Key.

INPUT_KEY_RIGHT
Right Key.
4.9. Input

INPUT_KEY_RIGHTALT
  Right Alt Key.

INPUT_KEY_RIGHTBRACE
  Right Brace Key.

INPUT_KEY_RIGHTCTRL
  Right Ctrl Key.

INPUT_KEY_RIGHTMETA
  Right Meta Key.

INPUT_KEY_RIGHTSHIFT
  Right Shift Key.

INPUT_KEY_S
  S Key.

INPUT_KEY_SCALE
  Scale Key.

INPUT_KEY_SCROLLLOCK
  Scroll Lock Key.

INPUT_KEY_SEMICOLON
  Semicolon Key.

INPUT_KEY_SLASH
  Slash Key.

INPUT_KEY_SLEEP
  System Sleep Key.

INPUT_KEY_SPACE
  Space Key.

INPUT_KEY_SYSRQ
  SysReq Key.

INPUT_KEY_T
  T Key.

INPUT_KEY_TAB
  Tab Key.

INPUT_KEY_U
  U Key.
INPUT_KEY_UP
Up Key.

INPUT_KEY_UWB
Ultra-Wideband Key.

INPUT_KEY_V
V Key.

INPUT_KEY_VOLUMEDOWN
Volume Down Key.

INPUT_KEY_VOLUMEUP
Volume Up Key.

INPUT_KEY_W
W Key.

INPUT_KEY_WAKEUP
System Wake Up Key.

INPUT_KEY_WLAN
Wireless LAN Key.

INPUT_KEY_X
X Key.

INPUT_KEY_Y
Y Key.

INPUT_KEY_Z
Z Key.

Input event BTN codes.

INPUT BTN 0
0 button

INPUT BTN 1
1 button

INPUT BTN 2
2 button

INPUT BTN 3
3 button
INPUT_BTN_4
4 button

INPUT_BTN_5
5 button

INPUT_BTN_6
6 button

INPUT_BTN_7
7 button

INPUT_BTN_8
8 button

INPUT_BTN_9
9 button

INPUT_BTN_A
A button.

INPUTBTN_B
B button.

INPUTBTN_C
C button.

INPUT_BTN_DPAD_DOWN
Directional pad Down.

INPUT BTN DPAD_LEFT
Directional pad Left.

INPUT BTN DPAD_RIGHT
Directional pad Right.

INPUT BTN DPAD_UP
Directional pad Up.

INPUT_BTN_EAST
East button.

INPUT BTN GEAR_DOWN
Gear Up button.

INPUT_BTN GEAR_UP
Gear Down button.
INPUT_BTN_LEFT
Left button.

INPUT_BTN_MIDDLE
Middle button.

INPUT_BTN_MODE
Mode button.

INPUT_BTN_NORTH
North button.

INPUT_BTN_RIGHT
Right button.

INPUT_BTN_SELECT
Select button.

INPUT_BTN_SOUTH
South button.

INPUT_BTN_START
Start button.

INPUT_BTN_THUMBL
Left thumbstick button.

INPUT_BTN_THUMBR
Right thumbstick button.

INPUT_BTN_TL
Left trigger (L1)

INPUT_BTN_TL2
Left trigger 2 (L2)

INPUT_BTN_TOUCH
Touchscreen touch.

INPUT_BTN_TR
Right trigger (R1)

INPUT_BTN_TR2
Right trigger 2 (R2)

INPUT_BTN_WEST
West button.
INPUT_BTN_X
X button.

INPUT_BTN_Y
Y button.

INPUT_BTN_Z
Z button.

Input event ABS codes.

INPUT_ABS_BRAKE
Absolute brake position.

INPUT_ABS_GAS
Absolute gas position.

INPUT_ABS_RUDDER
Absolute rudder position.

INPUT_ABS_RX
Absolute rotation around X axis.

INPUT_ABS_RY
Absolute rotation around Y axis.

INPUT_ABS_RZ
Absolute rotation around Z axis.

INPUT_ABS_THROTTLE
Absolute throttle position.

INPUT_ABS_WHEEL
Absolute wheel position.

INPUT_ABS_X
Absolute X coordinate.

INPUT_ABS_Y
Absolute Y coordinate.

INPUT_ABS_Z
Absolute Z coordinate.
Input event REL codes.

**INPUT_REL_DIAL**
Relative dial coordinate.

**INPUT_REL_HWHEEL**
Relative horizontal wheel coordinate.

**INPUT_REL_MISC**
Relative misc coordinate.

**INPUT_REL_RX**
Relative rotation around X axis.

**INPUT_REL_RY**
Relative rotation around Y axis.

**INPUT_REL_RZ**
Relative rotation around Z axis.

**INPUT_REL_WHEEL**
Relative wheel coordinate.

**INPUT_REL_X**
Relative X coordinate.

**INPUT_REL_Y**
Relative Y coordinate.

**INPUT_REL_Z**
Relative Z coordinate.

Input event MSC codes.

**INPUT_MSC_SCAN**
Scan code.

### 4.9.9 Analog Axis API Reference

*group input_analog_axis*

Analog axis API.
Typedefs

typedef void (*analog_axis_raw_data_t)(const struct device *dev, int channel, int16_t raw_val)
Analog axis raw data callback.

Param dev
Analog axis device.

Param channel
Channel number.

Param raw_val
Raw value for the channel.

Functions

void analog_axis_set_raw_data_cb(const struct device *dev, analog_axis_raw_data_t cb)
Set a raw data callback.
Set a callback to receive raw data for the specified analog axis device. This is meant to
be use in the application to acquire the data to use for calibration. Set cb to NULL to
disable the callback.

Parameters

• dev – Analog axis device.
• cb – An analog_axis_raw_data_t callback to use, NULL disable.

int analog_axis_num_axes(const struct device *dev)
Get the number of defined axes.

Return values

n – The number of defined axes for dev.

int analog_axis_calibration_get(const struct device *dev, int channel, struct analog_axis_calibration *cal)
Get the axis calibration data.

Parameters

• dev – Analog axis device.
• channel – Channel number.
• cal – Pointer to an analog_axis_calibration structure that is going to get
set with the current calibration data.

Return values

• 0 – If successful.
• -EINVAL – If the specified channel is not valid.

int analog_axis_calibration_set(const struct device *dev, int channel, struct analog_axis_calibration *cal)
Set the axis calibration data.

Parameters

• dev – Analog axis device.
• channel – Channel number.
• cal – Pointer to an `analog_axis_calibration` structure with the new calibration data

**Return values**

• 0 – If successful.
• -EINVAL – If the specified channel is not valid.

```c
int analog_axis_calibration_save(const struct device *dev)
```

Save the calibration data.

Save the calibration data permanently on the specified device, requires the the Settings subsystem to be configured and initialized.

**Parameters**

• dev – Analog axis device.

**Return values**

• 0 – If successful.
• -errno – In case of any other error.

```c
struct analog_axis_calibration
```

`#include <input_analog_axis.h>` Analog axis calibration data structure.

Holds the calibration data for a single analog axis. Initial values are set from the devicetree and can be changed by the application in runtime using `analog_axis_calibration_set` and `analog_axis_calibration_get`.

**Public Members**

```c
int16_t in_min
```

Input value that corresponds to the minimum output value.

```c
int16_t in_max
```

Input value that corresponds to the maximum output value.

```c
uint16_t out_deadzone
```

Output value deadzone relative to the output range.

## 4.10 Interprocessor Communication (IPC)

### 4.10.1 IPC service

- **Overview**
- **Simple data exchange**
- **Data exchange using the no-copy API**
  - Backends
  - API Reference
- **IPC service API**
The IPC service API provides an interface to exchange data between two domains or CPUs.

**Overview**

An IPC service communication channel consists of one instance and one or several endpoints associated with the instance.

An instance is the external representation of a physical communication channel between two domains or CPUs. The actual implementation and internal representation of the instance is peculiar to each backend.

An individual instance is not used to send data between domains/CPUs. To send and receive the data, the user must create (register) an endpoint in the instance. This allows for the connection of the two domains of interest.

It is possible to have zero or multiple endpoints for one single instance, possibly with different priorities, and to use each to exchange data. Endpoint prioritization and multi-instance ability highly depend on the backend used.

The endpoint is an entity the user must use to send and receive data between two domains (connected by the instance). An endpoint is always associated to an instance.

The creation of the instances is left to the backend, usually at init time. The registration of the endpoints is left to the user, usually at run time.

The API does not mandate a way for the backend to create instances but it is strongly recommended to use the devicetree to retrieve the configuration parameters for an instance. Currently, each backend defines its own DT-compatible configuration that is used to configure the interface at boot time.

The following usage scenarios are supported:

- Simple data exchange.
- Data exchange using the no-copy API.

**Simple data exchange**

To send data between domains or CPUs, an endpoint must be registered onto an instance.

See the following example:

**Note:** Before registering an endpoint, the instance must be opened using the `ipc_service_open_instance()` function.

```c
#include <zephyr/ipc/ipc_service.h>

static void bound_cb(void *priv) {
    /* Endpoint bounded */
}

static void recv_cb(const void *data, size_t len, void *priv) {
    /* Data received */
}
```

(continues on next page)
Data exchange using the no-copy API

If the backend supports the no-copy API you can use it to directly write and read to and from shared memory regions.

See the following example:

```c
#include <zephyr/ipc/ipc_service.h>
#include <stdio.h>
#include <string.h>

static struct ipc_ept ept0;

static void bound_cb(void *priv)
{
    /* Endpoint bounded */
}

static void recv_cb_nocopy(const void *data, size_t len, void *priv)
{
    int ret;

    ret = ipc_service_hold_rx_buffer(&ept0, (void *)data);
    /* Process directly or put the buffer somewhere else and release. */
    ret = ipc_service_release_rx_buffer(&ept0, (void *)data);
}

static struct ipc_ept_cfg ept0_cfg = {
    .name = "ept0",
    .cb = {
        .bound = bound_cb,
        .received = recv_cb,
    },
};
```

(continues on next page)
```c
int main(void)
{
    const struct device *inst0;
    int ret;

    inst0 = DEVICE_DT_GET(DT_NODELABEL(ipc0));
    ret = ipc_service_open_instance(inst0);
    ret = ipc_service_register_endpoint(inst0, &ept0, &ept0_cfg);

    /* Wait for endpoint bound (bound_cb called) */
    void *data;
    unsigned char message[] = "hello world";
    uint32_t len = sizeof(message);

    ret = ipc_service_get_tx_buffer(&ept0, &data, &len, K_FOREVER);
    memcpy(data, message, len);
    ret = ipc_service_send_nocopy(&ept0, data, sizeof(message));
}
```

**Backends**  The requirements needed for implementing backends give flexibility to the IPC service. These allow for the addition of dedicated backends having only a subsets of features for specific use cases.

The backend must support at least the following:
- The init-time creation of instances.
- The run-time registration of an endpoint in an instance.

Additionally, the backend can also support the following:
- The run-time deregistration of an endpoint from the instance.
- The run-time closing of an instance.
- The no-copy API.

Each backend can have its own limitations and features that make the backend unique and dedicated to a specific use case. The IPC service API can be used with multiple backends simultaneously, combining the pros and cons of each backend.

**ICMsg backend**  The inter core messaging backend (ICMsg) is a lighter alternative to the heavier RPMsg static vrings backend. It offers a minimal feature set in a small memory footprint. The ICMsg backend is build on top of *Single Producer Single Consumer Packet Buffer*.

**Overview**  The ICMsg backend uses shared memory and MBOX devices for exchanging data. Shared memory is used to store the data, MBOX devices are used to signal that the data has been written.

The backend supports the registration of a single endpoint on a single instance. If the application requires more than one communication channel, you must define multiple instances, each having its own dedicated endpoint.

**Configuration**  The backend is configured via Kconfig and devicetree. When configuring the backend, do the following:
• Define two memory regions and assign them to \texttt{tx-region} and \texttt{rx-region} of an instance. Ensure that the memory regions used for data exchange are unique (not overlapping any other region) and accessible by both domains (or CPUs).

• Define MBOX devices which are used to send the signal that informs the other domain (or CPU) that data has been written. Ensure that the other domain (or CPU) is able to receive the signal.

See the following configuration example for one of the instances:

```c
reserved-memory {
    tx: memory@20070000 {
        reg = @0x20070000 0x0800;  
    },
    rx: memory@20078000 {
        reg = @0x20078000 0x0800;  
    },
    ipc {
        ipc0: ipc0 {
            compatible = "zephyr,ipc-icmsg";
            tx-region = @tx;     
            rx-region = @rx;     
            mboxes = @mbox0, @mbox1;
            mbox-names = "tx", "rx";
            status = "okay";
        }
    },
};
```

You must provide a similar configuration for the other side of the communication (domain or CPU) but you must swap the MBOX channels and memory regions (\texttt{tx-region} and \texttt{rx-region}).

**Bonding**  When the endpoint is registered, the following happens on each domain (or CPU) connected through the IPC instance:

1. The domain (or CPU) writes a magic number to its \texttt{tx-region} of the shared memory. It then sends a signal to the other domain or CPU, informing that the data has been written. Sending the signal to the other domain or CPU is repeated with timeout specified by \texttt{CONFIG_IPC_SERVICE_ICMSG_BOND_NOTIFY_REPEAT_TO_MS} option. When the signal from the other domain or CPU is received, the magic number is read from \texttt{rx-region}. If it is correct, the bonding process is finished and the backend informs the application by calling \texttt{ipc_service_cb.bound} callback.

**Samples**

• ipc-icmsg

**ICMsg with dynamically allocated buffers backend**  This backend is built on top of the \texttt{ICMsg backend}. Data transferred over this backend travels in dynamically allocated buffers on shared memory. The ICMsg just sends references to the buffers. It also supports multiple endpoints.

This architecture allows for overcoming some common problems with other backends (mostly related to multithread access and zero-copy). This backend provides an alternative with no significant limitations.
Overview  The shared memory is divided into two parts. One is reserved for the ICMmsg and the other contains equal-sized blocks. The number of blocks is configured in the devicetree.

The data sending process is following:

- The sender allocates one or more blocks. If there are not enough sequential blocks, it waits using the timeout provided in the parameter that also includes K_FOREVER and K_NO_WAIT.
- The allocated blocks are filled with data. For the zero-copy case, this is done by the caller, otherwise, it is copied automatically. During this time other threads are not blocked in any way as long as there are enough free blocks for them. They can allocate, send data and receive data.
- A message containing the block index is sent over ICMmsg to the receiver. The size of the ICMmsg queue is large enough to hold messages for all blocks, so it will never overflow.
- The receiver can hold the data as long as desired. Again, other threads are not blocked as long as there are enough free blocks for them.
- When data is no longer needed, the backend sends a release message over ICMmsg.
- When the backend receives this message, it deallocates all blocks. It is done internally by the backend and it is invisible to the caller.

Configuration  The backend is configured using Kconfig and devicetree. When configuring the backend, do the following:

- Define two memory regions and assign them to tx-region and rx-region of an instance. Ensure that the memory regions used for data exchange are unique (not overlapping any other region) and accessible by both domains (or CPUs).
- Define the number of allocable blocks for each region with tx-blocks and rx-blocks.
- Define MBOX devices for sending a signal that informs the other domain (or CPU) of the written data. Ensure that the other domain (or CPU) can receive the signal.

See the following configuration example for one of the instances:

```c
reserved-memory {
  tx: memory@20070000 {
    reg = <0x20070000 0x0800>;
  };
  rx: memory@20078000 {
    reg = <0x20078000 0x0800>;
  };
}
ipc {
  ipc0: ipc0 {
    compatible = "zephyr,ipc-icbmsg";
    tx-region = <&tx>;
    rx-region = <&rx>;
    tx-blocks = <16>;
    rx-blocks = <32>;
    mboxes = <&mbox 0>, <&mbox 1>;
    mbox-names = "tx", "rx";
    status = "okay";
  };
}
```

You must provide a similar configuration for the other side of the communication (domain or CPU). Swap the MBOX channels, memory regions (tx-region and rx-region), and block count (tx-blocks and rx-blocks).
Samples

- ipc_multi_endpoint_sample

API Reference

IPC service API

`group ipc_service_api`
IPC Service API.

Functions

`int ipc_service_open_instance(const struct device *instance)`

Open an instance.
Function to be used to open an instance before being able to register a new endpoint on it.

**Parameters**

- instance – [in] Instance to open.

**Return values**

- `-EINVAL` – when instance configuration is invalid.
- `-EIO` – when no backend is registered.
- `-EALREADY` – when the instance is already opened (or being opened).
- `0` – on success or when not implemented on the backend (not needed).
- `other` – errno codes depending on the implementation of the backend.

`int ipc_service_close_instance(const struct device *instance)`

Close an instance.
Function to be used to close an instance. All bounded endpoints must be deregistered using `ipc_service_deregister_endpoint` before this is called.

**Parameters**

- instance – [in] Instance to close.

**Return values**

- `-EINVAL` – when instance configuration is invalid.
- `-EIO` – when no backend is registered.
- `-EALREADY` – when the instance is already opened.
- `-EBUSY` – when an endpoint exists that hasn’t been deregistered
- `0` – on success or when not implemented on the backend (not needed).
- `other` – errno codes depending on the implementation of the backend.
int ipc_service_register_endpoint(const struct device *instance, struct ipc_ept *ept, const struct ipc_ept_cfg *cfg)

Register IPC endpoint onto an instance.

Registers IPC endpoint onto an instance to enable communication with a remote device.

The same function registers endpoints for both host and remote devices.

**Note:** Keep the variable pointed by cfg alive when endpoint is in use.

**Parameters**
- **instance** – [in] Instance to register the endpoint onto.
- **ept** – [in] Endpoint object.
- **cfg** – [in] Endpoint configuration.

**Return values**
- `-EIO` – when no backend is registered.
- `-EINVAL` – when instance, endpoint or configuration is invalid.
- `-EBUSY` – when the instance is busy.
- `0` – on success.
- `other` – errno codes depending on the implementation of the backend.

int ipc_service_deregister_endpoint(struct ipc_ept *ept)

Deregister an IPC endpoint from its instance.

Deregisters an IPC endpoint from its instance.

The same function deregisters endpoints for both host and remote devices.

**Parameters**
- **ept** – [in] Endpoint object.

**Return values**
- `-EIO` – when no backend is registered.
- `-EINVAL` – when instance, endpoint or configuration is invalid.
- `-ENOENT` – when the endpoint is not registered with the instance.
- `-EBUSY` – when the instance is busy.
- `0` – on success.
- `other` – errno codes depending on the implementation of the backend.

int ipc_service_send(struct ipc_ept *ept, const void *data, size_t len)

Send data using given IPC endpoint.

**Parameters**
- **ept** – [in] Registered endpoint by `ipc_service_register_endpoint`.
- **data** – [in] Pointer to the buffer to send.
- **len** – [in] Number of bytes to send.

**Return values**
• -EIO – when no backend is registered or send hook is missing from backend.
• -EINVAL – when instance or endpoint is invalid.
• -ENOENT – when the endpoint is not registered with the instance.
• -EBADMSG – when the data is invalid (i.e. invalid data format, invalid length, ...)
• -EBUSY – when the instance is busy.
• -ENOMEM – when no memory / buffers are available.
• bytes – number of bytes sent.
• other – errno codes depending on the implementation of the backend.

int ipc_service_get_tx_buffer_size(struct ipc_ept *ept)
Get the TX buffer size.
Get the maximal size of a buffer which can be obtained by *ipc_service_get_tx_buffer*

Parameters
• ept – [in] Registered endpoint by *ipc_service_register_endpoint*.

Return values
• -EIO – when no backend is registered or send hook is missing from backend.
• -EINVAL – when instance or endpoint is invalid.
• -ENOENT – when the endpoint is not registered with the instance.
• -ENOTSUP – when the operation is not supported by backend.
• size – TX buffer size on success.
• other – errno codes depending on the implementation of the backend.

int ipc_service_get_tx_buffer(struct ipc_ept *ept, void **data, uint32_t *size, k_timeout_t wait)
Get an empty TX buffer to be sent using *ipc_service_send_nocopy*.

This function can be called to get an empty TX buffer so that the application can directly put its data into the sending buffer without copy from an application buffer.

It is the application responsibility to correctly fill the allocated TX buffer with data and passing correct parameters to *ipc_service_send_nocopy* function to perform data no-copy-send mechanism.

The size parameter can be used to request a buffer with a certain size:
• if the size can be accommodated the function returns no errors and the buffer is allocated
• if the requested size is too big, the function returns -ENOMEM and the the buffer is not allocated.
• if the requested size is '0' the buffer is allocated with the maximum allowed size.

In all the cases on return the size parameter contains the maximum size for the returned buffer.

When the function returns no errors, the buffer is intended as allocated and it is released under two conditions: (1) when sending the buffer using *ipc_service_send_nocopy* (and in this case the buffer is automatically released by the backend), (2) when using *ipc_service_drop_tx_buffer* on a buffer not sent.

Parameters
• **ept** – [in] Registered endpoint by `ipc_service_register_endpoint`.
• **data** – [out] Pointer to the empty TX buffer.
• **size** – [inout] Pointer to store the requested TX buffer size. If the function returns -ENOMEM, this parameter returns the maximum allowed size.
• **wait** – [in] Timeout waiting for an available TX buffer.

**Return values**
- -EIO – when no backend is registered or send hook is missing from backend.
- -EINVAL – when instance or endpoint is invalid.
- -ENOENT – when the endpoint is not registered with the instance.
- -ENOTSUP – when the operation or the timeout is not supported by backend.
- -ENOBUFFS – when there are no TX buffers available.
- -EALREADY – when a buffer was already claimed and not yet released.
- -ENOMEM – when the requested size is too big (and the size parameter contains the maximum allowed size).
- 0 – on success.
- other – errno codes depending on the implementation of the backend.

```c
int ipc_service_drop_tx_buffer(struct ipc_ept *ept, const void *data)
```

Drop and release a TX buffer. It is possible to drop only TX buffers obtained by using `ipc_service_get_tx_buffer`.

**Parameters**
- **ept** – [in] Registered endpoint by `ipc_service_register_endpoint`.
- **data** – [in] Pointer to the TX buffer.

**Return values**
- -EIO – when no backend is registered or send hook is missing from backend.
- -EINVAL – when instance or endpoint is invalid.
- -ENOENT – when the endpoint is not registered with the instance.
- -ENOTSUP – when this is not supported by backend.
- -EALREADY – when the buffer was already dropped.
- -ENXIO – when the buffer was not obtained using `ipc_service_get_tx_buffer`
- 0 – on success.
- other – errno codes depending on the implementation of the backend.

```c
int ipc_service_send_nocopy(struct ipc_ept *ept, const void *data, size_t len)
```

Send data in a TX buffer reserved by `ipc_service_get_tx_buffer` using the given IPC endpoint.

This is equivalent to `ipc_service_send` but in this case the TX buffer has been obtained by using `ipc_service_get_tx_buffer`.

4.10. Interprocessor Communication (IPC)
The application has to take the responsibility for getting the TX buffer using `ipc_service_get_tx_buffer` and filling the TX buffer with the data.

After the `ipc_service_send_nocopy` function is issued the TX buffer is no more owned by the sending task and must not be touched anymore unless the function fails and returns an error.

If this function returns an error, `ipc_service_drop_tx_buffer` can be used to drop the TX buffer.

**Parameters**
- `data` – `[in]` Pointer to the buffer to send obtained by `ipc_service_get_tx_buffer`.
- `len` – `[in]` Number of bytes to send.

**Return values**
- `-EIO` – when no backend is registered or send hook is missing from backend.
- `-EINVAL` – when instance or endpoint is invalid.
- `-ENOENT` – when the endpoint is not registered with the instance.
- `-EBADMSG` – when the data is invalid (i.e. invalid data format, invalid length, ...)
- `-EBUSY` – when the instance is busy.
- `bytes` – number of bytes sent.
- `other` – errno codes depending on the implementation of the backend.

```c
int ipc_service_hold_rx_buffer(struct ipc_ept *ept, void *data)
```

Holds the RX buffer for usage outside the receive callback.

Calling this function prevents the receive buffer from being released back to the pool of shmem buffers. This function can be called in the receive callback when the user does not want to copy the message out in the callback itself.

After the message is processed, the application must release the buffer using the `ipc_service_release_rx_buffer` function.

**Parameters**
- `data` – `[in]` Pointer to the RX buffer to hold.

**Return values**
- `-EIO` – when no backend is registered or release hook is missing from backend.
- `-EINVAL` – when instance or endpoint is invalid.
- `-ENOENT` – when the endpoint is not registered with the instance.
- `-EALREADY` – when the buffer data has been hold already.
- `-ENOTSUP` – when this is not supported by backend.
- `0` – on success.
- `other` – errno codes depending on the implementation of the backend.
int ipc_service_release_rx_buffer(struct ipc_ept *ept, void *data)
    Release the RX buffer for future reuse.

    When supported by the backend, this function can be called after the received message has been processed and the buffer can be marked as reusable again.

    It is possible to release only RX buffers on which ipc_service_hold_rx_buffer was previously used.

    Parameters
    • ept – [in] Registered endpoint by ipc_service_register_endpoint.
    • data – [in] Pointer to the RX buffer to release.

    Return values
    • -EIO – when no backend is registered or release hook is missing from backend.
    • -EINVAL – when instance or endpoint is invalid.
    • -ENOENT – when the endpoint is not registered with the instance.
    • -EALREADY – when the buffer data has been already released.
    • -ENOTSUP – when this is not supported by backend.
    • -ENXIO – when the buffer was not hold before using ipc_service_hold_rx_buffer
    • 0 – on success.
    • other – errno codes depending on the implementation of the backend.

struct ipc_service_cb
    #include <ipc_service.h> Event callback structure.

    It is registered during endpoint registration. This structure is part of the endpoint configuration.

Public Members

void (*bound)(void *priv)
    Bind was successful.
    This callback is called when the endpoint binding is successful.
    Param priv
    [in] Private user data.

void (*received)(const void *data, size_t len, void *priv)
    New packet arrived.
    This callback is called when new data is received.

    Note: When ipc_service_hold_rx_buffer is not used, the data buffer is to be considered released and available again only when this callback returns.

    Param data
    [in] Pointer to data buffer.
    Param len
    [in] Length of data.
Param priv
   [in] Private user data.

void (*error)(const char *message, void *priv)
   An error occurred.
   Param message
   Param priv
   [in] Private user data.

struct ipc_ept
   #include <ipc_service.h> Endpoint instance.
   Token is not important for user of the API. It is implemented in a specific backend.

Public Members

const struct device *instance
   Instance this endpoint belongs to.

void *token
   Backend-specific token used to identify an endpoint in an instance.

struct ipc_ept_cfg
   #include <ipc_service.h> Endpoint configuration structure.

Public Members

const char *name
   Name of the endpoint.

int prio
   Endpoint priority.
   If the backend supports priorities.

struct ipc_service_cb cb
   Event callback structure.

void *priv
   Private user data.

IPC service backend API

group ipc_service_backend
   IPC service backend.
struct ipc_service_backend

#include <ipc_service_backend.h> IPC backend configuration structure.
This structure is used for configuration backend during registration.

Public Members

int (*open_instance)(const struct device *instance)
Pointer to the function that will be used to open an instance.
    Param instance [in] Instance pointer.
    Retval -EALREADY when the instance is already opened.
    Retval 0 on success
    Retval other errno codes depending on the implementation of the backend.

int (*close_instance)(const struct device *instance)
Pointer to the function that will be used to close an instance.
    Param instance [in] Instance pointer.
    Retval -EALREADY when the instance is not already inited.
    Retval 0 on success
    Retval other errno codes depending on the implementation of the backend.

int (*send)(const struct device *instance, void *token, const void *data, size_t len)
Pointer to the function that will be used to send data to the endpoint.
    Param instance [in] Instance pointer.
    Param data [in] Pointer to the buffer to send.
    Param len [in] Number of bytes to send.
    Retval -EINVAL when instance is invalid.
    Retval -ENOENT when the endpoint is not registered with the instance.
    Retval -EBADEMSG when the message is invalid.
    Retval -EBUSY when the instance is busy or not ready.
    Retval -ENOMEM when no memory / buffers are available.
    Retval bytes number of bytes sent.
    Retval other errno codes depending on the implementation of the backend.
int (*register_endpoint)(const struct device *instance, void **token, const struct ipc_ept_cfg *cfg)

Pointer to the function that will be used to register endpoints.

Param instance
    [in] Instance to register the endpoint onto.

Param token
    [out] Backend-specific token.

Param cfg
    [in] Endpoint configuration.

Retval -EINVAL
    when the endpoint configuration or instance is invalid.

Retval -EBUSY
    when the instance is busy or not ready.

Retval 0
    on success

Retval other
    errno codes depending on the implementation of the backend.

int (*deregister_endpoint)(const struct device *instance, void *token)

Pointer to the function that will be used to deregister endpoints.

Param instance
    [in] Instance from which to deregister the endpoint.

Param token

Retval -EINVAL
    when the endpoint configuration or instance is invalid.

Retval -ENOENT
    when the endpoint is not registered with the instance.

Retval -EBUSY
    when the instance is busy or not ready.

Retval 0
    on success

Retval other
    errno codes depending on the implementation of the backend.

int (*get_tx_buffer_size)(const struct device *instance, void *token)

Pointer to the function that will return the TX buffer size.

Param instance
    [in] Instance pointer.

Param token

Retval -EINVAL
    when instance is invalid.

Retval -ENOENT
    when the endpoint is not registered with the instance.

Retval -ENOTSUP
    when the operation is not supported.

Retval size
    TX buffer size on success.

Retval other
    errno codes depending on the implementation of the backend.

int (*get_tx_buffer)(const struct device *instance, void *token, void **data, uint32_t *len, k_timeout_t wait)

Pointer to the function that will return an empty TX buffer.
Param instance
  [in] Instance pointer.
Param token
Param data
  [out] Pointer to the empty TX buffer.
Param len
  [inout] Pointer to store the TX buffer size.
Param wait
  [in] Timeout waiting for an available TX buffer.
Retval -EINVAL
  when instance is invalid.
Retval -ENOENT
  when the endpoint is not registered with the instance.
Retval -ENOTSUP
  when the operation or the timeout is not supported.
Retval -ENOBUFFS
  when there are no TX buffers available.
Retval -EALREADY
  when a buffer was already claimed and not yet released.
Retval -ENOMEM
  when the requested size is too big (and the size parameter contains the
  maximum allowed size).
Retval 0
  on success
Retval other
  errno codes depending on the implementation of the backend.

int (*drop_tx_buffer)(const struct device *instance, void *token, const void *data)
  Pointer to the function that will drop a TX buffer.
  Param instance
    [in] Instance pointer.
  Param token
  Param data
    [in] Pointer to the TX buffer.
  Retval -EINVAL
    when instance is invalid.
  Retval -ENOENT
    when the endpoint is not registered with the instance.
  Retval -ENOTSUP
    when this function is not supported.
  Retval -EALREADY
    when the buffer was already dropped.
  Retval 0
    on success
  Retval other
    errno codes depending on the implementation of the backend.

int (*send_nocopy)(const struct device *instance, void *token, const void *data, size_t len)
  Pointer to the function that will be used to send data to the endpoint when the TX
  buffer has been obtained using ipc_service_get_tx_buffer.
  Param instance
    [in] Instance pointer.
  Param token
Param data
[in] Pointer to the buffer to send.

Param len
[in] Number of bytes to send.

Retval -EINVAL
when instance is invalid.

Retval -ENOENT
when the endpoint is not registered with the instance.

Retval -EBADMSG
when the data is invalid (i.e. invalid data format, invalid length, ...)

Retval -EBUSY
when the instance is busy or not ready.

Retval bytes
number of bytes sent.

Retval other
errno codes depending on the implementation of the backend.

int (*hold_rx_buffer)(const struct device *instance, void *token, void *data)
Pointer to the function that will hold the RX buffer.

Param instance
[in] Instance pointer.

Param token

Param data
[in] Pointer to the RX buffer to hold.

Retval -EINVAL
when instance is invalid.

Retval -ENOENT
when the endpoint is not registered with the instance.

Retval -EALREADY
when the buffer data has been already hold.

Retval -ENOTSUP
when this function is not supported.

Retval 0
on success

Retval other
errno codes depending on the implementation of the backend.

int (*release_rx_buffer)(const struct device *instance, void *token, void *data)
Pointer to the function that will release the RX buffer.

Param instance
[in] Instance pointer.

Param token

Param data
[in] Pointer to the RX buffer to release.

Retval -EINVAL
when instance is invalid.

Retval -ENOENT
when the endpoint is not registered with the instance.

Retval -EALREADY
when the buffer data has been already released.

Retval -ENOTSUP
when this function is not supported.

Retval 0
on success

Retval other
4.11 Linkable Loadable Extensions (LLEXT)

The llext subsystem provides a toolbox for extending the functionality of an application at run-time with linkable loadable code.

Extensions can be loaded from precompiled ELF formatted data which is verified, loaded, and linked with other extensions. Extensions can be manipulated and introspected to some degree, as well as unloaded when no longer needed.

An extension may be loaded using any implementation of a llext_loader which has a set of function pointers that provide the necessary functionality to read the ELF data. A loader also provides some minimal context (memory) needed by the llext_load() function. An implementation over a buffer containing an ELF in addressable memory in memory is available as llext_buf_loader.

4.11.1 API Reference

Related code samples

Linkable loadable extensions shell module
Manage loadable extensions using shell commands.

```sh

group llext
   Linkable loadable extensions.

Defines

LLEXT_MEM_PARTITIONS

LLEXT_LOAD_PARAM_DEFAULT

 Enums

enum llext_mem
   List of ELF regions that are stored or referenced in the llext.
   Values:

   enumerator LLEXT_MEM_TEXT
   enumerator LLEXT_MEM_DATA
   enumerator LLEXT_MEM_RODATA
   enumerator LLEXT_MEM_BSS
```
enumerator LLEXT_MEM_EXPORT
enumerator LLEXT_MEM_SYMTAB
enumerator LLEXT_MEM_STRTAB
enumerator LLEXT_MEM_SHSTRTAB
enumerator LLEXT_MEM_COUNT

Functions

struct *llext_by_name(const char *name)
Find an llext by name.

Parameters
- name – [in] String name of the llext

Return values
- NULL – if no llext not found
- llext – if llext found

int llext_iterate(int (*fn)(struct llext *ext, void *arg), void *arg)
Iterate overall registered llext instances.
Calls a provided callback function for each registered extension or until the callback
function returns a non-0 value.

Parameters
- fn – [in] callback function
- arg – [in] a private argument to be provided to the callback function

Return values
- 0 – if no extensions are registered
- value – returned by the most recent callback invocation

int llext_load(struct llext_loader *loader, const char *name, struct llext **ext, struct llext_load_param *ldr_parm)
Load and link an extension.
Loads relevant ELF data into memory and provides a structure to work with it.
Only relocatable ELF files are currently supported (partially linked).

Parameters
- loader – [in] An extension loader that provides input data and context
- name – [in] A string identifier for the extension
- ext – [out] This will hold the pointer to the llext struct
- ldr_parm – [in] Loader parameters

Return values
- 0 – Success
-ENOMEM – Not enough memory
-EINVAL – Invalid ELF stream

int llext_unload(struct llext **ext)
Unload an extension.

Parameters
- ext – [in] Extension to unload

const void *const llext_find_sym(const struct llext_symtable *sym_table, const char *sym_name)
Find the address for an arbitrary symbol name.

Parameters
- sym_table – [in] Symbol table to lookup symbol in, if NULL uses base table
- sym_name – [in] Symbol name to find

Return values
- NULL – if no symbol found
- addr – Address of symbol in memory if found

int llext_call_fn(struct llext *ext, const char *sym_name)
Call a function by name.

Expects a symbol representing a void fn(void) style function exists and may be called.

Parameters
- ext – [in] Extension to call function in
- sym_name – [in] Function name (exported symbol) in the extension

Return values
- 0 – success
- -EINVAL – invalid symbol name

int llext_add_domain(struct llext *ext, struct k_mem_domain *domain)
Add the known memory partitions of the extension to a memory domain.

Allows an extension to be executed in supervisor or user mode threads when memory protection hardware is enabled.

Parameters
- ext – [in] Extension to add to a domain
- domain – [in] Memory domain to add partitions to

Return values
- 0 – success
- -errno – error

void arch_elf_relocate(elf_rela_t *rel, uintptr_t opaddr, uintptr_t opval)
Architecture specific function for updating op codes given a relocation.

Elf files contain a series of relocations described in a section. These relocation instructions are architecture specific and each architecture supporting extensions must implement this. They are instructions on how to rewrite opcodes given the actual placement of some symbolic data such as a section, function, or object.

Parameters
• **rel** – [in] Relocation data provided by elf
• **opaddr** – [in] Address of operation to rewrite with relocation
• **opval** – [in] Value of looked up symbol to relocate

```c
ssize_t llext_find_section(struct llext_loader *loader, const char *search_name)
```
Find an ELF section.

**Parameters**
- **loader** – Extension loader data and context
- **search_name** – Section name to search for

**Return values**
- Section – offset or a negative error code

```c
void arch_elf_relocate_local(struct llext_loader *loader, struct llext *ext, elf_rela_t *rel, size_t got_offset)
```
Architecture specific function for updating addresses via relocation table.

**Parameters**
- **loader** – [in] Extension loader data and context
- **ext** – [in] Extension to call function in
- **rel** – [in] Relocation data provided by elf
- **got_offset** – [in] Offset within a relocation table

```c
struct llext
```
#include <llext.h> Linkable loadable extension.

**Public Members**

char name[16]
Name of the llext.

void *mem[LLEXT_MEM_COUNT]
Lookup table of llext memory regions.

bool mem_on_heap[LLEXT_MEM_COUNT]
Is the memory for this section allocated on heap?

size_t mem_size[LLEXT_MEM_COUNT]
Size of each stored section.

size_t alloc_size
Total llext allocation size.

struct llext_symtable exp_tab
Exported symbols from the llext, may be linked against by other llext.

unsigned int use_count
Extension use counter, prevents unloading while in use.
struct llext_load_param

#include <llext.h> llext loader parameters

These are parameters, not saved in the permanent llext context, needed only for the loader

Public Members

bool relocate_local

Should local relocation be performed.

group llext_symbols

Linkable loadable extension symbol.

Defines

EXPORT_SYMBOL(x)

Export a constant symbol to a table of symbols.
Takes a symbol (function or object) by symbolic name and adds the name and address of the symbol to a table of symbols that may be used for linking.

Parameters
• x – Symbol to export

LL_EXTENSION_SYMBOL(x)

EXPORT_SYSCALL(x)

Export a system call to a table of symbols.
Takes a system call name and uses EXPORT_SYMBOL() to export the respective function.

Parameters
• x – System call to export

struct llext_const_symbol

#include <symbol.h> Constant symbols are unchangeable named memory addresses.
Symbols may be named function or global objects that have been exported for linking. These constant symbols are useful in the base image as they may be placed in ROM.

Public Members

const char *const name

Name of symbol.

const void *const addr

Address of symbol.
struct l1ext_symbol
    
    #include <symbol.h> Symbols are named memory addresses.

    Symbols may be named function or global objects that have been exported for linking.
    These are mutable and should come from extensions where the location may need
    updating depending on where memory is placed.

**Public Members**

    const char *name
        Name of symbol.

    void *addr
        Address of symbol.

struct l1ext_symtable
    
    #include <symbol.h> A symbol table.

    An array of symbols

**Public Members**

    size_t sym_cnt
        Number of symbols in the table.

    struct l1ext_symbol *syms
        Array of symbols.

**group l1ext_loader**

    Loader context for l1ext.

**Functions**

    static inline int l1ext_read(struct l1ext_loader *l, void *buf, size_t len)
    static inline int l1ext_seek(struct l1ext_loader *l, size_t pos)
    static inline void *l1ext_peek(struct l1ext_loader *l, size_t pos)

**struct l1ext_loader**

    #include <loader.h> Linkable loadable extension loader context.

**Public Members**

    int (*read)(struct l1ext_loader *ldr, void *out, size_t len)
        Read (copy) from the loader.
        Copies len bytes into buf from the current position of the loader.
**Param ldr**
[in] Loader

**Param out**
[in] Output location

**Param len**
[in] Length to copy into the output location

**Retval 0**
Success

**Retval -errno**
Error reading (any errno)

```c
int (*seek)(struct llext_loader *ldr, size_t pos)
```
Seek to a new absolute location.

Changes the location of the loader position to a new absolute given position.

**Param ldr**
[in] Loader

**Param pos**
[in] Position in stream to move loader

**Retval 0**
Success

**Retval -errno**
Error reading (any errno)

```c
void *(*peek)(struct llext_loader *ldr, size_t pos)
```
Peek at an absolute location.

Return a pointer to the buffer at specified offset.

**Param ldr**
[in] Loader

**Param pos**
[in] Position to obtain a pointer to

**Retval pointer**
into the buffer

---

**Define**

```c
LLEXT_BUF_LOADER(_buf, _buf_len)
```
Initialize an extension buf loader.

**Parameters**

- `_buf` – Buffer containing an ELF binary
- `_buf_len` – Buffer length in bytes

---

**Public Members**

```c
struct llext_loader
```

An extension loader from a provided buffer containing an ELF.

---

4.11. Linkable Loadable Extensions (LLEXT)
The logging API provides a common interface to process messages issued by developers. Messages are passed through a frontend and are then processed by active backends. Custom frontend and backends can be used if needed.

Summary of the logging features:

- Deferred logging reduces the time needed to log a message by shifting time consuming operations to a known context instead of processing and sending the log message when called.
- Multiple backends supported (up to 9 backends).
- Custom frontend support. It can work together with backends.
- Compile time filtering on module level.
- Run time filtering independent for each backend.
- Additional run time filtering on module instance level.
- Timestamping with user provided function. Timestamp can have 32 or 64 bits.
- Dedicated API for dumping data.
• Dedicated API for handling transient strings.
• Panic support - in panic mode logging switches to blocking, synchronous processing.
• Printk support - printk message can be redirected to the logging.
• Design ready for multi-domain/multi-processor system.
• Support for logging floating point variables and long long arguments.
• Built-in copying of transient strings used as arguments.
• Support for multi-domain logging.

Logging API is highly configurable at compile time as well as at run time. Using Kconfig options (see Global Kconfig Options) logs can be gradually removed from compilation to reduce image size and execution time when logs are not needed. During compilation logs can be filtered out on module basis and severity level.

Logs can also be compiled in but filtered on run time using dedicate API. Run time filtering is independent for each backend and each source of log messages. Source of log messages can be a module or specific instance of the module.

There are four severity levels available in the system: error, warning, info and debug. For each severity level the logging API (include/zephyr/logging/log.h) has set of dedicated macros. Logger API also has macros for logging data.

For each level following set of macros are available:

• LOG_X for standard printf-like messages, e.g. LOG_ERR.
• LOG_HEXDUMP_X for dumping data, e.g. LOG_HEXDUMP_WRN.
• LOG_INST_X for standard printf-like message associated with the particular instance, e.g. LOG_INST_INF.
• LOG_INST_HEXDUMP_X for dumping data associated with the particular instance, e.g. LOG_HEXDUMP_INST_DBG

There are two configuration categories: configurations per module and global configuration. When logging is enabled globally, it works for modules. However, modules can disable logging locally. Every module can specify its own logging level. The module must define the LOG_LEVEL macro before using the API. Unless a global override is set, the module logging level will be honored. The global override can only increase the logging level. It cannot be used to lower module logging levels that were previously set higher. It is also possible to globally limit logs by providing maximal severity level present in the system, where maximal means lowest severity (e.g. if maximal level in the system is set to info, it means that errors, warnings and info levels are present but debug messages are excluded).

Each module which is using the logging must specify its unique name and register itself to the logging. If module consists of more than one file, registration is performed in one file but each file must define a module name.

Logger’s default frontend is designed to be thread safe and minimizes time needed to log the message. Time consuming operations like string formatting or access to the transport are not performed by default when logging API is called. When logging API is called a message is created and added to the list. Dedicated, configurable buffer for pool of log messages is used. There are 2 types of messages: standard and hexdump. Each message contain source ID (module or instance ID and domain ID which might be used for multiprocessor systems), timestamp and severity level. Standard message contains pointer to the string and arguments. Hexdump message contains copied data and string.

4.12.1 Global Kconfig Options

These options can be found in the following path subsys/logging/Kconfig.
CONFIG_LOG: Global switch, turns on/off the logging.

Mode of operations:
- CONFIG_LOG_MODE_DEFERRED: Deferred mode.
- CONFIG_LOG_MODE_IMMEDIATE: Immediate (synchronous) mode.
- CONFIG_LOG_MODE_MINIMAL: Minimal footprint mode.

Filtering options:
- CONFIG_LOG_RUNTIME_FILTERING: Enables runtime reconfiguration of the filtering.
- CONFIG_LOG_DEFAULT_LEVEL: Default level, sets the logging level used by modules that are not setting their own logging level.
- CONFIG_LOG_OVERRIDE_LEVEL: It overrides module logging level when it is not set or set lower than the override value.
- CONFIG_LOG_MAX_LEVEL: Maximal (lowest severity) level which is compiled in.

Processing options:
- CONFIG_LOG_MODE_OVERFLOW: When new message cannot be allocated, oldest one are discarded.
- CONFIG_LOG_BLOCK_IN_THREAD: If enabled and new log message cannot be allocated thread context will block for up to CONFIG_LOG_BLOCK_IN_THREAD_TIMEOUT_MS or until log message is allocated.
- CONFIG_LOG_PRINTK: Redirect printk calls to the logging.
- CONFIG_LOG_PROCESS_TRIGGER_THRESHOLD: When the number of buffered log messages reaches the threshold, the dedicated thread (see log_thread_set()) is woken up. If CONFIG_LOG_PROCESS_THREAD is enabled then this threshold is used by the internal thread.
- CONFIG_LOG_PROCESS_THREAD: When enabled, logging thread is created which handles log processing.
- CONFIG_LOG_PROCESS_THREAD_STARTUP_DELAY_MS: Delay in milliseconds after which logging thread is started.
- CONFIG_LOG_BUFFER_SIZE: Number of bytes dedicated for the circular packet buffer.
- CONFIG_LOG_FRONTEND: Direct logs to a custom frontend.
- CONFIG_LOG_FRONTEND_ONLY: No backends are used when messages goes to frontend.
- CONFIG_LOG_FRONTEND_OPT_API: Optional API optimized for the most common simple messages.
- CONFIG_LOG_CUSTOM_HEADER: Injects an application provided header into log.h
- CONFIG_LOG_TIMESTAMP_64BIT: 64 bit timestamp.
- CONFIG_LOG_SIMPLE_MSG_OPTIMIZE: Optimizes simple log messages for size and performance. Option available only for 32 bit architectures.

Formatting options:
- CONFIG_LOG_FUNC_NAME_PREFIX_ERR: Prepend standard ERROR log messages with function name. Hexdump messages are not prepended.
- CONFIG_LOG_FUNC_NAME_PREFIX_WRN: Prepend standard WARNING log messages with function name. Hexdump messages are not prepended.
- CONFIG_LOG_FUNC_NAME_PREFIX_INF: Prepend standard INFO log messages with function name. Hexdump messages are not prepended.
- CONFIG_LOG_FUNC_NAME_PREFIX_DBG: Prepend standard DEBUG log messages with function name. Hexdump messages are not prepended.
- CONFIG_LOG_BACKEND_SHOW_COLOR: Enables coloring of errors (red) and warnings (yellow).
CONFIG_LOG_BACKEND_FORMAT_TIMESTAMP: If enabled timestamp is formatted to \textit{hh:mm:ss:mmm,uuu}. Otherwise is printed in raw format.

Backend options:
CONFIG_LOG_BACKEND_UART: Enabled built-in UART backend.

### 4.12.2 Usage

#### Logging in a module

In order to use logging in the module, a unique name of a module must be specified and module must be registered using `LOG_MODULE_REGISTER`. Optionally, a compile time log level for the module can be specified as the second parameter. Default log level (CONFIG_LOG_DEFAULT_LEVEL) is used if custom log level is not provided.

```c
#include <zephyr/logging/log.h>
LOG_MODULE_REGISTER(foo, CONFIG_FOO_LOG_LEVEL);
```

If the module consists of multiple files, then `LOG_MODULE_REGISTER()` should appear in exactly one of them. Each other file should use `LOG_MODULE_DECLARE` to declare its membership in the module. Optionally, a compile time log level for the module can be specified as the second parameter. Default log level (CONFIG_LOG_DEFAULT_LEVEL) is used if custom log level is not provided.

```c
#include <zephyr/logging/log.h>
/* In all files comprising the module but one */
LOG_MODULE_DECLARE(foo, CONFIG_FOO_LOG_LEVEL);
```

In order to use logging API in a function implemented in a header file `LOG_MODULE_DECLARE` macro must be used in the function body before logging API is called. Optionally, a compile time log level for the module can be specified as the second parameter. Default log level (CONFIG_LOG_DEFAULT_LEVEL) is used if custom log level is not provided.

```c
#include <zephyr/logging/log.h>

static inline void foo(void)
{
    LOG_MODULE_DECLARE(foo, CONFIG_FOO_LOG_LEVEL);
    LOG_INF("foo");
}
```

Dedicated Kconfig template (subsys/logging/Kconfig.template.log_config) can be used to create local log level configuration.

Example below presents usage of the template. As a result CONFIG_FOO_LOG_LEVEL will be generated:

```bash
module = FOO
module-str = foo
source "subsys/logging/Kconfig.template.log_config"
```

#### Logging in a module instance

In case of modules which are multi-instance and instances are widely used across the system enabling logs will lead to flooding. The logger provides the tools which can be used to provide filtering on instance level rather than module level. In that case logging can be enabled for particular instance.

In order to use instance level filtering following steps must be performed:
• a pointer to specific logging structure is declared in instance structure. LOG_INSTANCE_PTR_DECLARE is used for that.

```c
#include <zephyr/logging/log_instance.h>

struct foo_object {
    LOG_INSTANCE_PTR_DECLARE(log);
    uint32_t id;
};
```

• module must provide macro for instantiation. In that macro, logging instance is registered and log instance pointer is initialized in the object structure.

```c
#define FOO_OBJECT_DEFINE(_name) \
    LOG_INSTANCE_REGISTER(foo, _name, CONFIG_FOO_LOG_LEVEL) \
    struct foo_object _name = { \
            LOG_INSTANCE_PTR_INIT(log, foo, _name) \
    }
```

Note that when logging is disabled logging instance and pointer to that instance are not created. In order to use the instance logging API in a source file, a compile-time log level must be set using LOG_LEVEL_SET.

```c
LOG_LEVEL_SET(CONFIG_FOO_LOG_LEVEL);
void foo_init(foo_object *f) {
    LOG_INST_INF(f->log, "Initialized.");
}
```

In order to use the instance logging API in a header file, a compile-time log level must be set using LOG_LEVEL_SET.

```c
static inline void foo_init(foo_object *f) {
    LOG_LEVEL_SET(CONFIG_FOO_LOG_LEVEL);
    LOG_INST_INF(f->log, "Initialized.");
}
```

**Controlling the logging**

By default, logging processing in deferred mode is handled internally by the dedicated task which starts automatically. However, it might not be available if multithreading is disabled. It can also be disabled by unsetting CONFIG_LOG_PROCESS_TRIGGER_THRESHOLD. In that case, logging can be controlled using the API defined in include/zephyr/logging/log_ctrl.h. Logging must be initialized before it can be used. Optionally, the user can provide a function which returns the timestamp value. If not provided, k_cycle_get or k_cycle_get_32 is used for timestamping. The log_process() function is used to trigger processing of one log message (if pending), and returns true if there are more messages pending. However, it is recommended to use macro wrappers (LOG_INIT and LOG_PROCESS) which handle the case where logging is disabled.

The following snippet shows how logging can be processed in simple forever loop.

```c
#include <zephyr/logging/log_ctrl.h>

int main(void) {
    LOG_INIT();
    (continues on next page)```
If logs are processed from a thread (user or internal) then it is possible to enable a feature which will wake up processing thread when certain amount of log messages are buffered (see `CONFIG_LOG_PROCESS_TRIGGER_THRESHOLD`).

### 4.12.3 Logging panic

In case of error condition system usually can no longer rely on scheduler or interrupts. In that situation deferred log message processing is not an option. Logger controlling API provides a function for entering into panic mode (`log_panic()`) which should be called in such situation.

When `log_panic()` is called, _panic_ notification is sent to all active backends. Once all backends are notified, all buffered messages are flushed. Since that moment all logs are processed in a blocking way.

### 4.12.4 Printk

Typically, logging and `printk()` use the same output, which they compete for. This can lead to issues if the output does not support preemption but it may also result in corrupted output because logging data is interleaved with printk data. However, it is possible to redirect printk messages to the logging subsystem by enabling `CONFIG_LOG_PRINTK`. In that case, printk entries are treated as log messages with level 0 (they cannot be disabled). When enabled, logging manages the output so there is no interleaving. However, in deferred mode the printk behaviour is changed since the output is delayed until the logging thread processes the data. `CONFIG_LOG_PRINTK` is enabled by default.

### 4.12.5 Architecture

Logging consists of 3 main parts:
- Frontend
- Core
- Backends

Log message is generated by a source of logging which can be a module or instance of a module.

#### Default Frontend

Default frontend is engaged when the logging API is called in a source of logging (e.g. `LOG_INF`) and is responsible for filtering a message (compile and run time), allocating a buffer for the message, creating the message and committing that message. Since the logging API can be called in an interrupt, the frontend is optimized to log the message as fast as possible.
**Log message** A log message contains a message descriptor (source, domain and level), timestamp, formatted string details (see *Cbprintf Packaging*) and optional data. Log messages are stored in a continuous block of memory. Memory is allocated from a circular packet buffer (*Multi Producer Single Consumer Packet Buffer*), which has a few consequences:

- Each message is a self-contained, continuous block of memory thus it is suited for copying
  the message (e.g. for offline processing).
- Messages must be sequentially freed. Backend processing is synchronous. Backend can
  make a copy for deferred processing.

A log message has following format:

| Message Header | 2 bits: MPSC packet buffer header |
|               | 1 bit: Trace/Log message flag      |
|               | 3 bits: Domain ID                  |
|               | 3 bits: Level                      |
|               | 10 bits: Cbprintf Package Length    |
|               | 12 bits: Data length               |
|               | 1 bit: Reserved                    |
|               | pointer: Pointer to the source descriptor |
| Cbprintf       | 32 or 64 bits: Timestamp           |
| package        | Optional padding                   |
| (optional)     | Header                              |
|                | Arguments                           |
|                | Appended strings                    |
| Hexdump data   | Alignment padding (optional)        |
| (optional)     |                                     |

**Log message allocation** It may happen that the frontend cannot allocate a message. This happens if the system is generating more log messages than it can process in certain time frame. There are two strategies to handle that case:

- No overflow - the new log is dropped if space for a message cannot be allocated.
- Overflow - the oldest pending messages are freed, until the new message can be allocated. Enabled by `CONFIG_LOG_MODE_OVERFLOW`. Note that it degrades performance thus it is recommended to adjust buffer size and amount of enabled logs to limit dropping.

**Run-time filtering** If run-time filtering is enabled, then for each source of logging a filter structure in RAM is declared. Such filter is using 32 bits divided into ten 3 bit slots. Except slot 0, each slot stores current filter for one backend in the system. Slot 0 (bits 0-2) is used to aggregate maximal filter setting for given source of logging. Aggregate slot determines if log message is created for given entry since it indicates if there is at least one backend expecting that log entry. Backend slots are examined when message is processed by the core to determine if message is accepted by the given backend. Contrary to compile time filtering, binary footprint is increased because logs are compiled in.

In the example below backend 1 is set to receive errors (slot 1) and backend 2 up to info level (slot 2). Slots 3-9 are not used. Aggregated filter (slot 0) is set to info level and up to this level message from that particular source will be buffered.

---

1 Depending on the platform and the timestamp size fields may be swapped.
2 It may be required for cbprintf package alignment
Custom Frontend

Custom frontend is enabled using CONFIG_LOG_FRONTEND. Logs are directed to functions declared in include/zephyr/logging/log_frontend.h. If option CONFIG_LOG_FRONTEND_ONLY is enabled then log message is not created and no backend is handled. Otherwise, custom frontend can coexist with backends.

In some cases, logs need to be redirected at the macro level. For these cases, CONFIG_LOG_CUSTOM_HEADER can be used to inject an application provided header named zephyr_custom_log.h at the end of include/zephyr/logging/log.h.

Logging strings

String arguments are handled by Cbprintf Packaging. See Limitations and recommendations for limitations and recommendations.

Multi-domain support

More complex systems can consist of multiple domains where each domain is an independent binary. Examples of domains are a core in a multicore SoC or one of the binaries (Secure or Nonsecure) on an ARM TrustZone core.

Tracing and debugging on a multi-domain system is more complex and requires an efficient logging system. Two approaches can be used to structure this logging system:

- Log inside each domain independently. This option is not always possible as it requires that each domain has an available backend (for example, UART). This approach can also be troublesome to use and not scalable, as logs are presented on independent outputs.
- Use a multi-domain logging system where log messages from each domain end up in one root domain, where they are processed exactly as in a single domain case. In this approach, log messages are passed between domains using a connection between domains created from the backend on one side and linked to the other.

The Log link is an interface introduced in this multi-domain approach. The Log link is responsible for receiving any log message from another domain, creating a copy, and putting that local log message copy (including remote data) into the message queue. This specific log link implementation matches the complementary backend implementation to allow log messages exchange and logger control like configuring filtering, getting log source names, and so on.

There are three types of domains in a multi-domain system:

- The end domain has the logging core implementation and a cross-domain backend. It can also have other backends in parallel.
- The relay domain has one or more links to other domains but does not have backends that output logs to the user. It has a cross-domain backend either to another relay or to the root domain.
- The root domain has one or multiple links and a backend that outputs logs to the user.

See the following image for an example of a multi-domain setup:

In this architecture, a link can handle multiple domains. For example, let's consider an SoC with two ARM Cortex-M33 cores with TrustZone: cores A and B (see the example illustrated above).
There are four domains in the system, as each core has both a Secure and a Nonsecure domain. If core A nonsecure (A_NS) is the root domain, it has two links: one to core A secure (A_NS-A_S) and one to core B nonsecure (A_NS-B_NS). B_NS domain has one link, to core B secure B_NS-B_S, and a backend to A_NS.

Since in all instances there is a standard logging subsystem, it is always possible to have multiple backends and simultaneously output messages to them. An example of this is shown in the illustration above as a dotted UART backend on the B_NS domain.

**Domain ID**  The source of each log message can be identified by the following fields in the header: source_id and domain_id.

The value assigned to the domain_id is relative. Whenever a domain creates a log message, it sets its domain_id to 0. When a message crosses the domain, domain_id changes as it is increased by the link offset. The link offset is assigned during the initialization, where the logger core is iterating over all the registered links and assigned offsets.

The first link has the offset set to 1. The following offset equals the previous link offset plus the number of domains in the previous link.

The following example is shown below, where the assigned domain_ids are shown for each domain:

Let's consider a log message created on the B_S domain:

1. Initially, it has its domain_id set to 0.
2. When the B_NS-B_S link receives the message, it increases the domain_id to 1 by adding the B_NS-B_S offset.
3. The message is passed to A_NS.
4. When the A_NS-B_NS link receives the message, it adds the offset (2) to the domain_id. The message ends up with the domain_id set to 3, which uniquely identifies the message originator.

**Cross-domain log message**  In most cases, the address space of each domain is unique, and one domain cannot access directly the data in another domain. For this reason, the backend can partially process the message before it is passed to another domain. Partial processing can include converting a string package to a *fully self-contained* version (copying read-only strings to the package body).

Each domain can have a different timestamp source in terms of frequency and offset. Logging does not perform any timestamp conversion.

**Runtime filtering**  In the single-domain case, each log source has a dedicated variable with runtime filtering for each backend in the system. In the multi-domain case, the originator of the log message is not aware of the number of backends in the root domain.

As such, to filter logs in multiple domains, each source requires a runtime filtering setting in each domain on the way to the root domain. As the number of sources in other domains is not known during the compilation, the runtime filtering of remote sources must use dynamically allocated memory (one word per source). When a backend in the root domain changes the filtering of the module from a remote domain, the local filter is updated. After the update, the aggregated filter (the maximum from all the local backends) is checked and, if changed, the remote domain is informed about this change. With this approach, the runtime filtering works identically in both multi-domain and single-domain scenarios.
Message ordering  Logging does not provide any mechanism for synchronizing timestamps across multiple domains:

- If domains have different timestamp sources, messages will be processed in the order of arrival to the buffer in the root domain.
- If domains have the same timestamp source or if there is an out-of-bound mechanism that recalculates timestamps, there are 2 options:
  - Messages are processed as they arrive in the buffer in the root domain. Messages are unordered but they can be sorted by the host as the timestamp indicates the time of the message generation.
  - Links have dedicated buffers. During processing, the head of each buffer is checked and the oldest message is processed first.

With this approach, it is possible to maintain the order of the messages at the cost of a suboptimal memory utilization (since the buffer is not shared) and increased processing latency (see CONFIG_LOG_PROCESSING_LATENCY_US).

Logging backends

Logging backends are registered using LOG_BACKEND_DEFINE. The macro creates an instance in the dedicated memory section. Backends can be dynamically enabled (log_backend_enable()) and disabled. When Run-time filtering is enabled, log_filter_set() can be used to dynamically change filtering of a module logs for given backend. Module is identified by source ID and domain ID. Source ID can be retrieved if source name is known by iterating through all registered sources.

Logging supports up to 9 concurrent backends. Log message is passed to the each backend in processing phase. Additionally, backend is notified when logging enter panic mode with log_backend_panic(). On that call backend should switch to synchronous, interrupt-less operation or shut down itself if that is not supported. Occasionally, logging may inform backend about number of dropped messages with log_backend_dropped(). Message processing API is version specific.

log_backend_msg_process() is used for processing message. It is common for standard and hex-dump messages because log message hold string with arguments and data. It is also common for deferred and immediate logging.

Message formatting  Logging provides set of function that can be used by the backend to format a message. Helper functions are available in include/zephyr/logging/log_output.h.

Example message formatted using log_output_msg_process().

[00:00:00.000,274] <info> sample_instance.inst1: logging message

Dictionary-based Logging

Dictionary-based logging, instead of human readable texts, outputs the log messages in binary format. This binary format encodes arguments to formatted strings in their native storage formats which can be more compact than their text equivalents. For statically defined strings (including the format strings and any string arguments), references to the ELF file are encoded instead of the whole strings. A dictionary created at build time contains the mappings between these references and the actual strings. This allows the offline parser to obtain the strings from the dictionary to parse the log messages. This binary format allows a more compact representation of log messages in certain scenarios. However, this requires the use of an offline parser and is not as intuitive to use as text-based log messages.
Note that long double is not supported by Python’s struct module. Therefore, log messages with long double will not display the correct values.

**Configuration** Here are kconfig options related to dictionary-based logging:

- CONFIG_LOG_DICTIONARY_SUPPORT enables dictionary-based logging support. This should be selected by the backends which require it.

- The UART backend can be used for dictionary-based logging. These are additional config for the UART backend:
  - CONFIG_LOG_BACKEND_UART_OUTPUT_DICTIONARY_HEX tells the UART backend to output hexadecimal characters for dictionary based logging. This is useful when the log data needs to be captured manually via terminals and consoles.
  - CONFIG_LOG_BACKEND_UART_OUTPUT_DICTIONARY_BIN tells the UART backend to output binary data.

**Usage** When dictionary-based logging is enabled via enabling related logging backends, a JSON database file, named log_dictionary.json, will be created in the build directory. This database file contains information for the parser to correctly parse the log data. Note that this database file only works with the same build, and cannot be used for any other builds.

To use the log parser:

```
./scripts/logging/dictionary/log_parser.py <build dir>/log_dictionary.json <log data file>
```

The parser takes two required arguments, where the first one is the full path to the JSON database file, and the second part is the file containing log data. Add an optional argument --hex to the end if the log data file contains hexadecimal characters (e.g. when CONFIG_LOG_BACKEND_UART_OUTPUT_DICTIONARY_HEX=y). This tells the parser to convert the hexadecimal characters to binary before parsing.

Please refer to the logging-dictionary sample to learn more on how to use the log parser.

**4.12.6 Recommendations**

The are following recommendations:

- Enable CONFIG_LOG_SPEED to slightly speed up deferred logging at the cost of slight increase in memory footprint.

- Compiler with C11_Generic keyword support is recommended. Logging performance is significantly degraded without it. See Cbprintf Packaging.

- It is recommended to cast pointer to const char * when it is used with %s format specifier and it points to a constant string.

- It is recommended to cast pointer to char * when it is used with %s format specifier and it points to a transient string.

- It is recommended to cast character pointer to non character pointer (e.g., void *) when it is used with %p format specifier.

```c
LOG_WRN("%s", str);
LOG_WRN("%p", (void *)str);
```
4.12.7 Benchmark

Benchmark numbers from tests/subsys/logging/log_benchmark performed on qemu_x86. It is a rough comparison to give a general overview.

<table>
<thead>
<tr>
<th>Feature</th>
<th>Time (us)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Kernel logging</td>
<td>7us/11us</td>
</tr>
<tr>
<td>User logging</td>
<td>13us</td>
</tr>
<tr>
<td>Kernel logging with overwrite</td>
<td>10us/15us</td>
</tr>
<tr>
<td>Logging transient string</td>
<td>42us</td>
</tr>
<tr>
<td>Logging transient string from user</td>
<td>50us</td>
</tr>
<tr>
<td>Memory utilization</td>
<td>518</td>
</tr>
<tr>
<td>Memory footprint (test)</td>
<td>2k</td>
</tr>
<tr>
<td>Memory footprint (application)</td>
<td>3.5k</td>
</tr>
<tr>
<td>Message footprint</td>
<td>47/32 bytes</td>
</tr>
</tbody>
</table>

Benchmark details

4.12.8 Stack usage

When logging is enabled it impacts stack usage of the context that uses logging API. If stack is optimized it may lead to stack overflow. Stack usage depends on mode and optimization. It also significantly varies between platforms. In general, when CONFIG_LOG_MODE_DEFERRED is used stack usage is smaller since logging is limited to creating and storing log message. When CONFIG_LOG_MODE_IMMEDIATE is used then log message is processed by the backend which includes string formatting. In case of that mode, stack usage will depend on which backends are used. tests/subsys/logging/log_stack test is used to characterize stack usage depending on mode, optimization and platform used. Test is using only the default backend.

Some of the platforms characterization for log message with two integer arguments listed below:

<table>
<thead>
<tr>
<th>Platform</th>
<th>Deferred</th>
<th>Deferred (no optimization)</th>
<th>Immediate</th>
<th>Immediate (no optimization)</th>
</tr>
</thead>
<tbody>
<tr>
<td>ARM Cortex-M3</td>
<td>40</td>
<td>152</td>
<td>412</td>
<td>783</td>
</tr>
<tr>
<td>x86</td>
<td>12</td>
<td>224</td>
<td>388</td>
<td>796</td>
</tr>
<tr>
<td>riscv32</td>
<td>24</td>
<td>208</td>
<td>456</td>
<td>844</td>
</tr>
<tr>
<td>xtensa</td>
<td>72</td>
<td>336</td>
<td>504</td>
<td>944</td>
</tr>
<tr>
<td>x86_64</td>
<td>32</td>
<td>528</td>
<td>1088</td>
<td>1440</td>
</tr>
</tbody>
</table>

4.12.9 API Reference

3 CONFIG_LOG_SPEED enabled.
4 Number of log messages with various number of arguments that fits in 2048 bytes dedicated for logging.
5 Logging subsystem memory footprint in tests/subsys/logging/log_benchmark where filtering and formatting features are not used.
6 Logging subsystem memory footprint in samples/subsys/logging/logger.
7 Average size of a log message (excluding string) with 2 arguments on Cortex M3
Logger API

Related code samples

BLE logging backend
Send log messages over BLE using the BLE logging backend.

Dictionary-based logging
Output binary log data using the dictionary-based logging API.

Logging
Output log messages to the console using the logging subsystem.

```c
4.12. Logging 873
```

Defines

**LOG_ERR(...)**
Writes an ERROR level message to the log.
It's meant to report severe errors, such as those from which it's not possible to recover.

**Parameters**
- `...` – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

**LOG_WRN(...)**
Writes a WARNING level message to the log.
It's meant to register messages related to unusual situations that are not necessarily errors.

**Parameters**
- `...` – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

**LOG_INF(...)**
Writes an INFO level message to the log.
It's meant to write generic user oriented messages.

**Parameters**
- `...` – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

**LOG_DBG(...)**
Writes a DEBUG level message to the log.
It's meant to write developer oriented information.

**Parameters**
- `...` – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.
LOG_PRINTK(...)  
Unconditionally print raw log message.
The result is same as if printk was used but it goes through logging infrastructure thus
utilizes logging mode, e.g. deferred mode.

**Parameters**  
- ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_RAW(...)  
Unconditionally print raw log message.
Provided string is printed as is without appending any characters (e.g., color or newline).

**Parameters**  
- ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_INST_ERR(_log_inst, ...)  
Writes an ERROR level message associated with the instance to the log.
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>.<instance_name>). It's meant to report severe errors, such as those from which it's not possible to recover.

**Parameters**  
- _log_inst – Pointer to the log structure associated with the instance.
- ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_INST_WRN(_log_inst, ...)  
Writes a WARNING level message associated with the instance to the log.
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>.<instance_name>). It's meant to register messages related to unusual situations that are not necessarily errors.

**Parameters**  
- _log_inst – Pointer to the log structure associated with the instance.
- ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_INST_INF(_log_inst, ...)  
Writes an INFO level message associated with the instance to the log.
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>.<instance_name>). It's meant to write generic user oriented messages.

**Parameters**  
- _log_inst – Pointer to the log structure associated with the instance.
- ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.
LOG_INST_DBG(_log_inst, ...)  
Writes a DEBUG level message associated with the instance to the log.  
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>..<instance_name>). It's meant to write developer oriented information.

Parameters

- _log_inst – Pointer to the log structure associated with the instance.
- ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_HEXDUMP_ERR(_data, _length, _str)  
Writes an ERROR level hexdump message to the log.  
It's meant to report severe errors, such as those from which it's not possible to recover.

Parameters

- _data – Pointer to the data to be logged.
- _length – Length of data (in bytes).
- _str – Persistent, raw string.

LOG_HEXDUMP_WRN(_data, _length, _str)  
Writes a WARNING level message to the log.  
It's meant to register messages related to unusual situations that are not necessarily errors.

Parameters

- _data – Pointer to the data to be logged.
- _length – Length of data (in bytes).
- _str – Persistent, raw string.

LOG_HEXDUMP_INF(_data, _length, _str)  
Writes an INFO level message to the log.  
It's meant to write generic user oriented messages.

Parameters

- _data – Pointer to the data to be logged.
- _length – Length of data (in bytes).
- _str – Persistent, raw string.

LOG_HEXDUMP_DBG(_data, _length, _str)  
Writes a DEBUG level message to the log.  
It's meant to write developer oriented information.

Parameters

- _data – Pointer to the data to be logged.
- _length – Length of data (in bytes).
- _str – Persistent, raw string.
LOG_INST_HEXDUMP_ERR(_log_inst, _data, _length, _str)
Writes an ERROR hexdump message associated with the instance to the log.
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>.<instance_name>). It's meant to report severe errors, such as those from which it's not possible to recover.

Parameters
- _log_inst – Pointer to the log structure associated with the instance.
- _data – Pointer to the data to be logged.
- _length – Length of data (in bytes).
- _str – Persistent, raw string.

LOG_INST_HEXDUMP_WRN(_log_inst, _data, _length, _str)
Writes a WARNING level hexdump message associated with the instance to the log.
It's meant to register messages related to unusual situations that are not necessarily errors.

Parameters
- _log_inst – Pointer to the log structure associated with the instance.
- _data – Pointer to the data to be logged.
- _length – Length of data (in bytes).
- _str – Persistent, raw string.

LOG_INST_HEXDUMP_INF(_log_inst, _data, _length, _str)
Writes an INFO level hexdump message associated with the instance to the log.
It's meant to write generic user oriented messages.

Parameters
- _log_inst – Pointer to the log structure associated with the instance.
- _data – Pointer to the data to be logged.
- _length – Length of data (in bytes).
- _str – Persistent, raw string.

LOG_INST_HEXDUMP_DBG(_log_inst, _data, _length, _str)
Writes a DEBUG level hexdump message associated with the instance to the log.
It's meant to write developer oriented information.

Parameters
- _log_inst – Pointer to the log structure associated with the instance.
- _data – Pointer to the data to be logged.
- _length – Length of data (in bytes).
- _str – Persistent, raw string.

LOG_MODULE_REGISTER(...)
Create module-specific state and register the module with Logger.
This macro normally must be used after including <zephyr/logging/log.h> to complete the initialization of the module.
Module registration can be skipped in two cases:
The module consists of more than one file, and another file invokes this macro. `LOG_MODULE_DECLARE()` should be used instead in all of the module's other files.

Instance logging is used and there is no need to create module entry. In that case `LOG_LEVEL_SET()` should be used to set log level used within the file.

Macro accepts one or two parameters:
- module name
- optional log level. If not provided then default log level is used in the file.

Example usage:
- `LOG_MODULE_REGISTER(foo, CONFIG_FOO_LOG_LEVEL)`
- `LOG_MODULE_REGISTER(foo)`

See also:
`LOG_MODULE_DECLARE`

Note: The module's state is defined, and the module is registered, only if `LOG_LEVEL` for the current source file is non-zero or it is not defined and `CONFIG_LOG_DEFAULT_LEVEL` is non-zero. In other cases, this macro has no effect.

`LOG_MODULE_DECLARE(...)`

Macro for declaring a log module (not registering it).

Modules which are split up over multiple files must have exactly one file use `LOG_MODULE_REGISTER()` to create module-specific state and register the module with the logger core.

The other files in the module should use this macro instead to declare that same state. (Otherwise, `LOG_INF()` etc. will not be able to refer to module-specific state variables.)

Macro accepts one or two parameters:
- module name
- optional log level. If not provided then default log level is used in the file.

Example usage:
- `LOG_MODULE_DECLARE(foo, CONFIG_FOO_LOG_LEVEL)`
- `LOG_MODULE_DECLARE(foo)`

See also:
`LOG_MODULE_REGISTER`

Note: The module's state is declared only if `LOG_LEVEL` for the current source file is non-zero or it is not defined and `CONFIG_LOG_DEFAULT_LEVEL` is non-zero. In other cases, this macro has no effect.

`LOG_LEVEL_SET(level)`

Macro for setting log level in the file or function where instance logging API is used.

Parameters
- `level` - Level used in file or in function.
Logger control

Related code samples

Logging
Output log messages to the console using the logging subsystem.

Remote syslog
Enable a remote syslog service that sends syslog messages to a remote server

\texttt{group log\_ctrl}
Logger control API.

\textbf{Defines}

\texttt{LOG\_CORE\_INIT()}
\texttt{LOG\_INIT()}
\texttt{LOG\_PANIC()}
\texttt{LOG\_PROCESS()}

\textbf{Typedefs}

typedef log\_timestamp\_t (*log\_timestamp\_get\_t)(void)

\textbf{Functions}

\texttt{void log\_core\_init(void)}
Function system initialization of the logger.
Function is called during start up to allow logging before user can explicitly initialize the logger.

\texttt{void log\_init(void)}
Function for user initialization of the logger.

\texttt{void log\_thread\_set(k\_tid\_t process\_tid)}
Function for providing thread which is processing logs.
See CONFIG\_LOG\_PROCESS\_TRIGGER\_THRESHOLD.

\textbf{Note:} Function has asserts and has no effect when CONFIG\_LOG\_PROCESS\_THREAD is set.

\textbf{Parameters}

- \texttt{process\_tid} – Process thread id. Used to wake up the thread.
int log_set_timestamp_func(log_timestamp_get_t timestamp_getter, uint32_t freq)
    Function for providing timestamp function.

Parameters
    • timestamp_getter – Timestamp function.
    • freq – Timestamping frequency.

Returns
    0 on success or error.

void log_panic(void)
    Switch the logger subsystem to the panic mode.
    Returns immediately if the logger is already in the panic mode.
    On panic the logger subsystem informs all backends about panic mode. Backends must
    switch to blocking mode or halt. All pending logs are flushed after switching to panic
    mode. In panic mode, all log messages must be processed in the context of the call.

bool log_process(void)
    Process one pending log message.

Return values
    • true – There are more messages pending to be processed.
    • false – No messages pending.

uint32_t log_buffered_cnt(void)
    Return number of buffered log messages.

Returns
    Number of currently buffered log messages.

uint32_t log_src_cnt_get(uint32_t domain_id)
    Get number of independent logger sources (modules and instances)

Parameters
    • domain_id – Domain ID.

Returns
    Number of sources.

const char *log_source_name_get(uint32_t domain_id, uint32_t source_id)
    Get name of the source (module or instance).

Parameters
    • domain_id – Domain ID.
    • source_id – Source ID.

Returns
    Source name or NULL if invalid arguments.

static inline uint8_t log_domains_count(void)
    Return number of domains present in the system.
    There will be at least one local domain.

Returns
    Number of domains.
const char *log_domain_name_get(uint32_t domain_id)
Get name of the domain.

**Parameters**
- **domain_id** – Domain ID.

**Returns**
Domain name.

int log_source_id_get(const char *name)
Function for finding source ID based on source name.

**Parameters**
- **name** – Source name

**Returns**
Source ID or negative number when source ID is not found.

uint32_t log_filter_get(struct log_backend const *const backend, uint32_t domain_id,
int16_t source_id, bool runtime)
Get source filter for the provided backend.

**Parameters**
- **backend** – Backend instance.
- **domain_id** – ID of the domain.
- **source_id** – Source (module or instance) ID.
- **runtime** – True for runtime filter or false for compiled in.

**Returns**
Severity level.

uint32_t log_filter_set(struct log_backend const *const backend, uint32_t domain_id,
int16_t source_id, uint32_t level)
Set filter on given source for the provided backend.

**Parameters**
- **backend** – Backend instance. NULL for all backends (and frontend).
- **domain_id** – ID of the domain.
- **source_id** – Source (module or instance) ID.
- **level** – Severity level.

**Returns**
Actual level set which may be limited by compiled level. If filter was set for all backends then maximal level that was set is returned.

uint32_t log_frontend_filter_get(int16_t source_id, bool runtime)
Get source filter for the frontend.

**Parameters**
- **source_id** – Source (module or instance) ID.
- **runtime** – True for runtime filter or false for compiled in.

**Returns**
Severity level.
uint32_t log_frontend_filter_set(int16_t source_id, uint32_t level)
Set filter on given source for the frontend.

Parameters
• source_id – Source (module or instance) ID.
• level – Severity level.

Returns
Actual level set which may be limited by compiled level.

void log_backend_enable(struct log_backend const *const backend, void *ctx, uint32_t level)
Enable backend with initial maximum filtering level.

Parameters
• backend – Backend instance.
• ctx – User context.
• level – Severity level.

void log_backend_disable(struct log_backend const *const backend)
Disable backend.

Parameters
• backend – Backend instance.

const struct log_backend *log_backend_get_by_name(const char *backend_name)
Get backend by name.

Parameters
• backend_name – [in] Name of the backend as defined by the LOG_BACKEND_DEFINE.

Return values
Pointer – to the backend instance if found, NULL if backend is not found.

const struct log_backend *log_format_set_all_active_backends(size_t log_type)
Sets logging format for all active backends.

Parameters
• log_type – Log format.

Return values
Pointer – to the last backend that failed, NULL for success.

static inline bool log_data_pending(void)
Check if there is pending data to be processed by the logging subsystem.
Function can be used to determine if all logs have been flushed. Function returns false when deferred mode is not enabled.

Return values
• true – There is pending data.
• false – No pending data to process.

int log_set_tag(const char *tag)
Configure tag used to prefix each message.

Parameters
• tag – Tag.
Return values
• 0 – on successful operation.
• -ENOTSUP – if feature is disabled.
• -ENOMEM – if string is longer than the buffer capacity. Tag will be trimmed.

int log_mem_get_usage(uint32_t *buf_size, uint32_t *usage)
Get current memory usage.
Parameters
• buf_size – [out] Capacity of the buffer used for storing log messages.
• usage – [out] Number of bytes currently containing pending log messages.
Return values
• -EINVAL – if logging mode does not use the buffer.
• 0 – successfully collected usage data.

int log_mem_get_max_usage(uint32_t *max)
Get maximum memory usage.
Requires CONFIG_LOG_MEM_UTILIZATION option.
Parameters
• max – [out] Maximum number of bytes used for pending log messages.
Return values
• -EINVAL – if logging mode does not use the buffer.
• -ENOTSUP – if instrumentation is not enabled.
• 0 – successfully collected usage data.

Log message

group log_msg
Log message API.

Defines

LOG_MSG_GENERIC_HDR
LOG_MSG_SIMPLE_ARG_CNT_CHECK(...)
LOG_MSG_SIMPLE_ARG_TYPE_CHECK_0(fmt)
LOG_MSG_SIMPLE_ARG_TYPE_CHECK_1(fmt, arg)
LOG_MSG_SIMPLE_ARG_TYPE_CHECK_2(fmt, arg0, arg1)
LOG_MSG_SIMPLE_ARG_TYPE_CHECK(...)
brief Determine if string arguments types allow to use simplified message creation mode.
Parameters
• ... – String with arguments.
LOG_MSG_SIMPLE_CHECK(...)  
Check if message can be handled using simplified method.  
Following conditions must be met:  
• 32 bit platform  
• Number of arguments from 0 to 2  
• Type of an argument must be a numeric value that fits in 32 bit word.  

Parameters  
• ... – String with arguments.  

Return values  
• 1 – if message qualifies.  
• 0 – if message does not qualify.  

LOG_MSG_SIMPLE_FUNC(_source, _level, ...)  
Call specific function to create a log message.  
Macro picks matching function (based on number of arguments) and calls it. String arguments are casted to uint32_t.  

Parameters  
• _source – Source.  
• _level – Severity level.  
• ... – String with arguments.  

Functions  

static inline uint32_t log_msg_get_total_wlen(const struct log_msg_desc desc)  
Get total length (in 32 bit words) of a log message.  

Parameters  
• desc – Log message descriptor.  

Returns  
Length.  

static inline uint32_t log_msg_generic_get_wlen(const union mpsc_pbuf_generic *item)  
Get length of the log item.  

Parameters  
• item – Item.  

Returns  
Length in 32 bit words.  

static inline uint8_t log_msg_get_domain(struct log_msg *msg)  
Get log message domain ID.  

Parameters  
• msg – Log message.  

Returns  
Domain ID
static inline uint8_t log_msg_get_level(struct log_msg *msg)
Get log message level.

Parameters
• msg – Log message.

Returns
Log level.

static inline const void *log_msg_get_source(struct log_msg *msg)
Get message source data.

Parameters
• msg – Log message.

Returns
Pointer to the source data.

static inline log_timestamp_t log_msg_get_timestamp(struct log_msg *msg)
Get timestamp.

Parameters
• msg – Log message.

Returns
Timestamp.

static inline void *log_msg_get_tid(struct log_msg *msg)
Get Thread ID.

Parameters
• msg – Log message.

Returns
Thread ID.

static inline uint8_t *log_msg_get_data(struct log_msg *msg, size_t *len)
Get data buffer.

Parameters
• msg – log message.
• len – location where data length is written.

Returns
pointer to the data buffer.

static inline uint8_t *log_msg_get_package(struct log_msg *msg, size_t *len)
Get string package.

Parameters
• msg – log message.
• len – location where string package length is written.

Returns
pointer to the package.

struct log_msg_desc
#include <log_msg.h>

union log_msg_source
#include <log_msg.h>
Public Members

const struct log_source_const_data *fixed

struct log_source_dynamic_data *dynamic

void *raw

struct log_msg_hdr
    #include <log_msg.h>

struct log_msg
    #include <log_msg.h>

struct log_msg_generic_hdr
    #include <log_msg.h>

union log_msg_generic
    #include <log_msg.h>

Public Members

union mpsc_pbuf_generic buf

struct log_msg_generic_hdr generic

struct log_msg log

Logger backend interface

Related code samples

BLE logging backend
Send log messages over BLE using the BLE logging backend.

Remote syslog
Enable a remote syslog service that sends syslog messages to a remote server

group log_backend
    Logger backend interface.

Defines
LOG_BACKEND_DEFINE(_name, _api, _autostart, ...)

Macro for creating a logger backend instance.

**Parameters**

- `_name` – Name of the backend instance.
- `_api` – Logger backend API.
- `_autostart` – If true backend is initialized and activated together with the logger subsystem.
- `...` – Optional context.

**Enums**

enum log_backend_evt

Backend events.

**Values:**

enumerator LOG_BACKEND_EVT_PROCESS_THREAD_DONE

Event when process thread finishes processing.

This event is emitted when the process thread finishes processing pending log messages.

**Note:** This is not emitted when there are no pending log messages being processed.

**Note:** Deferred mode only.

enumerator LOG_BACKEND_EVT_MAX

Maximum number of backend events.

**Functions**

static inline void log_backend_init(const struct log_backend *const backend)

Initialize or initiate the logging backend.

If backend initialization takes longer time it could block logging thread if backend is autostarted. That is because all backends are initialized in the context of the logging thread. In that case, backend shall provide function for polling for readiness (log_backend_is_ready).

**Parameters**

- `backend` – **[in]** Pointer to the backend instance.

static inline int log_backend_is_ready(const struct log_backend *const backend)

Poll for backend readiness.

If backend is ready immediately after initialization then backend may not provide this function.

**Parameters**
• **backend** – [in] Pointer to the backend instance.

**Return values**

- 0 – if backend is ready.
- -EBUSY – if backend is not yet ready.

static inline void **log_backend_msg_process**(const struct **log_backend** *const backend, union **log_msg_generic** *msg)

Process message.

Function is used in deferred and immediate mode. On return, message content is processed by the backend and memory can be freed.

**Parameters**

- **backend** – [in] Pointer to the backend instance.
- **msg** – [in] Pointer to message with log entry.

static inline void **log_backend_dropped**(const struct **log_backend** *const backend, uint32_t cnt)

Notify backend about dropped log messages.

Function is optional.

**Parameters**

- **backend** – [in] Pointer to the backend instance.
- **cnt** – [in] Number of dropped logs since last notification.

static inline void **log_backend_panic**(const struct **log_backend** *const backend)

Reconfigure backend to panic mode.

**Parameters**

- **backend** – [in] Pointer to the backend instance.

static inline void **log_backend_id_set**(const struct **log_backend** *const backend, uint8_t id)

Set backend id.

**Note:** It is used internally by the logger.

**Parameters**

- **backend** – Pointer to the backend instance.
- **id** – ID.

static inline uint8_t **log_backend_id_get**(const struct **log_backend** *const backend)

Get backend id.

**Note:** It is used internally by the logger.

**Parameters**

- **backend** – [in] Pointer to the backend instance.

**Returns**

Id.
static inline const struct log_backend *log_backend_get(uint32_t idx)

Get backend.

**Parameters**


**Returns**

Pointer to the backend instance.

static inline int log_backend_count_get(void)

Get number of backends.

**Returns**

Number of backends.

static inline void log_backend_activate(const struct log_backend *const backend, void *ctx)

Activate backend.

**Parameters**


static inline void log_backend_deactivate(const struct log_backend *const backend)

Deactivate backend.

**Parameters**


static inline bool log_backend_is_active(const struct log_backend *const backend)

Check state of the backend.

**Parameters**


**Returns**

True if backend is active, false otherwise.

static inline int log_backend_format_set(const struct log_backend *backend, uint32_t log_type)

Set logging format.

**Parameters**

- `backend` – Pointer to the backend instance.
- `log_type` – Log format.

**Return values**

- `-ENOTSUP` – If the backend does not support changing format types.
- `-EINVAL` – If the input is invalid.
- `0` – for success.

static inline void log_backend_notify(const struct log_backend *const backend, enum log_backend_evt event, union log_backend_evt_arg *arg)

Notify a backend of an event.

**Parameters**

- `backend` – Pointer to the backend instance.
• event – Event to be notified.
• arg – Pointer to the argument(s).

union log_backend_evt_arg
#include <log_backend.h> Argument(s) for backend events.

Public Members

void *raw
    Unspecified argument(s).

struct log_backend_api
#include <log_backend.h> Logger backend API.

struct log_backend_control_block
#include <log_backend.h> Logger backend control block.

struct log_backend
#include <log_backend.h> Logger backend structure.

Logger output formatting

group log_output
    Log output API.

Unnamed Group

void log_custom_output_msg_process(const struct log_output *log_output, struct log_msg *msg, uint32_t flags)
    Custom logging output formatting.
    Process log messages from an external output function set with log_custom_output_msg_set
    Function is using provided context with the buffer and output function to process formatted string and output the data.

    Parameters
    • log_output – Pointer to the log output instance.
    • msg – Log message.
    • flags – Optional flags.

Defines

LOG_OUTPUT_TEXT
    Supported backend logging format types for use with log_format_set() API to switch log format at runtime.

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LOG_OUTPUT_SYST

LOG_OUTPUT_DICT

LOG_OUTPUT_CUSTOM

LOG_OUTPUT_DEFINE(_name, _func, _buf, _size)
Create log_output instance.

Parameters
- _name – Instance name.
- _func – Function for processing output data.
- _buf – Pointer to the output buffer.
- _size – Size of the output buffer.

Typedefs

typedef int (*log_output_func_t)(uint8_t *buf, size_t size, void *ctx)
Prototype of the function processing output data.

**Note:** If the log output function cannot process all of the data, it is its responsibility to mark them as dropped or discarded by returning the corresponding number of bytes dropped or discarded to the caller.

**Param buf**
The buffer data.

**Param size**
The buffer size.

**Param ctx**
User context.

**Return**
Number of bytes processed, dropped or discarded.

typedef void (*log_format_func_t)(const struct log_output *output, struct log_msg *msg, uint32_t flags)
Typedef of the function pointer table “format_table”.

**Param output**
Pointer to log_output struct.

**Param msg**
Pointer to log_msg struct.

**Param flags**
Flags used for text formatting options.

**Return**
Function pointer based on Kconfigs defined for backends.
Functions

`log_format_func_t log_format_func_t_get(uint32_t log_type)`
Declaration of the get routine for function pointer table format_table.

`void log_output_msg_process(const struct log_output *log_output, struct log_msg *msg, uint32_t flags)`
Process log messages v2 to readable strings.
Function is using provided context with the buffer and output function to process formatted string and output the data.

**Parameters**

- `log_output` – Pointer to the log output instance.
- `msg` – Log message.
- `flags` – Optional flags. See Log output formatting flags.

`void log_output_process(const struct log_output *log_output, log_timestamp_t timestamp, const char *domain, const char *source, k_tid_t tid, uint8_t level, const uint8_t *package, const uint8_t *data, size_t data_len, uint32_t flags)`
Process input data to a readable string.

**Parameters**

- `log_output` – Pointer to the log output instance.
- `timestamp` – Timestamp.
- `domain` – Domain name string. Can be NULL.
- `source` – Source name string. Can be NULL.
- `tid` – Thread ID.
- `level` – Criticality level.
- `package` – CPRINTF package with a logging message string.
- `data` – Data passed to hexdump API. Can be NULL.
- `data_len` – Data length.
- `flags` – Formatting flags. See Log output formatting flags.

`void log_output_msg_syst_process(const struct log_output *log_output, struct log_msg *msg, uint32_t flags)`
Process log messages v2 to SYS-T format.
Function is using provided context with the buffer and output function to process formatted string and output the data in sys-t log output format.

**Parameters**

- `log_output` – Pointer to the log output instance.
- `msg` – Log message.
- `flags` – Optional flags. See Log output formatting flags.

`void log_output_dropped_process(const struct log_output *output, uint32_t cnt)`
Process dropped messages indication.
Function prints error message indicating lost log messages.

**Parameters**
• output – Pointer to the log output instance.
• cnt – Number of dropped messages.

void log_output_flush(const struct log_output *output)
Flush output buffer.

Parameters
• output – Pointer to the log output instance.

static inline void log_output_ctx_set(const struct log_output *output, void *ctx)
Function for setting user context passed to the output function.

Parameters
• output – Pointer to the log output instance.
• ctx – User context.

static inline void log_output_hostname_set(const struct log_output *output, const char *hostname)
Function for setting hostname of this device.

Parameters
• output – Pointer to the log output instance.
• hostname – Hostname of this device

void log_output_timestamp_freq_set(uint32_t freq)
Set timestamp frequency.

Parameters
• freq – Frequency in Hz.

uint64_t log_output_timestamp_to_us(log_timestamp_t timestamp)
Convert timestamp of the message to us.

Parameters
• timestamp – Message timestamp

Returns
Timestamp value in us.

struct log_output_control_block

#include <log_output.h>

struct log_output

#include <log_output.h> Log_output instance structure.

4.13 Tracing

4.13.1 Overview

The tracing feature provides hooks that permits you to collect data from your application and allows tools running on a host to visualize the inner-working of the kernel and various subsystems.

Every system has application-specific events to trace out. Historically, that has implied:

1. Determining the application-specific payload,
2. Choosing suitable serialization-format,
3. Writing the on-target serialization code,
4. Deciding on and writing the I/O transport mechanics,
5. Writing the PC-side deserializer/parser,
6. Writing custom ad-hoc tools for filtering and presentation.

An application can use one of the existing formats or define a custom format by overriding the macros declared in include/zephyr/tracing/tracing.h.

Different formats, transports and host tools are available and supported in Zephyr. In fact, I/O varies greatly from system to system. Therefore, it is instructive to create a taxonomy for I/O types when we must ensure the interface between payload/format (Top Layer) and the transport mechanics (bottom Layer) is generic and efficient enough to model these. See the I/O taxonomy section below.

4.13.2 Serialization Formats

Common Trace Format (CTF) Support

Common Trace Format, CTF, is an open format and language to describe trace formats. This enables tool reuse, of which line-textual (babeltrace) and graphical (TraceCompass) variants already exist.

CTF should look familiar to C programmers but adds stronger typing. See CTF - A Flexible, High-performance Binary Trace Format.

CTF allows us to formally describe application specific payload and the serialization format, which enables common infrastructure for host tools and parsers and tools for filtering and presentation.

A Generic Interface  In CTF, an event is serialized to a packet containing one or more fields. As seen from I/O taxonomy section below, a bottom layer may:

- perform actions at transaction-start (e.g. mutex-lock),
- process each field in some way (e.g. sync-push emit, concat, enqueue to thread-bound FIFO),
- perform actions at transaction-stop (e.g. mutex-release, emit of concat buffer).

CTF Top-Layer Example  The CTF_EVENT macro will serialize each argument to a field:

```c
/* Example for illustration */
static inline void ctf_top_foo(uint32_t thread_id, ctf_bounded_string_t name)
{
  CTF_EVENT(
    CTF_LITERAL(uint8_t, 42),
    thread_id,
    name,
    "hello, I was emitted from function: ",
    __func__ /* __func__ is standard since C99 */
  );
}
```

How to serialize and emit fields as well as handling alignment, can be done internally and statically at compile-time in the bottom-layer.

4.13. Tracing
The CTF top layer is enabled using the configuration option \texttt{CONFIG\_TRACING\_CTF} and can be used with the different transport backends both in synchronous and asynchronous modes.

**SEGGER SystemView Support**

Zephyr provides built-in support for \texttt{SEGGER SystemView} that can be enabled in any application for platforms that have the required hardware support.

The payload and format used with SystemView is custom to the application and relies on RTT as a transport. Newer versions of SystemView support other transports, for example UART or using snapshot mode (both still not supported in Zephyr).

To enable tracing support with \texttt{SEGGER SystemView} add the configuration option \texttt{CONFIG\_SEGGER\_SYSTEMVIEW} to your project configuration file and set it to \texttt{y}. For example, this can be added to the synchronization sample to visualize fast switching between threads. SystemView can also be used for post-mortem tracing, which can be enabled with \texttt{CONFIG\_SEGGER\_SYSVIEW\_POST\_MORTEM\_MODE}. In this mode, a debugger can be attached after the system has crashed using \texttt{west attach} after which the latest data from the internal RAM buffer can be loaded into SystemView:

```
CONFIG\_STDOUT\_CONSOLE=y
# enable to use thread names
CONFIG\_THREAD\_NAME=y
CONFIG\_SEGGER\_SYSTEMVIEW=y
CONFIG\_USE\_SEGGER\_RTT=y
CONFIG\_TRACING=y
# enable for post-mortem tracing
CONFIG\_SEGGER\_SYSVIEW\_POST\_MORTEM\_MODE=n
```

Recent versions of \texttt{SEGGER SystemView} come with an API translation table for Zephyr which is incomplete and does not match the current level of support available in Zephyr. To use the latest Zephyr API description table, copy the file available in the tree to your local configuration directory to override the built-in table:

```
# On Linux and MacOS
cp \$ZEPHYR\_BASE\/subsys\/tracing\/sysview\/SYSVIEW\_Zephyr.txt ~/.config/SEGGER/
```
User-Defined Tracing

This tracing format allows the user to define functions to perform any work desired when a task is switched in or out, when an interrupt is entered or exited, and when the cpu is idle.

Examples include: - simple toggling of GPIO for external scope tracing while minimizing extra cpu load - generating/outputting trace data in a non-standard or proprietary format that can not be supported by the other tracing systems

The following functions can be defined by the user:

```c
void sys_trace_thread_create_user(struct k_thread *thread);
void sys_trace_thread_abort_user(struct k_thread *thread);
void sys_trace_thread_suspend_user(struct k_thread *thread);
void sys_trace_thread_resume_user(struct k_thread *thread);
void sys_trace_thread_name_set_user(struct k_thread *thread);
void sys_trace_thread_switched_in_user(struct k_thread *thread);
void sys_trace_thread_switched_out_user(struct k_thread *thread);
void sys_trace_thread_info_user(struct k_thread *thread);
void sys_trace_thread_sched_ready_user(struct k_thread *thread);
void sys_trace_thread_pend_user(struct k_thread *thread);
void sys_trace_thread_priority_set_user(struct k_thread *thread, int prio);
void sys_trace_isr_enter_user(int nested_interrupts);
void sys_trace_isr_exit_user(int nested_interrupts);
void sys_trace_idle_user();
```

Enable this format with the `CONFIG_TRACING_USER` option.

### 4.13.3 Transport Backends

The following backends are currently supported:

- UART
- USB
- File (Using the native port with POSIX architecture based targets)
- RTT (With SystemView)
- RAM (buffer to be retrieved by a debugger)

### 4.13.4 Using Tracing

The sample `samples/subsys/tracing` demonstrates tracing with different formats and backends.

To get started, the simplest way is to use the CTF format with the native_sim port, build the sample as follows:

Using west:

```
west build -b native_sim samples/subsys/tracing -- -DCONF_FILE=prj_native_ctf.conf
```

Using CMake and ninja:

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -B build -GNinja -DBOARD=native_sim -DCONF_FILE=prj_native_ctf.conf samples/subsys/tracing

# Now run the build tool on the generated build system:
ninja -C build
```
You can then run the resulting binary with the option `-trace-file` to generate the tracing data:

```bash
mkdir data
cp $ZEPHYR_BASE/subsys/tracing/ctf/tsdl/metadata data/
./build/zephyr/zephyr.exe -trace-file=data/channel0_0
```

The resulting CTF output can be visualized using babeltrace or TraceCompass by pointing the tool to the `data` directory with the metadata and trace files.

**Using RAM backend**

For devices that do not have available I/O for tracing such as USB or UART but have enough RAM to collect trace data, the ram backend can be enabled with configuration `CONFIG_TRACING_BACKEND_RAM`. Adjust `CONFIG_RAM_TRACING_BUFFER_SIZE` to be able to record enough traces for your needs. Then thanks to a runtime debugger such as gdb this buffer can be fetched from the target to an host computer:

```gdb
(gdb) dump binary memory data/channel0_0 <ram_tracing_start> <ram_tracing_end>
```

The resulting `channel0_0` file have to be placed in a directory with the `metadata` file like the other backend.

### 4.13.5 Visualisation Tools

**TraceCompass**

TraceCompass is an open source tool that visualizes CTF events such as thread scheduling and interrupts, and is helpful to find unintended interactions and resource conflicts on complex systems.

See also the presentation by Ericsson, *Advanced Trouble-shooting Of Real-time Systems*.

### 4.13.6 Future LTTng Inspiration

Currently, the top-layer provided here is quite simple and bare-bones, and needlessly copied from Zephyr’s Segger SystemView debug module.

For an OS like Zephyr, it would make sense to draw inspiration from Linux's LTTng and change the top-layer to serialize to the same format. Doing this would enable direct reuse of TraceCompass’ canned analyses for Linux. Alternatively, LTTng-analyses in TraceCompass could be customized to Zephyr. It is ongoing work to enable TraceCompass visibility of Zephyr in a target-agnostic and open source way.

**I/O Taxonomy**

- **Atomic Push/Produce/Write/Enqueue:**
  - **synchronous:** means data-transmission has completed with the return of the call.
  - **asynchronous:** means data-transmission is pending or ongoing with the return of the call. Usually, interrupts/callbacks/signals or polling is used to determine completion.
- **buffered:**
  means data-transmissions are copied and grouped together to form a larger ones. Usually for amortizing overhead (burst dequeue) or jitter Mitigation (steady dequeue).

**Examples:**
- **sync unbuffered**
  E.g. PIO via GPIOs having steady stream, no extra FIFO memory needed. Low jitter but may be less efficient (can’t amortize the overhead of writing).
- **sync buffered**
  E.g. fwrite() or enqueuing into FIFO. Blockingly burst the FIFO when its buffer-waterlevel exceeds threshold. Jitter due to bursts may lead to missed deadlines.
- **async unbuffered**
  E.g. DMA, or zero-copying in shared memory. Be careful of data hazards, race conditions, etc!
- **async buffered**
  E.g. enqueuing into FIFO.

• Atomic Pull/Consume/Read/Dequeue:
  - **synchronous:**
    means data-reception has completed with the return of the call.
  - **asynchronous:**
    means data-reception is pending or ongoing with the return of the call. Usually, interrupts/callbacks/signals or polling is used to determine completion.
  - **buffered:**
    means data is copied-in in larger chunks than request-size. Usually for amortizing wait-time.

**Examples:**
- **sync unbuffered**
  E.g. Blocking read-call, fread() or SPI-read, zero-copying in shared memory.
- **sync buffered**
  E.g. Blocking read-call with caching applied. Makes sense if read pattern exhibits spatial locality.
- **async unbuffered**
  E.g. zero-copying in shared memory. Be careful of data hazards, race conditions, etc!
- **async buffered**
  E.g. aio_read() or DMA.

Unfortunately, I/O may not be atomic and may, therefore, require locking. Locking may not be needed if multiple independent channels are available.

• **The system has non-atomic write and one shared channel**
  E.g. UART. Locking required.
  
  lock(); emit(a); emit(b); emit(c); release();

• **The system has non-atomic write but many channels**
  E.g. Multi-UART. Lock-free if the bottom-layer maps each Zephyr thread+ISR to its own channel, thus alleviating races as each thread is sequentially consistent with itself.
  
  emit(a,thread_id); emit(b,thread_id); emit(c,thread_id);

• **The system has atomic write but one shared channel**
  E.g. native_sim or board with DMA. May or may not need locking.
emit(a ## b ## c); /* Concat to buffer */
lock(); emit(a); emit(b); emit(c); release(); /* No extra mem */

- The system has atomic write and many channels
  E.g. native_sim or board with multi-channel DMA. Lock-free.
  emit(a ## b ## c, thread_id);

### 4.13.7 Object tracking

The kernel can also maintain lists of objects that can be used to track their usage. Currently, the following lists can be enabled:

```c
struct k_timer *_track_list_k_timer;
struct k_mem_slab *_track_list_k_mem_slab;
struct k_sem *_track_list_k_sem;
struct k_mutex *_track_list_k_mutex;
struct k_stack *_track_list_k_stack;
struct k_msgq *_track_list_k_msgq;
struct k_mbox *_track_list_k_mbox;
struct k_pipe *_track_list_k_pipe;
struct k_queue *_track_list_k_queue;
struct k_event *_track_list_k_event;
```

Those global variables are the head of each list - they can be traversed with the help of macro SYS_PORT_TRACK_NEXT. For instance, to traverse all initialized mutexes, one can write:

```c
struct k_mutex *cur = _track_list_k_mutex;
while (cur != NULL) {
  /* Do something */
  cur = SYS_PORT_TRACK_NEXT(cur);
}
```

To enable object tracking, enable CONFIG_TRACING_OBJECT_TRACKING. Note that each list can be enabled or disabled via their tracing configuration. For example, to disable tracking of semaphores, one can disable CONFIG_TRACING_SEMAPHORE.

Object tracking is behind tracing configuration as it currently leverages tracing infrastructure to perform the tracking.

### 4.13.8 API

**Common**

`group subsys_tracing_apis`

  Tracing APIs.

  **Functions**

  void `sys_trace_isr_enter(void)`
  Called when entering an ISR.

  void `sys_trace_isr_exit(void)`
  Called when exiting an ISR.
void sys_trace_isr_exit_to_scheduler(void)
   Called when exiting an ISR and switching to scheduler.

void sys_trace_idle(void)
   Called when the cpu enters the idle state.

Threads

group subsys_tracing_apis_thread
   Thread Tracing APIs.

Defines

sys_port_trace_k_thread_foreach_enter()
   Called when entering a k_thread_foreach call.

sys_port_trace_k_thread_foreach_exit()
   Called when exiting a k_thread_foreach call.

sys_port_trace_k_thread_foreach_unlocked Enter()
   Called when entering a k_thread_foreach_unlocked.

sys_port_trace_k_thread_foreach_unlocked exit()
   Called when exiting a k_thread_foreach_unlocked.

sys_port_trace_k_thread_create(new_thread)
   Trace creating a Thread.

Parameters
   • new_thread – Thread object

sys_port_trace_k_thread_user_mode_enter()
   Trace Thread entering user mode.

sys_port_trace_k_thread_join_enter(thread, timeout)
   Called when entering a k_thread_join.

Parameters
   • thread – Thread object
   • timeout – Timeout period

sys_port_trace_k_thread_join_blocking(thread, timeout)
   Called when k_thread_join blocks.

Parameters
   • thread – Thread object
   • timeout – Timeout period

sys_port_trace_k_thread_join_exit(thread, timeout, ret)
   Called when exiting k_thread_join.

Parameters
   • thread – Thread object
   • timeout – Timeout period
   • ret – Return value
sys_port_trace_k_thread_sleep_enter(timeout)
Called when entering k_thread_sleep.

Parameters
• timeout – Timeout period

sys_port_trace_k_thread_sleep_exit(timeout, ret)
Called when exiting k_thread_sleep.

Parameters
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_thread_msleep_enter(ms)
Called when entering k_thread_msleep.

Parameters
• ms – Duration in milliseconds

sys_port_trace_k_thread_msleep_exit(ms, ret)
Called when exiting k_thread_msleep.

Parameters
• ms – Duration in milliseconds
• ret – Return value

sys_port_trace_k_thread_usleep_enter(us)
Called when entering k_thread_usleep.

Parameters
• us – Duration in microseconds

sys_port_trace_k_thread_usleep_exit(us, ret)
Called when exiting k_thread_usleep.

Parameters
• us – Duration in microseconds
• ret – Return value

sys_port_trace_k_thread_busy_wait_enter(usec_to_wait)
Called when entering k_thread_busy_wait.

Parameters
• usec_to_wait – Duration in microseconds

sys_port_trace_k_thread_busy_wait_exit(usec_to_wait)
Called when exiting k_thread_busy_wait.

Parameters
• usec_to_wait – Duration in microseconds

sys_port_trace_k_thread_yield()
Called when a thread yields.

sys_port_trace_k_thread_wakeup(thread)
Called when a thread wakes up.

Parameters
• thread – Thread object
sys_port_trace_k_thread_start(thread)
Called when a thread is started.

Parameters
• thread – Thread object

sys_port_trace_k_thread_abort(thread)
Called when a thread is being aborted.

Parameters
• thread – Thread object

sys_port_trace_k_thread_abort_enter(thread)
Called when a thread enters the k_thread_abort routine.

Parameters
• thread – Thread object

sys_port_trace_k_thread_abort_exit(thread)
Called when a thread exits the k_thread_abort routine.

Parameters
• thread – Thread object

sys_port_trace_k_thread_priority_set(thread)
Called when setting priority of a thread.

Parameters
• thread – Thread object

sys_port_trace_k_thread_suspend_enter(thread)
Called when a thread enters the k_thread_suspend function.

Parameters
• thread – Thread object

sys_port_trace_k_thread_suspend_exit(thread)
Called when a thread exits the k_thread_suspend function.

Parameters
• thread – Thread object

sys_port_trace_k_thread_resume_enter(thread)
Called when a thread enters the resume from suspension function.

Parameters
• thread – Thread object

sys_port_trace_k_thread_resume_exit(thread)
Called when a thread exits the resumed from suspension function.

Parameters
• thread – Thread object

sys_port_trace_k_thread_sched_lock()
Called when the thread scheduler is locked.

sys_port_trace_k_thread_sched_unlock()
Called when the thread scheduler is unlocked.
sys_port_trace_k_thread_name_set(thread, ret)
Called when a thread name is set.

Parameters
• thread – Thread object
• ret – Return value

sys_port_trace_k_thread_switched_out()
Called before a thread has been selected to run.

sys_port_trace_k_thread_switched_in()
Called after a thread has been selected to run.

sys_port_trace_k_thread_ready(thread)
Called when a thread is ready to run.

Parameters
• thread – Thread object

sys_port_trace_k_thread_pend(thread)
Called when a thread is pending.

Parameters
• thread – Thread object

sys_port_trace_k_thread_info(thread)
Provide information about specific thread.

Parameters
• thread – Thread object

sys_port_trace_k_thread_sched_wakeup(thread)
Trace implicit thread wakeup invocation by the scheduler.

Parameters
• thread – Thread object

sys_port_trace_k_thread_sched_abort(thread)
Trace implicit thread abort invocation by the scheduler.

Parameters
• thread – Thread object

sys_port_trace_k_thread_sched_priority_set(thread, prio)
Trace implicit thread set priority invocation by the scheduler.

Parameters
• thread – Thread object
• prio – Thread priority

sys_port_trace_k_thread_sched_ready(thread)
Trace implicit thread ready invocation by the scheduler.

Parameters
• thread – Thread object
sys_port_trace_k_thread_sched_pend(thread)
    Trace implicit thread pend invocation by the scheduler.

    Parameters
    • thread – Thread object

sys_port_trace_k_thread_sched_resume(thread)
    Trace implicit thread resume invocation by the scheduler.

    Parameters
    • thread – Thread object

sys_port_trace_k_thread_sched_suspend(thread)
    Trace implicit thread suspend invocation by the scheduler.

    Parameters
    • thread – Thread object

**Work Queues**

group subsys_tracing_apis_work
    Work Tracing APIs.

**Defines**

sys_port_trace_k_work_init(work)
    Trace initialisation of a Work structure.

    Parameters
    • work – Work structure

sys_port_trace_k_work_submit_to_queue_enter(queue, work)
    Trace submit work to work queue call entry.

    Parameters
    • queue – Work queue structure
    • work – Work structure

sys_port_trace_k_work_submit_to_queue_exit(queue, work, ret)
    Trace submit work to work queue call exit.

    Parameters
    • queue – Work queue structure
    • work – Work structure
    • ret – Return value

sys_port_trace_k_work_submit_enter(work)
    Trace submit work to system work queue call entry.

    Parameters
    • work – Work structure
sys_port_trace_k_work_submit_exit(work, ret)
Trace submit work to system work queue call exit.

Parameters
- work – Work structure
- ret – Return value

sys_port_trace_k_work_flush_enter(work)
Trace flush work call entry.

Parameters
- work – Work structure

sys_port_trace_k_work_flush_blocking(work, timeout)
Trace flush work call blocking.

Parameters
- work – Work structure
- timeout – Timeout period

sys_port_trace_k_work_flush_exit(work, ret)
Trace flush work call exit.

Parameters
- work – Work structure
- ret – Return value

sys_port_trace_k_work_cancel_enter(work)
Trace cancel work call entry.

Parameters
- work – Work structure

sys_port_trace_k_work_cancel_exit(work, ret)
Trace cancel work call exit.

Parameters
- work – Work structure
- ret – Return value

sys_port_trace_k_work_cancel_sync_enter(work, sync)
Trace cancel sync work call entry.

Parameters
- work – Work structure
- sync – Sync object

sys_port_trace_k_work_cancel_sync_blocking(work, sync)
Trace cancel sync work call blocking.

Parameters
- work – Work structure
- sync – Sync object
sys_port_trace_k_work_cancel_sync_exit(work, sync, ret)
Trace cancel sync work call exit.

Parameters
- work – Work structure
- sync – Sync object
- ret – Return value

Poll

group subsys_tracing_apis_poll
Poll Tracing APIs.

Defines

sys_port_trace_k_poll_api_event_init(event)
Trace initialisation of a Poll Event.

Parameters
- event – Poll Event

sys_port_trace_k_poll_api_poll_enter(events)
Trace Polling call start.

Parameters
- events – Poll Events

sys_port_trace_k_poll_api_poll_exit(events, ret)
Trace Polling call outcome.

Parameters
- events – Poll Events
- ret – Return value

sys_port_trace_k_poll_api_signal_init(signal)
Trace initialisation of a Poll Signal.

Parameters
- signal – Poll Signal

sys_port_trace_k_poll_api_signal_reset(signal)
Trace resetting of Poll Signal.

Parameters
- signal – Poll Signal

sys_port_trace_k_poll_api_signal_check(signal)
Trace checking of Poll Signal.

Parameters
- signal – Poll Signal

4.13. Tracing
sys_port_trace_k_poll_api_signal_raise(signal, ret)
Trace raising of Poll Signal.

**Parameters**
- `signal` – Poll Signal
- `ret` – Return value

**Semaphore**

*group* subsys_tracing_apis_sem
Semaphore Tracing APIs.

**Defines**

sys_port_trace_k_sem_init(sem, ret)
Trace initialisation of a Semaphore.

**Parameters**
- `sem` – Semaphore object
- `ret` – Return value

sys_port_trace_k_sem_give_enter(sem)
Trace giving a Semaphore entry.

**Parameters**
- `sem` – Semaphore object

sys_port_trace_k_sem_give_exit(sem)
Trace giving a Semaphore exit.

**Parameters**
- `sem` – Semaphore object

sys_port_trace_k_sem_take_enter(sem, timeout)
Trace taking a Semaphore attempt start.

**Parameters**
- `sem` – Semaphore object
- `timeout` – Timeout period

sys_port_trace_k_sem_take_blocking(sem, timeout)
Trace taking a Semaphore attempt blocking.

**Parameters**
- `sem` – Semaphore object
- `timeout` – Timeout period

sys_port_trace_k_sem_take_exit(sem, timeout, ret)
Trace taking a Semaphore attempt outcome.

**Parameters**
- `sem` – Semaphore object
- `timeout` – Timeout period
- ret – Return value

sys_port_trace_k_sem_reset(sem)
Trace resetting a Semaphore.

**Parameters**
- sem – Semaphore object

**Mutex**

group subsys_tracing_api_mutex
Mutex Tracing APIs.

**Defines**

sys_port_trace_k_mutex_init(mutex, ret)
Trace initialization of Mutex.

**Parameters**
- mutex – Mutex object
- ret – Return value

sys_port_trace_k_mutex_lock_enter(mutex, timeout)
Trace Mutex lock attempt start.

**Parameters**
- mutex – Mutex object
- timeout – Timeout period

sys_port_trace_k_mutex_lock_blocking(mutex, timeout)
Trace Mutex lock attempt blocking.

**Parameters**
- mutex – Mutex object
- timeout – Timeout period

sys_port_trace_k_mutex_lock_exit(mutex, timeout, ret)
Trace Mutex lock attempt outcome.

**Parameters**
- mutex – Mutex object
- timeout – Timeout period
- ret – Return value

sys_port_trace_k_mutex_unlock_enter(mutex)
Trace Mutex unlock entry.

**Parameters**
- mutex – Mutex object

sys_port_trace_k_mutex_unlock_exit(mutex, ret)
Trace Mutex unlock exit.
Condition Variables

(group subsys_tracing_apis_condvar
  Conditional Variable Tracing APIs.

Defines

sys_port_trace_k_condvar_init(condvar, ret)
  Trace initialization of Conditional Variable.
  Parameters
  • condvar – Conditional Variable object
  • ret – Return value

sys_port_trace_k_condvar_signal_enter(condvar)
  Trace Conditional Variable signaling start.
  Parameters
  • condvar – Conditional Variable object

sys_port_trace_k_condvar_signal_blocking(condvar, timeout)
  Trace Conditional Variable signaling blocking.
  Parameters
  • condvar – Conditional Variable object
  • timeout – Timeout period

sys_port_trace_k_condvar_signal_exit(condvar, ret)
  Trace Conditional Variable signaling outcome.
  Parameters
  • condvar – Conditional Variable object
  • ret – Return value

sys_port_trace_k_condvar_broadcast_enter(condvar)
  Trace Conditional Variable broadcast enter.
  Parameters
  • condvar – Conditional Variable object

sys_port_trace_k_condvar_broadcast_exit(condvar, ret)
  Trace Conditional Variable broadcast exit.
  Parameters
  • condvar – Conditional Variable object
  • ret – Return value

sys_port_trace_k_condvar_wait_enter(condvar)
  Trace Conditional Variable wait enter.
  Parameters
  • condvar – Conditional Variable object
sys_port_trace_k_condvar_wait_exit(condvar, ret)
Trace Conditional Variable wait exit.

**Parameters**
- **condvar** – Conditional Variable object
- **ret** – Return value

### Queues

*group* subsys_tracing.Apis_queue
Queue Tracing APIs.

### Defines

**sys_port_trace_k_queue_init(queue)**
Trace initialization of Queue.

**Parameters**
- **queue** – Queue object

**sys_port_trace_k_queue_cancel_wait(queue)**
Trace Queue cancel wait.

**Parameters**
- **queue** – Queue object

**sys_port_trace_k_queue_queue_insert_enter(queue, alloc)**
Trace Queue insert attempt entry.

**Parameters**
- **queue** – Queue object
- **alloc** – Allocation flag

**sys_port_trace_k_queue_queue_insert_blocking(queue, alloc, timeout)**
Trace Queue insert attempt blocking.

**Parameters**
- **queue** – Queue object
- **alloc** – Allocation flag
- **timeout** – Timeout period

**sys_port_trace_k_queue_queue_insert_exit(queue, alloc, ret)**
Trace Queue insert attempt outcome.

**Parameters**
- **queue** – Queue object
- **alloc** – Allocation flag
- **ret** – Return value
sys_port_trace_k_queue_append_enter(queue)
Trace Queue append enter.

Parameters
• queue – Queue object

sys_port_trace_k_queue_append_exit(queue)
Trace Queue append exit.

Parameters
• queue – Queue object

sys_port_trace_k_queue_alloc_append_enter(queue)
Trace Queue alloc append enter.

Parameters
• queue – Queue object

sys_port_trace_k_queue_alloc_append_exit(queue, ret)
Trace Queue alloc append exit.

Parameters
• queue – Queue object
• ret – Return value

sys_port_trace_k_queue_prepend_enter(queue)
Trace Queue prepend enter.

Parameters
• queue – Queue object

sys_port_trace_k_queue_prepend_exit(queue)
Trace Queue prepend exit.

Parameters
• queue – Queue object

sys_port_trace_k_queue_alloc_prepend_enter(queue)
Trace Queue alloc prepend enter.

Parameters
• queue – Queue object

sys_port_trace_k_queue_alloc_prepend_exit(queue, ret)
Trace Queue alloc prepend exit.

Parameters
• queue – Queue object
• ret – Return value

sys_port_trace_k_queue_insert_enter(queue)
Trace Queue insert attempt entry.

Parameters
• queue – Queue object
sys_port_trace_k_queue_insert_blocking(queue, timeout)
    Trace Queue insert attempt blocking.
    **Parameters**
    - queue – Queue object
    - timeout – Timeout period

sys_port_trace_k_queue_insert_exit(queue)
    Trace Queue insert attempt exit.
    **Parameters**
    - queue – Queue object

sys_port_trace_k_queue_append_list_enter(queue)
    Trace Queue append list enter.
    **Parameters**
    - queue – Queue object

sys_port_trace_k_queue_append_list_exit(queue, ret)
    Trace Queue append list exit.
    **Parameters**
    - queue – Queue object
    - ret – Return value

sys_port_trace_k_queue_merge_slist_enter(queue)
    Trace Queue merge slist enter.
    **Parameters**
    - queue – Queue object

sys_port_trace_k_queue_merge_slist_exit(queue, ret)
    Trace Queue merge slist exit.
    **Parameters**
    - queue – Queue object
    - ret – Return value

sys_port_trace_k_queue_get_enter(queue, timeout)
    Trace Queue get attempt enter.
    **Parameters**
    - queue – Queue object
    - timeout – Timeout period

sys_port_trace_k_queue_get_blocking(queue, timeout)
    Trace Queue get attempt blockings.
    **Parameters**
    - queue – Queue object
    - timeout – Timeout period

sys_port_trace_k_queue_get_exit(queue, timeout, ret)
    Trace Queue get attempt outcome.
    **Parameters**
• queue – Queue object
• timeout – Timeout period
• ret – Return value

`sys_port_trace_k_queue_remove_enter(queue)`
Trace Queue remove enter.

**Parameters**
• queue – Queue object

`sys_port_trace_k_queue_remove_exit(queue, ret)`
Trace Queue remove exit.

**Parameters**
• queue – Queue object
• ret – Return value

`sys_port_trace_k_queue_unique_append_enter(queue)`
Trace Queue unique append enter.

**Parameters**
• queue – Queue object

`sys_port_trace_k_queue_unique_append_exit(queue, ret)`
Trace Queue unique append exit.

**Parameters**
• queue – Queue object
• ret – Return value

`sys_port_trace_k_queue_peek_head(queue, ret)`
Trace Queue peek head.

**Parameters**
• queue – Queue object
• ret – Return value

`sys_port_trace_k_queue_peek_tail(queue, ret)`
Trace Queue peek tail.

**Parameters**
• queue – Queue object
• ret – Return value

**FIFO**

`group subsys_tracing apis fifo`

FIFO Tracing APIs.
Defines

**sys_port_trace_k_fifo_init_enter**(fifo)
Trace initialization of FIFO Queue entry.

**Parameters**
- fifo – FIFO object

**sys_port_trace_k_fifo_init_exit**(fifo)
Trace initialization of FIFO Queue exit.

**Parameters**
- fifo – FIFO object

**sys_port_trace_k_fifo_cancel_wait_enter**(fifo)
Trace FIFO Queue cancel wait entry.

**Parameters**
- fifo – FIFO object

**sys_port_trace_k_fifo_cancel_wait_exit**(fifo)
Trace FIFO Queue cancel wait exit.

**Parameters**
- fifo – FIFO object

**sys_port_trace_k_fifo_put_enter**(fifo, data)
Trace FIFO Queue put entry.

**Parameters**
- fifo – FIFO object
- data – Data item

**sys_port_trace_k_fifo_put_exit**(fifo, data)
Trace FIFO Queue put exit.

**Parameters**
- fifo – FIFO object
- data – Data item

**sys_port_trace_k_fifo_alloc_put_enter**(fifo, data)
Trace FIFO Queue alloc put entry.

**Parameters**
- fifo – FIFO object
- data – Data item

**sys_port_trace_k_fifo_alloc_put_exit**(fifo, data, ret)
Trace FIFO Queue alloc put exit.

**Parameters**
- fifo – FIFO object
- data – Data item
- ret – Return value
sys_port_trace_k_fifo_put_list_enter(fifo, head, tail)
Trace FIFO Queue put list entry.

Parameters
• fifo – FIFO object
• head – First ll-node
• tail – Last ll-node

sys_port_trace_k_fifo_put_list_exit(fifo, head, tail)
Trace FIFO Queue put list exit.

Parameters
• fifo – FIFO object
• head – First ll-node
• tail – Last ll-node

sys_port_trace_k_fifo_alloc_put_slist_enter(fifo, list)
Trace FIFO Queue put slist entry.

Parameters
• fifo – FIFO object
• list – Syslist object

sys_port_trace_k_fifo_alloc_put_slist_exit(fifo, list)
Trace FIFO Queue put slist exit.

Parameters
• fifo – FIFO object
• list – Syslist object

sys_port_trace_k_fifo_get_enter(fifo, timeout)
Trace FIFO Queue get entry.

Parameters
• fifo – FIFO object
• timeout – Timeout period

sys_port_trace_k_fifo_get_exit(fifo, timeout, ret)
Trace FIFO Queue get exit.

Parameters
• fifo – FIFO object
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_fifo.peek_head_enter(fifo)
Trace FIFO Queue peek head entry.

Parameters
• fifo – FIFO object

sys_port_trace_k_fifo.peek_head_exit(fifo, ret)
Trace FIFO Queue peek head exit.

Parameters
fifo – FIFO object
ret – Return value

sys_port_trace_k_fifo.Peek_tail Enter(fifo)
Trace FIFO Queue peek tail entry.
Parameters
• fifo – FIFO object

sys_port_trace_k_fifo.Peek_tail Exit(fifo, ret)
Trace FIFO Queue peek tail exit.
Parameters
• fifo – FIFO object
• ret – Return value

LIFO

group subsys_tracing_apis_lifo
LIFO Tracing APIs.

Defines

sys_port_trace_k_lifo.Init Enter(lifo)
Trace initialization of LIFO Queue entry.
Parameters
• lifo – LIFO object

sys_port_trace_k_lifo.Init Exit(lifo)
Trace initialization of LIFO Queue exit.
Parameters
• lifo – LIFO object

sys_port_trace_k_lifo.Put Enter(lifo, data)
Trace LIFO Queue put entry.
Parameters
• lifo – LIFO object
• data – Data item

sys_port_trace_k_lifo.Put Exit(lifo, data)
Trace LIFO Queue put exit.
Parameters
• lifo – LIFO object
• data – Data item

sys_port_trace_k_lifo.Alloc Put Enter(lifo, data)
Trace LIFO Queue alloc put entry.
Parameters
• lifo – LIFO object
• data – Data item

**sys_port_trace_k_lifo_alloc_put_exit**(lifo, data, ret)
Trace LIFO Queue alloc put exit.

**Parameters**
• lifo – LIFO object
• data – Data item
• ret – Return value

**sys_port_trace_k_lifo_get_enter**(lifo, timeout)
Trace LIFO Queue get entry.

**Parameters**
• lifo – LIFO object
• timeout – Timeout period

**sys_port_trace_k_lifo_get_exit**(lifo, timeout, ret)
Trace LIFO Queue get exit.

**Parameters**
• lifo – LIFO object
• timeout – Timeout period
• ret – Return value

**Stacks**

**group** subsys_tracing.Apis_stack
Stack Tracing APIs.

**Defines**

**sys_port_trace_k_stack_init**(stack)
Trace initialization of Stack.

**Parameters**
• stack – Stack object

**sys_port_trace_k_stack_alloc_init_enter**(stack)
Trace Stack alloc init attempt entry.

**Parameters**
• stack – Stack object

**sys_port_trace_k_stack_alloc_init_exit**(stack, ret)
Trace Stack alloc init outcome.

**Parameters**
• stack – Stack object
• ret – Return value
sys_port_trace_k_stack_cleanup_enter(stack)
Trace Stack cleanup attempt entry.

Parameters
• stack – Stack object

sys_port_trace_k_stack_cleanup_exit(stack, ret)
Trace Stack cleanup outcome.

Parameters
• stack – Stack object
• ret – Return value

sys_port_trace_k_stack_push_enter(stack)
Trace Stack push attempt entry.

Parameters
• stack – Stack object

sys_port_trace_k_stack_push_exit(stack, ret)
Trace Stack push attempt outcome.

Parameters
• stack – Stack object
• ret – Return value

sys_port_trace_k_stack_pop_enter(stack, timeout)
Trace Stack pop attempt entry.

Parameters
• stack – Stack object
• timeout – Timeout period

sys_port_trace_k_stack_pop_blocking(stack, timeout)
Trace Stack pop attempt blocking.

Parameters
• stack – Stack object
• timeout – Timeout period

sys_port_trace_k_stack_pop_exit(stack, timeout, ret)
Trace Stack pop attempt outcome.

Parameters
• stack – Stack object
• timeout – Timeout period
• ret – Return value

Message Queues

group subsys_tracing apis_msgq
Message Queue Tracing APIs.
Defines

sys_port_trace_k_msgq_init(msgq)
Trace initialization of Message Queue.

Parameters
• msgq – Message Queue object

sys_port_trace_k_msgq_alloc_init_enter(msgq)
Trace Message Queue alloc init attempt entry.

Parameters
• msgq – Message Queue object

sys_port_trace_k_msgq_alloc_init_exit(msgq, ret)
Trace Message Queue alloc init attempt outcome.

Parameters
• msgq – Message Queue object
• ret – Return value

sys_port_trace_k_msgq_cleanup_enter(msgq)
Trace Message Queue cleanup attempt entry.

Parameters
• msgq – Message Queue object

sys_port_trace_k_msgq_cleanup_exit(msgq, ret)
Trace Message Queue cleanup attempt outcome.

Parameters
• msgq – Message Queue object
• ret – Return value

sys_port_trace_k_msgq_put_enter(msgq, timeout)
Trace Message Queue put attempt entry.

Parameters
• msgq – Message Queue object
• timeout – Timeout period

sys_port_trace_k_msgq_put_blocking(msgq, timeout)
Trace Message Queue put attempt blocking.

Parameters
• msgq – Message Queue object
• timeout – Timeout period

sys_port_trace_k_msgq_put_exit(msgq, timeout, ret)
Trace Message Queue put attempt outcome.

Parameters
• msgq – Message Queue object
• timeout – Timeout period
• ret – Return value
sys_port_trace_k_msgq_get_enter(msgq, timeout)
Trace Message Queue get attempt entry.

Parameters
- msgq – Message Queue object
- timeout – Timeout period

sys_port_trace_k_msgq_get_blocking(msgq, timeout)
Trace Message Queue get attempt blockings.

Parameters
- msgq – Message Queue object
- timeout – Timeout period

sys_port_trace_k_msgq_get_exit(msgq, timeout, ret)
Trace Message Queue get attempt outcome.

Parameters
- msgq – Message Queue object
- timeout – Timeout period
- ret – Return value

sys_port_trace_k_msgq_peek(msgq, ret)
Trace Message Queue peek.

Parameters
- msgq – Message Queue object
- ret – Return value

sys_port_trace_k_msgq_purge(msgq)
Trace Message Queue purge.

Parameters
- msgq – Message Queue object

Mailbox

group subsys_tracing_apis_mbox
Mailbox Tracing APIs.

Defines

sys_port_trace_k mbox_init(mbox)
Trace initialization of Mailbox.

Parameters
- mbox – Mailbox object

sys_port_trace_k mbox_message_put_enter(mbox, timeout)
Trace Mailbox message put attempt entry.

Parameters
- mbox – Mailbox object

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• timeout – Timeout period

`sys_port_trace_k_mbox_message_put_blocking(mbox, timeout)`
Trace Mailbox message put attempt blocking.

**Parameters**
- `mbox` – Mailbox object
- `timeout` – Timeout period

`sys_port_trace_k_mbox_message_put_exit(mbox, timeout, ret)`
Trace Mailbox message put attempt outcome.

**Parameters**
- `mbox` – Mailbox object
- `timeout` – Timeout period
- `ret` – Return value

`sys_port_trace_k_mbox_put_enter(mbox, timeout)`
Trace Mailbox put attempt entry.

**Parameters**
- `mbox` – Mailbox object
- `timeout` – Timeout period

`sys_port_trace_k_mbox_put_exit(mbox, timeout, ret)`
Trace Mailbox put attempt blocking.

**Parameters**
- `mbox` – Mailbox object
- `timeout` – Timeout period
- `ret` – Return value

`sys_port_trace_k_mbox_async_put_enter(mbox, sem)`
Trace Mailbox async put entry.

**Parameters**
- `mbox` – Mailbox object
- `sem` – Semaphore object

`sys_port_trace_k_mbox_async_put_exit(mbox, sem)`
Trace Mailbox async put exit.

**Parameters**
- `mbox` – Mailbox object
- `sem` – Semaphore object

`sys_port_trace_k_mbox_get_enter(mbox, timeout)`
Trace Mailbox get attempt entry.

**Parameters**
- `mbox` – Mailbox entry
- `timeout` – Timeout period

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sys_port_trace_k_mbox_get_blocking(mbox, timeout)
   Trace Mailbox get attempt blocking.
   \textbf{Parameters}
   \begin{itemize}
   \item mbox – Mailbox entry
   \item timeout – Timeout period
   \end{itemize}

sys_port_trace_k_mbox_get_exit(mbox, timeout, ret)
   Trace Mailbox get attempt outcome.
   \textbf{Parameters}
   \begin{itemize}
   \item mbox – Mailbox entry
   \item timeout – Timeout period
   \item ret – Return value
   \end{itemize}

sys_port_trace_k_mbox_data_get(rx_msg)
   Trace Mailbox data get.
   rx_msg Receive Message object

\subsection*{Pipes}

\texttt{group} subsys_tracing apis pipe
   Pipe Tracing APIs.

\subsection*{Defines}

sys_port_trace_k_pipe_init(pipe)
   Trace initialization of Pipe.
   \textbf{Parameters}
   \begin{itemize}
   \item pipe – Pipe object
   \end{itemize}

sys_port_trace_k_pipe_cleanup_enter(pipe)
   Trace Pipe cleanup entry.
   \textbf{Parameters}
   \begin{itemize}
   \item pipe – Pipe object
   \end{itemize}

sys_port_trace_k_pipe_cleanup_exit(pipe, ret)
   Trace Pipe cleanup exit.
   \textbf{Parameters}
   \begin{itemize}
   \item pipe – Pipe object
   \item ret – Return value
   \end{itemize}

sys_port_trace_k_pipe_alloc_init_enter(pipe)
   Trace Pipe alloc init entry.
   \textbf{Parameters}
   \begin{itemize}
   \item pipe – Pipe object
   \end{itemize}
sys_port_trace_k_pipe_alloc_init_exit(pipe, ret)
  Trace Pipe alloc init exit.

  Parameters
  • pipe – Pipe object
  • ret – Return value

sys_port_trace_k_pipe_flush_enter(pipe)
  Trace Pipe flush entry.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_flush_exit(pipe)
  Trace Pipe flush exit.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_buffer_flush_enter(pipe)
  Trace Pipe buffer flush entry.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_buffer_flush_exit(pipe)
  Trace Pipe buffer flush exit.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_put_enter(pipe, timeout)
  Trace Pipe put attempt entry.

  Parameters
  • pipe – Pipe object
  • timeout – Timeout period

sys_port_trace_k_pipe_put_blocking(pipe, timeout)
  Trace Pipe put attempt blocking.

  Parameters
  • pipe – Pipe object
  • timeout – Timeout period

sys_port_trace_k_pipe_put_exit(pipe, timeout, ret)
  Trace Pipe put attempt outcome.

  Parameters
  • pipe – Pipe object
  • timeout – Timeout period
  • ret – Return value

sys_port_trace_k_pipe_get_enter(pipe, timeout)
  Trace Pipe get attempt entry.

  Parameters
• pipe – Pipe object
• timeout – Timeout period

sys_port_trace_k_pipe_get_blocking(pipe, timeout)
Trace Pipe get attempt blocking.

Parameters
• pipe – Pipe object
• timeout – Timeout period

sys_port_trace_k_pipe_get_exit(pipe, timeout, ret)
Trace Pipe get attempt outcome.

Parameters
• pipe – Pipe object
• timeout – Timeout period
• ret – Return value

Heaps

group subsys_tracing APIs_heap
Heap Tracing APIs.

Defines

sys_port_trace_k_heap_init(h)
Trace initialization of Heap.

Parameters
• h – Heap object

sys_port_trace_k_heap_aligned_alloc_enter(h, timeout)
Trace Heap aligned alloc attempt entry.

Parameters
• h – Heap object
• timeout – Timeout period

sys_port_trace_k_heap_aligned_alloc_blocking(h, timeout)
Trace Heap align alloc attempt blocking.

Parameters
• h – Heap object
• timeout – Timeout period

sys_port_trace_k_heap_aligned_alloc_exit(h, timeout, ret)
Trace Heap align alloc attempt outcome.

Parameters
• h – Heap object
• timeout – Timeout period
• ret – Return value
sys_port_trace_k_heap_alloc_enter(h, timeout)
Trace Heap alloc enter.

Parameters
- h – Heap object
- timeout – Timeout period

sys_port_trace_k_heap_alloc_exit(h, timeout, ret)
Trace Heap alloc exit.

Parameters
- h – Heap object
- timeout – Timeout period
- ret – Return value

sys_port_trace_k_heap_free(h)
Trace Heap free.

Parameters
- h – Heap object

sys_port_trace_k_heap_sys_k_aligned_alloc_enter(heap)
Trace System Heap aligned alloc enter.

Parameters
- heap – Heap object

sys_port_trace_k_heap_sys_k_aligned_alloc_exit(heap, ret)
Trace System Heap aligned alloc exit.

Parameters
- heap – Heap object
- ret – Return value

sys_port_trace_k_heap_sys_k_malloc_enter(heap)
Trace System Heap aligned alloc enter.

Parameters
- heap – Heap object

sys_port_trace_k_heap_sys_k_malloc_exit(heap, ret)
Trace System Heap aligned alloc exit.

Parameters
- heap – Heap object
- ret – Return value

sys_port_trace_k_heap_sys_k_free_enter(heap, heap_ref)
Trace System Heap free entry.

Parameters
- heap – Heap object
- heap_ref – Heap reference
sys_port_trace_k_heap_sys_k_free_exit(heap, heap_ref)
Trace System Heap free exit.

Parameters
- heap – Heap object
- heap_ref – Heap reference

sys_port_trace_k_heap_sys_k_calloc_enter(heap)
Trace System heap calloc enter.

Parameters
- heap –

sys_port_trace_k_heap_sys_k_calloc_exit(heap, ret)
Trace System heap calloc exit.

Parameters
- heap – Heap object
- ret – Return value

Memory Slabs

group subsys_tracing_apis_mslab
Memory Slab Tracing APIs.

Defines

sys_port_trace_k_mem_slab_init(slab, rc)
Trace initialization of Memory Slab.

Parameters
- slab – Memory Slab object
- rc – Return value

sys_port_trace_k_mem_slab_alloc_enter(slab, timeout)
Trace Memory Slab alloc attempt entry.

Parameters
- slab – Memory Slab object
- timeout – Timeout period

sys_port_trace_k_mem_slab_alloc_blocking(slab, timeout)
Trace Memory Slab alloc attempt blocking.

Parameters
- slab – Memory Slab object
- timeout – Timeout period

sys_port_trace_k_mem_slab_alloc_exit(slab, timeout, ret)
Trace Memory Slab alloc attempt outcome.

Parameters
- slab – Memory Slab object
• **timeout** – Timeout period
• **ret** – Return value

```c
sys_port_trace_k_mem_slab_free_enter(slab)
```
Trace Memory Slab free entry.

**Parameters**
- **slab** – Memory Slab object

```c
sys_port_trace_k_mem_slab_free_exit(slab)
```
Trace Memory Slab free exit.

**Parameters**
- **slab** – Memory Slab object

---

**Timers**

```c
sys_port_trace_k_timer_init(timer)
```
Trace initialization of Timer.

**Parameters**
- **timer** – Timer object

```c
sys_port_trace_k_timer_start(timer, duration, period)
```
Trace Timer start.

**Parameters**
- **timer** – Timer object
- **duration** – Timer duration
- **period** – Timer period

```c
sys_port_trace_k_timer_stop(timer)
```
Trace Timer stop.

**Parameters**
- **timer** – Timer object

```c
sys_port_trace_k_timer_status_sync_enter(timer)
```
Trace Timer status sync entry.

**Parameters**
- **timer** – Timer object

```c
sys_port_trace_k_timer_status_sync_blocking(timer, timeout)
```
Trace Timer Status sync blocking.

**Parameters**
- **timer** – Timer object
- **timeout** – Timeout period
sys_port_trace_k_timer_status_sync_exit(tagger, result)
Trace Time Status sync outcome.

**Parameters**

- *timer* – Timer object
- *result* – Return value

**Object tracking**

*group* subsys_tracing_object_tracking
Object tracking.

Object tracking provides lists to kernel objects, so their existence and current status can be tracked.

The following global variables are the heads of available lists:

- _track_list_k_timer
- _track_list_k_mem_slab
- _track_list_k_sem
- _track_list_k_mutex
- _track_list_k_stack
- _track_list_k_msgq
- _track_list_k_mbox
- _track_list_k_pipe
- _track_list_k_queue
- _track_list_k_event

**Defines**

SYS_PORT_TRACK_NEXT(list)
Gets node's next element in a object tracking list.

**Parameters**

- *list* – Node to get next element from.

**Syscalls**

*group* subsys_tracing_apis_syscall
Syscall Tracing APIs.

**Defines**
sys_port_trace_syscall_enter(id, name, ...)

Trace syscall entry.

**Parameters**

- **id** – Syscall ID (as defined in the generated syscall_list.h)
- **name** – Syscall name as a token (ex: k_thread_create)
- ... – Other parameters passed to the syscall

sys_port_trace_syscall_exit(id, name, ...)

Trace syscall exit.

**Parameters**

- **id** – Syscall ID (as defined in the generated syscall_list.h)
- **name** – Syscall name as a token (ex: k_thread_create)
- ... – Other parameters passed to the syscall, if the syscall has a return, the return value is the last parameter in the list

## 4.14 Resource Management

There are various situations where it's necessary to coordinate resource use at runtime among multiple clients. These include power rails, clocks, other peripherals, and binary device power management. The complexity of properly managing multiple consumers of a device in a multi-threaded system, especially when transitions may be asynchronous, suggests that a shared implementation is desirable.

Zephyr provides managers for several coordination policies. These managers are embedded into services that use them for specific functions.

- **On-Off Manager**

### 4.14.1 On-Off Manager

An on-off manager supports an arbitrary number of clients of a service which has a binary state. Example applications are power rails, clocks, and binary device power management.

The manager has the following properties:

- The stable states are off, on, and error. The service always begins in the off state. The service may also be in a transition to a given state.
- The core operations are request (add a dependency) and release (remove a dependency). Supporting operations are reset (to clear an error state) and cancel (to reclaim client data from an in-progress transition). The service manages the state based on calls to functions that initiate these operations.
- The service transitions from off to on when first client request is received.
- The service transitions from on to off when last client release is received.
- Each service configuration provides functions that implement the transition from off to on, from on to off, and optionally from an error state to off. Transitions must be invokable from both thread and interrupt context.
- The request and reset operations are asynchronous using *Asynchronous Notifications*. Both operations may be cancelled, but cancellation has no effect on the in-progress transition.
Requests to turn on may be queued while a transition to off is in progress: when the service has turned off successfully it will be immediately turned on again (where context allows) and waiting clients notified when the start completes.

Requests are reference counted, but not tracked. That means clients are responsible for recording whether their requests were accepted, and for initiating a release only if they have previously successfully completed a request. Improper use of the API can cause an active client to be shut out, and the manager does not maintain a record of specific clients that have been granted a request.

Failures in executing a transition are recorded and inhibit further requests or releases until the manager is reset. Pending requests are notified (and cancelled) when errors are discovered.

Transition operation completion notifications are provided through *Asynchronous Notifications*. Clients and other components interested in tracking all service state changes, including when a service begins turning off or enters an error state, can be informed of state transitions by registering a monitor with `onoff_monitor_register()`. Notification of changes are provided before issuing completion notifications associated with the new state.

**Note:** A generic API may be implemented by multiple drivers where the common case is asynchronous. The on-off client structure may be an appropriate solution for the generic API. Where drivers that can guarantee synchronous context-independent transitions a driver may use `onoff_sync_service` and its supporting API rather than `onoff_manager`, with only a small reduction in functionality (primarily no support for the monitor API).

```c
#define group resource_mgmt_onoff_apis

#define ONOFF_FLAG_ERROR   // Flag indicating an error state.
#define ONOFF_RESET()      // Error states are cleared using onoff_reset().

#define ONOFF_STATE_MASK   // Mask used to isolate bits defining the service state.
#define ONOFF_STATE_OFF    // Mask a value with this then test for ONOFF_FLAG_ERROR to determine whether
#define ONOFF_STATE_ON     // the machine has an unfixed error, or compare against ONOFF_STATE_ON,
#define ONOFF_STATE_TO_ON  // ONOFF_STATE_OFF, ONOFF_STATE_TO_ON, ONOFF_STATE_TO_OFF, or
#define ONOFF_STATE_TO_OFF // ONOFF_STATE_RESETTING.
#define ONOFF_STATE_ERROR  // Value exposed by ONOFF_STATE_MASK when service is off.

#define ONOFF_STATE_OFF    // Value exposed by ONOFF_STATE_MASK when service is on.

#define ONOFF_STATE_ERROR  // Value exposed by ONOFF_STATE_MASK when the service is in an error state (and not
#define ONOFF_STATE_ERROR  // in the process of resetting its state).
```

ONOFF_STATE_TO_ON
Value exposed by ONOFF_STATE_MASK when service is transitioning to on.

ONOFF_STATE_TO_OFF
Value exposed by ONOFF_STATE_MASK when service is transitioning to off.

ONOFF_STATE_RESETTING
Value exposed by ONOFF_STATE_MASK when service is in the process of resetting.

ONOFF_TRANSITIONS_INITIALIZER(_start, _stop, _reset)
Initializer for a onoff_transitions object.

Parameters
- _start – a function used to transition from off to on state.
- _stop – a function used to transition from on to off state.
- _reset – a function used to clear errors and force the service to an off state. Can be null.

ONOFF_CLIENT_EXTENSION_POS
Identify region of sys_notify flags available for containing services.
Bits of the flags field of the sys_notify structure contained within the queued_operation structure at and above this position may be used by extensions to the onoff_client structure.
These bits are intended for use by containing service implementations to record client-specific information and are subject to other conditions of use specified on the sys_notify API.

Typedefs

typedef void (*onoff_notify_fn)(struct onoff_manager *mgr, int res)
Signature used to notify an on-off manager that a transition has completed.
Functions of this type are passed to service-specific transition functions to be used to report the completion of the operation. The functions may be invoked from any context.

Param mgr
the manager for which transition was requested.

Param res
the result of the transition. This shall be non-negative on success, or a negative error code. If an error is indicated the service shall enter an error state.

typedef void (*onoff_transition_fn)(struct onoff_manager *mgr, onoff_notify_fn notify)
Signature used by service implementations to effect a transition.
Service definitions use two required function pointers of this type to be notified that a transition is required, and a third optional one to reset the service when it is in an error state.
The start function will be called only from the off state.
The stop function will be called only from the on state.
The reset function (where supported) will be called only when `onoff_has_error()` returns true.

**Note:** All transitions functions must be isr-ok.

**Param mgr**
the manager for which transition was requested.

**Param notify**
the function to be invoked when the transition has completed. If the transition is synchronous, notify shall be invoked by the implementation before the transition function returns. Otherwise the implementation shall capture this parameter and invoke it when the transition completes.

typedef void (*onoff_client_callback)(struct onoff_manager *mgr, struct onoff_client *cli, uint32_t state, int res)

Signature used to notify an on-off service client of the completion of an operation.

These functions may be invoked from any context including pre-kernel, ISR, or cooperative or pre-emptible threads. Compatible functions must be isr-ok and not sleep.

**Param mgr**
the manager for which the operation was initiated. This may be null if the on-off service uses synchronous transitions.

**Param cli**
the client structure passed to the function that initiated the operation.

**Param state**
the state of the machine at the time of completion, restricted by ONOFF_STATE_MASK. ONOFF_FLAG_ERROR must be checked independently of whether res is negative as a machine error may indicate that all future operations except `onoff_reset()` will fail.

**Param res**
the result of the operation. Expected values are service-specific, but the value shall be non-negative if the operation succeeded, and negative if the operation failed. If res is negative ONOFF_FLAG_ERROR will be set in state, but if res is non-negative ONOFF_FLAG_ERROR may still be set in state.

typedef void (*onoff_monitor_callback)(struct onoff_manager *mgr, struct onoff_monitor *mon, uint32_t state, int res)

Signature used to notify a monitor of an onoff service of errors or completion of a state transition.

This is similar to onoff_client_callback but provides information about all transitions, not just ones associated with a specific client. Monitor callbacks are invoked before any completion notifications associated with the state change are made.

These functions may be invoked from any context including pre-kernel, ISR, or cooperative or pre-emptible threads. Compatible functions must be isr-ok and not sleep.

The callback is permitted to unregister itself from the manager, but must not register or unregister any other monitors.

**Param mgr**
the manager for which a transition has completed.

**Param mon**
the monitor instance through which this notification arrived.
Param state
the state of the machine at the time of completion, restricted by ONOFF_STATE_MASK. All valid states may be observed.

Param res
the result of the operation. Expected values are service- and state-specific, but the value shall be non-negative if the operation succeeded, and negative if the operation failed.

Functions

int onoff_manager_init(struct onoff_manager *mgr, const struct onoff_transitions *transitions)
Initialize an on-off service to off state.
This function must be invoked exactly once per service instance, by the infrastructure that provides the service, and before any other on-off service API is invoked on the service.
This function should never be invoked by clients of an on-off service.

Parameters
• mgr – the manager definition object to be initialized.
• transitions – pointer to a structure providing transition functions. The referenced object must persist as long as the manager can be referenced.

Return values
• 0 – on success
• -EINVAL – if start, stop, or flags are invalid

static inline bool onoff_has_error(const struct onoff_manager *mgr)
Test whether an on-off service has recorded an error.
This function can be used to determine whether the service has recorded an error. Errors may be cleared by invoking onoff_reset().
This is an unlocked convenience function suitable for use only when it is known that no other process might invoke an operation that transitions the service between an error and non-error state.

Returns
true if and only if the service has an uncleared error.

int onoff_request(struct onoff_manager *mgr, struct onoff_client *cli)
Request a reservation to use an on-off service.
The return value indicates the success or failure of an attempt to initiate an operation to request the resource be made available. If initiation of the operation succeeds the result of the request operation is provided through the configured client notification method, possibly before this call returns.
Note that the call to this function may succeed in a case where the actual request fails. Always check the operation completion result.

Parameters
• mgr – the manager that will be used.
• cli – a non-null pointer to client state providing instructions on synchronous expectations and how to notify the client when the request completes. Behavior is undefined if client passes a pointer object associated with an incomplete service operation.
Return values
- **non-negative** – the observed state of the machine at the time the request was processed, if successful.
- **-EIO** – if service has recorded an an error.
- **-EINVAL** – if the parameters are invalid.
- **-EAGAIN** – if the reference count would overflow.

```c
int onoff_release(struct onoff_manager *mgr)
```

Release a reserved use of an on-off service.

This synchronously releases the caller’s previous request. If the last request is released the manager will initiate a transition to off, which can be observed by registering an `onoff_monitor`.

**Note:** Behavior is undefined if this is not paired with a preceding `onoff_request()` call that completed successfully.

Parameters
- **mgr** – the manager for which a request was successful.

Return values
- **non-negative** – the observed state (ONOFF_STATE_ON) of the machine at the time of the release, if the release succeeds.
- **-EIO** – if service has recorded an an error.
- **-ENOTSUP** – if the machine is not in a state that permits release.

```c
int onoff_cancel(struct onoff_manager *mgr, struct onoff_client *cli)
```

Attempt to cancel an in-progress client operation.

It may be that a client has initiated an operation but needs to shut down before the operation has completed. For example, when a request was made and the need is no longer present.

Cancelling is supported only for `onoff_request()` and `onoff_reset()` operations, and is a synchronous operation. Be aware that any transition that was initiated on behalf of the client will continue to progress to completion: it is only notification of transition completion that may be eliminated. If there are no active requests when a transition to on completes the manager will initiate a transition to off.

Client notification does not occur for cancelled operations.

Parameters
- **mgr** – the manager for which an operation is to be cancelled.
- **cli** – a pointer to the same client state that was provided when the operation to be cancelled was issued.

Return values
- **non-negative** – the observed state of the machine at the time of the cancellation, if the cancellation succeeds. On successful cancellation ownership of *cli reverts to the client.
- **-EINVAL** – if the parameters are invalid.
- **-EALREADY** – if cli was not a record of an uncompleted notification at the time the cancellation was processed. This likely indicates that the operation and client notification had already completed.
static inline int onoff_cancel_or_release(struct onoff_manager *mgr, struct onoff_client *cli)

Helper function to safely cancel a request.

Some applications may want to issue requests on an asynchronous event (such as connection to a USB bus) and to release on a paired event (such as loss of connection to a USB bus). Applications cannot precisely determine that an in-progress request is still pending without using onoff_monitor and carefully avoiding race conditions.

This function is a helper that attempts to cancel the operation and issues a release if cancellation fails because the request was completed. This synchronously ensures that ownership of the client data reverts to the client so is available for a future request.

**Parameters**

- `mgr` – the manager for which an operation is to be cancelled.
- `cli` – a pointer to the same client state that was provided when onoff_request() was invoked. Behavior is undefined if this is a pointer to client data associated with an onoff_reset() request.

**Return values**

- `ONOFF_STATE_TO_ON` – if the cancellation occurred before the transition completed.
- `ONOFF_STATE_ON` – if the cancellation occurred after the transition completed.
- `-EINVAL` – if the parameters are invalid.
- `negative` – other errors produced by onoff_release().

```c
int onoff_reset(struct onoff_manager *mgr, struct onoff_client *cli)
```

Clear errors on an on-off service and reset it to its off state.

A service can only be reset when it is in an error state as indicated by onoff_has_error().

The return value indicates the success or failure of an attempt to initiate an operation to reset the resource. If initiation of the operation succeeds the result of the reset operation itself is provided through the configured client notification method, possibly before this call returns. Multiple clients may request a reset; all are notified when it is complete.

Note that the call to this function may succeed in a case where the actual reset fails. Always check the operation completion result.

**Note:** Due to the conditions on state transition all incomplete asynchronous operations will have been informed of the error when it occurred. There need be no concern about dangling requests left after a reset completes.

**Parameters**

- `mgr` – the manager to be reset.
- `cli` – pointer to client state, including instructions on how to notify the client when reset completes. Behavior is undefined if cli references an object associated with an incomplete service operation.

**Return values**

- `non-negative` – the observed state of the machine at the time of the reset, if the reset succeeds.
- `-ENOTSUP` – if reset is not supported by the service.
-EINVAL – if the parameters are invalid.
-EINVAL – if the service does not have a recorded error.

```c
int onoff_monitor_register(struct onoff_manager *mgr, struct onoff_monitor *mon)
```

Add a monitor of state changes for a manager.

**Parameters**
- `mgr` – the manager for which a state changes are to be monitored.
- `mon` – a linkable node providing a non-null callback to be invoked on state changes.

**Returns**
non-negative on successful addition, or a negative error code.

```c
int onoff_monitor_unregister(struct onoff_manager *mgr, struct onoff_monitor *mon)
```

Remove a monitor of state changes from a manager.

**Parameters**
- `mgr` – the manager for which a state changes are to be monitored.
- `mon` – a linkable node providing the callback to be invoked on state changes.

**Returns**
non-negative on successful removal, or a negative error code.

```c
int onoff_sync_lock(struct onoff_sync_service *srv, k_spinlock_key_t *keyp)
```

Lock a synchronous onoff service and provide its state.

**Note:** If an error state is returned it is the caller’s responsibility to decide whether to preserve it (finalize with the same error state) or clear the error (finalize with a non-error result).

**Parameters**
- `srv` – pointer to the synchronous service state.
- `keyp` – pointer to where the lock key should be stored

**Returns**
negative if the service is in an error state, otherwise the number of active requests at the time the lock was taken. The lock is held on return regardless of whether a negative state is returned.

```c
int onoff_sync_finalize(struct onoff_sync_service *srv, k_spinlock_key_t key, struct onoff_client *cli, int res, bool on)
```

Process the completion of a transition in a synchronous service and release lock.
This function updates the service state on the `res` and `on` parameters then releases the lock. If `cli` is not null it finalizes the client notification using `res`.
If the service was in an error state when locked, and `res` is non-negative when finalized, the count is reset to zero before completing finalization.

**Parameters**
- `srv` – pointer to the synchronous service state
- `key` – the key returned by the preceding invocation of `onoff_sync_lock()`.
• cli – pointer to the onoff client through which completion information is returned. If a null pointer is passed only the state of the service is updated. For compatibility with the behavior of callbacks used with the manager API cli must be null when on is false (the manager does not support callbacks when turning off devices).

• res – the result of the transition. A negative value places the service into an error state. A non-negative value increments or decrements the reference count as specified by on.

• on – Only when res is non-negative, the service reference count will be incremented if on is true, and decremented if on is false.

Returns
negative if the service is left or put into an error state, otherwise the number of active requests at the time the lock was released.

struct onoff_transitions
#include <onoff.h> On-off service transition functions.

Public Members

onoff_transition_fn start
Function to invoke to transition the service to on.

onoff_transition_fn stop
Function to invoke to transition the service to off.

onoff_transition_fn reset
Function to force the service state to reset, where supported.

struct onoff_manager
#include <onoff.h> State associated with an on-off manager.
No fields in this structure are intended for use by service providers or clients. The state is to be initialized once, using onoff_manager_init(), when the service provider is initialized. In case of error it may be reset through the onoff_reset() API.

Public Members

sys_slist_t clients
List of clients waiting for request or reset completion notifications.

sys_slist_t monitors
List of monitors to be notified of state changes including errors and transition completion.

const struct onoff_transitions *transitions
Transition functions.

struct k_spinlock lock
Mutex protection for other fields.
int last_res
   The result of the last transition.

uint16_t flags
   Flags identifying the service state.

uint16_t refs
   Number of active clients for the service.

struct onoff_client
   #include <onoff.h> State associated with a client of an on-off service.

Objects of this type are allocated by a client, which is responsible for zero-initializing the node field and invoking the appropriate sys_notify init function to configure notification.

Control of the object content transfers to the service provider when a pointer to the object is passed to any on-off manager function. While the service provider controls the object the client must not change any object fields. Control reverts to the client concurrent with release of the owned sys_notify structure, or when indicated by an onoff_cancel() return value.

After control has reverted to the client the notify field must be reinitialized for the next operation.

Public Members

struct sys_notify notify
   Notification configuration.

struct onoff_monitor
   #include <onoff.h> Registration state for notifications of onoff service transitions.

Any given onoff_monitor structure can be associated with at most one onoff_manager instance.

Public Members

sys_snode_t node
   Links the client into the set of waiting service users.
   This must be zero-initialized.

onoff_monitor_callback callback
   Callback to be invoked on state change.
   This must not be null.

struct onoff_sync_service
   #include <onoff.h> State used when a driver uses the on-off service API for synchronous operations.
This is useful when a subsystem API uses the on-off API to support asynchronous operations but the transitions required by a particular driver are isr-ok and not sleep. It serves as a substitute for onoff_manager, with locking and persisted state updates supported by onoff_sync_lock() and onoff_sync_finalize().

Public Members

struct k_spinlock lock
  Mutex protection for other fields.

int32_t count
  Negative is error, non-negative is reference count.

4.15 Memory Attributes

It is possible in the devicetree to mark the memory regions with attributes by using the zephyr, memory-attr property. This property and the related memory region can then be retrieved at run-time by leveraging a provided helper library.

The set of general attributes that can be specified in the property are defined and explained in include/zephyr/dt-bindings/memory-attr/memory-attr.h.

For example, to mark a memory region in the devicetree as non-volatile, cacheable, out-of-order:

```c
mem: memory@10000000 {
  compatible = "mmio-sram";
  reg = <0x10000000 0x1000>;
  zephyr,memory-attr = <( DT_MEM_NON_VOLATILE | DT_MEM_CACHEABLE | DT_MEM_OOO )>;
};
```

Note: The zephyr,memory-attr usage does not result in any memory region actually created. When it is needed to create an actual section out of the devicetree defined memory region, it is possible to use the compatible zephyr,memory-region that will result (only when supported by the architecture) in a new linker section and region.

The zephyr,memory-attr property can also be used to set architecture-specific and software-specific custom attributes that can be interpreted at run time. This is leveraged, among other things, to create MPU regions out of devicetree defined memory regions, for example:

```c
mem: memory@10000000 {
  compatible = "mmio-sram";
  reg = <0x10000000 0x1000>;
  zephyr,memory-region = "NOCACHE_REGION";
  zephyr,memory-attr = <( DT_MEM_ARM(ATTR_MPU_RAM_NOCACHE) )>;
};
```

See include/zephyr/dt-bindings/memory-attr/memory-attr-arm.h and Arm Cortex-M Developer Guide for more details about MPU usage.

The conventional and recommended way to deal and manage with memory regions marked with attributes is by using the provided mem-attr helper library by enabling CONFIG_MEM_ATTR. When this option is enabled the list of memory regions and their attributes are compiled in a user-accessible array and a set of functions is made available that can be used to query, probe and act on regions and attributes (see next section for more details).
**Note:** The `zephyr, memory-attr` property is only a descriptive property of the capabilities of the associated memory region, but it does not result in any actual setting for the memory to be set. The user, code or subsystem willing to use this information to do some work (for example creating an MPU region out of the property) must use either the provided `mem-attr` library or the usual devicetree helpers to perform the required work / setting.

A test for the `mem-attr` library and its usage is provided in `tests/subsys/mem_mgmt/mem_attr/`.

### 4.15.1 Migration guide from `zephyr, memory-region-mpu`

When the `zephyr, memory-attr` property was introduced, the `zephyr, memory-region-mpu` property was removed and deprecated.

The developers that are still using the deprecated property can move to the new one by renaming the property and changing its value according to the following list:

```
"RAM" -> <( DT_ARM_MPU(ATTR_MPU_RAM) )>
"RAM_NOCACHE" -> <( DT_ARM_MPU(ATTR_MPU_RAM_NOCACHE) )>
"FLASH" -> <( DT_ARM_MPU(ATTR_MPU_FLASH) )>
"PPB" -> <( DT_ARM_MPU(ATTR_MPU_PPB) )>
"IO" -> <( DT_ARM_MPU(ATTR_MPU_IO) )>
"EXTMEM" -> <( DT_ARM_MPU(ATTR_MPU_EXTMEM) )>
```

### 4.15.2 Memory Attributes Heap Allocator

It is possible to leverage the memory attribute property `zephyr, memory-attr` to define and create a set of memory heaps from which the user can allocate memory from with certain attributes / capabilities.

When the `CONFIG_MEM_ATTR_HEAP` is set, every region marked with one of the memory attributes listed in `include/zephyr/dt-bindings/memory-attr/memory-attr-sw.h` is added to a pool of memory heaps used for dynamic allocation of memory buffers with certain attributes.

Here a non exhaustive list of possible attributes:

```
DT_MEM_SW_ALLOC_CACHE
DT_MEM_SW_ALLOC_NON_CACHE
DT_MEM_SW_ALLOC_DMA
```

For example we can define several memory regions with different attributes and use the appropriate attribute to indicate that it is possible to dynamically allocate memory from those regions:

```c
mem_cacheable: memory@10000000 {
    compatible = "mmio-sram";
    reg = <0x10000000 0x1000>
    zephyr, memory-attr = <( DT_MEM_CACHEABLE | DT_MEM_SW_ALLOC_CACHE )>;
};

mem_non_cacheable: memory@20000000 {
    compatible = "mmio-sram";
    reg = <0x20000000 0x1000>
    zephyr, memory-attr = <( DT_MEM_NON_CACHEABLE | ATTR_SW_ALLOC_NON_CACHE )>;
};

mem_cacheable_big: memory@30000000 {
    compatible = "mmio-sram";
    reg = <0x30000000 0x1000>
};
```

(continues on next page)
zephyr,memory-attr = <( DT_MEM_CACHEABLE | DT_MEM_OOO | DT_MEM_SW_ALLOC_CACHE )>;

mem_cacheable_dma: memory@40000000 {
    compatible = "mmio-sram";
    reg = <0x40000000 0x10000>
    zephyr,memory-attr = <( DT_MEM_CACHEABLE | DT_MEM_DMA | DT_MEM_SW_ALLOC_CACHE | DT_MEM_SW_ALLOC_DMA )>;
}

The user can then dynamically carve memory out of those regions using the provided functions, the library will take care of allocating memory from the correct heap depending on the provided attribute and size:

```
// Init the pool
mem_attr_heap_pool_init();

// Allocate 0x100 bytes of cacheable memory from `mem_cacheable`
block = mem_attr_heap_alloc(DT_MEM_SW_ALLOC_CACHE, 0x100);

// Allocate 0x200 bytes of non-cacheable memory aligned to 32 bytes
// from `mem_non_cacheable`
block = mem_attr_heap_aligned_alloc(ATTR_SW_ALLOC_NON_CACHE, 0x100, 32);

// Allocate 0x100 bytes of cacheable and dma-able memory from `mem_cacheable_dma`
block = mem_attr_heap_alloc(DT_MEM_SW_ALLOC_CACHE | DT_MEM_SW_ALLOC_DMA, 0x100);
```

When several regions are marked with the same attributes, the memory is allocated:

1. From the regions where the zephyr,memory-attr property has the requested property (or properties).
2. Among the regions as at point 1, from the smallest region if there is any unallocated space left for the requested size
3. If there is not enough space, from the next bigger region able to accommodate the requested size

The following example shows the point 3:

```
// This memory is allocated from `mem_non_cacheable`
block = mem_attr_heap_alloc(DT_MEM_SW_ALLOC_CACHE, 0x100);

// This memory is allocated from `mem_cacheable_big`
block = mem_attr_heap_alloc(DT_MEM_SW_ALLOC_CACHE, 0x5000);
```

**Note:** The framework is assuming that the memory regions used to create the heaps are usable by the code and available at init time. The user must take of initializing and setting the memory area before calling `mem_attr_heap_pool_init()`.

That means that the region must be correctly configured in terms of MPU / MMU (if needed) and that an actual heap can be created out of it, for example by leveraging the zephyr,memory-region property to create a proper linker section to accommodate the heap.

### 4.15.3 API Reference

**group memory_attr_interface**

Memory-Attr Interface.
Defines

**DT_MEMORY_ATTR_FOREACH_STATUS_OKAY_NODE(fn)**
Invokes fn for every status okay node in the tree with property zephyr,memory-attr

The macro fn must take one parameter, which will be a node identifier with the zephyr,memory-attr property. The macro is expanded once for each node in the tree with status okay. The order that nodes are visited in is not specified.

**Parameters**
- fn – macro to invoke

Functions

**size_t mem_attr_get_regions(const struct mem_attr_region_t **region)**
Get the list of memory regions.

Get the list of enabled memory regions with their memory-attribute as gathered by DT.

**Parameters**
- region – Pointer to pointer to the list of memory regions.

**Return values**
- Number – of memory regions returned in the parameter.

**int mem_attr_check_buf(void *addr, size_t size, uint32_t attr)**
Check if a buffer has correct size and attributes.

This function is used to check if a given buffer with a given set of attributes fully match a memory region in terms of size and attributes.

This is usually used to verify that a buffer has the expected attributes (for example the buffer is cacheable / non-cacheable or belongs to RAM / FLASH, etc…) and it has been correctly allocated.

The expected set of attributes for the buffer is and-matched against the full set of attributes for the memory region it belongs to (bitmask). So the buffer is considered matching when at least that set of attributes are valid for the memory region (but the region can be marked also with other attributes besides the one passed as parameter).

**Parameters**
- addr – Virtual address of the user buffer.
- size – Size of the user buffer.
- attr – Expected / desired attribute for the buffer.

**Return values**
- 0 – if the buffer has the correct size and attribute.
- -ENOSYS – if the operation is not supported (for example if the MMU is enabled).
- -ENOTSUP – if the wrong parameters were passed.
- -EINVAL – if the buffer has the wrong set of attributes.
- -ENOSPC – if the buffer is too big for the region it belongs to.
- -ENOBUFS – if the buffer is entirely allocated outside a memory region.
struct mem_attr_region_t
#include <mem_attr.h> memory-attr region structure.
This structure represents the data gathered from DT about a memory-region marked
with memory attributes.

Public Members

const char *dt_name
Memory node full name.

uintptr_t dt_addr
Memory region physical address.

size_t dt_size
Memory region size.

uint32_t dt_attr
Memory region attributes.

group memory_attr_heap
Memory heaps based on memory attributes.

Functions

int mem_attr_heap_pool_init(void)
Init the memory pool.
This must be the first function to be called to initialize the memory pools from all the
memory regions with the a software attribute.

Return values
• 0 – on success.
• -EALREADY – if the pool was already initialized.
• -ENOMEM – too many regions already allocated.

void *mem_attr_heap_alloc(uint32_t attr, size_t bytes)
Allocate memory with a specified attribute and size.
Allocates a block of memory of the specified size in bytes and with a specified capability
attribute. The attribute is used to select the correct memory heap to allocate memory
from.

Parameters
• attr – capability / attribute requested for the memory block.
• bytes – requested size of the allocation in bytes.

Return values
• ptr – a valid pointer to the allocated memory.
• NULL – if no memory is available with that attribute and size.
void *mem_attr_heap_aligned_alloc(uint32_t attr, size_t align, size_t bytes)
Allocate aligned memory with a specified attribute, size and alignment.
Allocates a block of memory of the specified size in bytes and with a specified capability / attribute. Takes an additional parameter specifying a power of two alignment in bytes.

Parameters
• attr – capability / attribute requested for the memory block.
• align – power of two alignment for the returned pointer in bytes.
• bytes – requested size of the allocation in bytes.

Return values
• ptr – a valid pointer to the allocated memory.
• NULL – if no memory is available with that attribute and size.

void mem_attr_heap_free(void *block)
Free the allocated memory.
Used to free the passed block of memory that must be the return value of a previously call to mem_attr_heap_alloc or mem_attr_heap_aligned_alloc.

Parameters
• block – block to free, must be a pointer to a block allocated by mem_attr_heap_alloc or mem_attr_heap_aligned_alloc.

const struct mem_attr_region_t *mem_attr_heap_get_region(void *addr)
Get a specific memory region descriptor for a provided address.
Finds the memory region descriptor struct controlling the provided pointer.

Parameters
• addr – address to be found, must be a pointer to a block allocated by mem_attr_heap_alloc or mem_attr_heap_aligned_alloc.

Return values
• str – pointer to a memory region structure the address belongs to.

4.16 Modbus

Modbus is an industrial messaging protocol. The protocol is specified for different types of networks or buses. Zephyr OS implementation supports communication over serial line and may be used with different physical interfaces, like RS485 or RS232. TCP support is not implemented directly, but there are helper functions to realize TCP support according to the application's needs.

Modbus communication is based on client/server model. Only one client may be present on the bus. Client can communicate with several server devices. Server devices themselves are passive and must not send requests or unsolicited responses. Services requested by the client are specified by function codes (FCxx), and can be found in the specification or documentation of the API below.

Zephyr RTOS implementation supports both client and server roles.

More information about Modbus and Modbus RTU can be found on the website MODBUS Protocol Specifications.
4.16.1 Samples

- modbus-rtu-server and modbus-rtu-client samples give the possibility to try out RTU server and RTU client implementation with an evaluation board.
- modbus-tcp-server sample is a simple Modbus TCP server.
- modbus-gateway sample shows how to build a TCP to serial line gateway with Zephyr OS.

4.16.2 API Reference

Related code samples

**Modbus RTU client**
Communicate with a Modbus RTU server.

**Modbus RTU server**
Implement a Modbus RTU server exposing Modbus commands to control LEDs.

**Modbus TCP server**
Implement a Modbus TCP server exposing Modbus commands to control LEDs.

**Modbus TCP-to-serial gateway**
Implement a gateway between an Ethernet TCP-IP network and a Modbus serial line.

```group modbus```
MODBUS transport protocol API.

**Modbus exception codes**

MODBUS_EXC_NONE
No exception.

MODBUS_EXC_ILLEGAL_FC
Illegal function code.

MODBUS_EXC_ILLEGAL_DATA_ADDR
Illegal data address.

MODBUS_EXC_ILLEGAL_DATA_VAL
Illegal data value.

MODBUS_EXC_SERVER_DEVICE_FAILURE
Server device failure.

MODBUS_EXC_ACK
Acknowledge.

MODBUS_EXC_SERVER_DEVICE_BUSY
Server device busy.
MODBUS_EXC_MEM_PARITY_ERROR
Memory parity error.

MODBUS_EXC_GW_PATH_UNAVAILABLE
Gateway path unavailable.

MODBUS_EXC_GW_TARGET_FAILED_TO_RESP
Gateway target device failed to respond.

Defines

MODBUS_MBAP_LENGTH
Length of MBAP Header.

MODBUS_MBAP_AND_FC_LENGTH
Length of MBAP Header plus function code.

MODBUS_CUSTOM_FC_DEFINE(name, user_cb, user_fc, userdata)
INTERNAL_HIDDEN.
Helper macro for initializing custom function code structs

Typedefs

typedef int (*modbus_raw_cb_t)(const int iface, const struct modbus_adu *adu, void *user_data)
ADU raw callback function signature.

Param iface
Modbus RTU interface index

Param adu
Pointer to the RAW ADU struct to send

Param user_data
Pointer to the user data

Retval 0
If transfer was successful

typedef bool (*modbus_custom_cb_t)(const int iface, const struct modbus_adu *const rx_adu, struct modbus_adu *const tx_adu, uint8_t *const excep_code, void *const user_data)
Custom function code handler function signature.

Modbus allows user defined function codes which can be used to extend the base protocol. These callbacks can also be used to implement function codes currently not supported by Zephyr’s Modbus subsystem.

If an error occurs during the handling of the request, the handler should signal this by setting excep_code to a modbus exception code.

User data pointer can be used to pass state between subsequent calls to the handler.

Param iface
Modbus interface index
Param rx_adu
  Pointer to the received ADU struct

Param tx_adu
  Pointer to the outgoing ADU struct

Param excep_code
  Pointer to possible exception code

Param user_data
  Pointer to user data

Retval true
  If response should be sent, false otherwise

Enums

enum modbus_mode
  Modbus interface mode.
  Values:

  enumerator MODBUS_MODE_RTU
    Modbus over serial line RTU mode.

  enumerator MODBUS_MODE_ASCII
    Modbus over serial line ASCII mode.

  enumerator MODBUS_MODE_RAW
    Modbus raw ADU mode.

Functions

int modbus_read_coils(const int iface, const uint8_t unit_id, const uint16_t start_addr,
                       uint8_t *const coil_tbl, const uint16_t num_coils)

Coil read (FC01)
Sends a Modbus message to read the status of coils from a server.

Parameters

  • iface – Modbus interface index
  • unit_id – Modbus unit ID of the server
  • start_addr – Coil starting address
  • coil_tbl – Pointer to an array of bytes containing the value of the coils read. The format is:

<table>
<thead>
<tr>
<th>MSB</th>
<th>B7</th>
<th>B6</th>
<th>B5</th>
<th>B4</th>
<th>B3</th>
<th>B2</th>
<th>B1</th>
<th>LSB</th>
</tr>
</thead>
<tbody>
<tr>
<td>coil_tbl[0]</td>
<td>#8</td>
<td>#7</td>
<td>#1</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>coil_tbl[1]</td>
<td>#16</td>
<td>#15</td>
<td>#9</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>...</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
Note that the array that will be receiving the coil values must be greater than or equal to: \((num\_coils - 1) / 8 + 1\)

- \(num\_coils\) – Quantity of coils to read

Return values

\[0\] – If the function was successful

\[
\text{int modbus_read_dinputs}(\text{const int iface, const uint8\_t unit\_id, const uint16\_t start\_addr, uint8\_t *const di\_tbl, const uint16\_t num\_di})
\]

Read discrete inputs (FC02)

Sends a Modbus message to read the status of discrete inputs from a server.

Parameters

- \(\text{iface}\) – Modbus interface index
- \(\text{unit\_id}\) – Modbus unit ID of the server
- \(\text{start\_addr}\) – Discrete input starting address
- \(\text{di\_tbl}\) – Pointer to an array that will receive the state of the discrete inputs. The format of the array is as follows:

<table>
<thead>
<tr>
<th>MSB</th>
<th>LSB</th>
</tr>
</thead>
<tbody>
<tr>
<td>B7</td>
<td>B6</td>
</tr>
<tr>
<td>B5</td>
<td>B4</td>
</tr>
<tr>
<td>B3</td>
<td>B2</td>
</tr>
<tr>
<td>B1</td>
<td>B0</td>
</tr>
</tbody>
</table>

\[
\text{di\_tbl}[0] \quad \#8 \quad \#7 \quad \#1
\]
\[
\text{di\_tbl}[1] \quad \#16 \quad \#15 \quad \#9
\]

Note that the array that will be receiving the discrete input values must be greater than or equal to: \((num\_di - 1) / 8 + 1\)

- \(num\_di\) – Quantity of discrete inputs to read

Return values

\[0\] – If the function was successful

\[
\text{int modbus_read_holding\_regs}(\text{const int iface, const uint8\_t unit\_id, const uint16\_t start\_addr, uint16\_t *const reg\_buf, const uint16\_t num\_regs})
\]

Read holding registers (FC03)

Sends a Modbus message to read the value of holding registers from a server.

Parameters

- \(\text{iface}\) – Modbus interface index
- \(\text{unit\_id}\) – Modbus unit ID of the server
- \(\text{start\_addr}\) – Register starting address
- \(\text{reg\_buf}\) – Is a pointer to an array that will receive the current values of the holding registers from the server. The array pointed to by ‘reg\_buf’ needs to be able to hold at least ‘num\_regs’ entries.
- \(\text{num\_regs}\) – Quantity of registers to read

Return values

\[0\] – If the function was successful

\[
\text{int modbus_read_input\_regs}(\text{const int iface, const uint8\_t unit\_id, const uint16\_t start\_addr, uint16\_t *const reg\_buf, const uint16\_t num\_regs})
\]
Read input registers (FC04)
Sends a Modbus message to read the value of input registers from a server.

**Parameters**
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
- start_addr – Register starting address
- reg_buf – Is a pointer to an array that will receive the current value of the holding registers from the server. The array pointed to by `reg_buf` needs to be able to hold at least `num_regs` entries.
- num_regs – Quantity of registers to read

**Return values**
- 0 – If the function was successful

```c
int modbus_write_coil(const int iface, const uint8_t unit_id, const uint16_t coil_addr, const bool coil_state)
```

Write single coil (FC05)
Sends a Modbus message to write the value of single coil to a server.

**Parameters**
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
- coil_addr – Coils starting address
- coil_state – Is the desired state of the coil

**Return values**
- 0 – If the function was successful

```c
int modbus_write_holding_reg(const int iface, const uint8_t unit_id, const uint16_t start_addr, const uint16_t reg_val)
```

Write single holding register (FC06)
Sends a Modbus message to write the value of single holding register to a server unit.

**Parameters**
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
- start_addr – Coils starting address
- reg_val – Desired value of the holding register

**Return values**
- 0 – If the function was successful

```c
int modbus_request_diagnostic(const int iface, const uint8_t unit_id, const uint16_t sfunc, const uint16_t data, uint16_t *data_out)
```

Read diagnostic (FC08)
Sends a Modbus message to perform a diagnostic function of a server unit.

**Parameters**
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
• `sfunc` – Diagnostic sub-function code
• `data` – Sub-function data
• `data_out` – Pointer to the data value

**Return values**
0 – If the function was successful

```c
int modbus_write_coils(const int iface, const uint8_t unit_id, const uint16_t start_addr, uint8_t *const coil_tbl, const uint16_t num_coils)
```

Write coils (FC15)
Sends a Modbus message to write to coils on a server unit.

**Parameters**
• `iface` – Modbus interface index
• `unit_id` – Modbus unit ID of the server
• `start_addr` – Coils starting address
• `coil_tbl` – Pointer to an array of bytes containing the value of the coils to write. The format is:

<table>
<thead>
<tr>
<th>MSB</th>
<th>B7</th>
<th>B6</th>
<th>B5</th>
<th>B4</th>
<th>B3</th>
<th>B2</th>
<th>B1</th>
<th>B0</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

```
coil_tbl[0]    #8  #7  #1
coil_tbl[1]    #16 #15 #9
```

Note that the array that will be receiving the coil values must be greater than or equal to: `(num_coils - 1) / 8 + 1`

• `num_coils` – Quantity of coils to write

**Return values**
0 – If the function was successful

```c
int modbus_write_holding_regs(const int iface, const uint8_t unit_id, const uint16_t start_addr, uint16_t *const reg_buf, const uint16_t num_regs)
```

Write holding registers (FC16)
Sends a Modbus message to write to integer holding registers to a server unit.

**Parameters**
• `iface` – Modbus interface index
• `unit_id` – Modbus unit ID of the server
• `start_addr` – Register starting address
• `reg_buf` – Is a pointer to an array containing the value of the holding registers to write. Note that the array containing the register values must be greater than or equal to ‘num_regs’
• `num_regs` – Quantity of registers to write

**Return values**
0 – If the function was successful

```c
int modbus_read_holding_regs_fp(const int iface, const uint8_t unit_id, const uint16_t start_addr, float *const reg_buf, const uint16_t num_regs)
```
Read floating-point holding registers (FC03)
Sends a Modbus message to read the value of floating-point holding registers from a
server unit.

Parameters
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
- start_addr – Register starting address
- reg_buf – Is a pointer to an array that will receive the current values of
the holding registers from the server. The array pointed to by ‘reg_buf’
needs to be able to hold at least ‘num_regs’ entries.
- num_regs – Quantity of registers to read

Return values
0 – If the function was successful

int modbus_write_holding_regs_fp(const int iface, const uint8_t unit_id, const uint16_t
start_addr, float *const reg_buf, const uint16_t
num_regs)

Write floating-point holding registers (FC16)
Sends a Modbus message to write to floating-point holding registers to a server unit.

Parameters
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
- start_addr – Register starting address
- reg_buf – Is a pointer to an array containing the value of the holding
registers to write. Note that the array containing the register values must
be greater than or equal to ‘num_regs’
- num_regs – Quantity of registers to write

Return values
0 – If the function was successful

int modbus_iface_get_by_name(const char *iface_name)
Get Modbus interface index according to interface name.
If there is more than one interface, it can be used to clearly identify interfaces in the
application.

Parameters
- iface_name – Modbus interface name

Return values
Modbus – interface index or negative error value.

int modbus_init_server(const int iface, struct modbus_iface_param param)
Configure Modbus Interface as raw ADU server.

Parameters
- iface – Modbus RTU interface index
- param – Configuration parameter of the server interface

Return values
0 – If the function was successful
int modbus_init_client(const int iface, struct modbus_iface_param param)
Configure Modbus Interface as raw ADU client.

Parameters
• iface – Modbus RTU interface index
• param – Configuration parameter of the client interface

Return values
0 – If the function was successful

int modbus_disable(const uint8_t iface)
Disable Modbus Interface.
This function is called to disable Modbus interface.

Parameters
• iface – Modbus interface index

Return values
0 – If the function was successful

int modbus_raw_submit_rx(const int iface, const struct modbus_adu *adu)
Submit raw ADU.

Parameters
• iface – Modbus RTU interface index
• adu – Pointer to the RAW ADU struct that is received

Return values
0 – If transfer was successful

void modbus_raw_put_header(const struct modbus_adu *adu, uint8_t *header)
Put MBAP header into a buffer.

Parameters
• adu – Pointer to the RAW ADU struct
• header – Pointer to the buffer in which MBAP header will be placed.

void modbus_raw_get_header(struct modbus_adu *adu, const uint8_t *header)
Get MBAP header from a buffer.

Parameters
• adu – Pointer to the RAW ADU struct
• header – Pointer to the buffer containing MBAP header

void modbus_raw_set_server_failure(struct modbus_adu *adu)
Set Server Device Failure exception.
This function modifies ADU passed by the pointer.

Parameters
• adu – Pointer to the RAW ADU struct

int modbus_raw_backend_txn(const int iface, struct modbus_adu *adu)
Use interface as backend to send and receive ADU.
This function overwrites ADU passed by the pointer and generates exception responses
if backend interface is misconfigured or target device is unreachable.

Parameters
• iface – Modbus client interface index
• adu – Pointer to the RAW ADU struct

Return values
0 – If transfer was successful

int modbus_register_user_fc(const int iface, struct modbus_custom_fc *custom_fc)
Register a user-defined function code handler.

The Modbus specification allows users to define standard function codes missing from
Zephyr's Modbus implementation as well as add non-standard function codes in the
ranges 65 to 72 and 100 to 110 (decimal), as per specification.

This function registers a new handler at runtime for the given function code.

Parameters
• iface – Modbus client interface index
• custom_fc – User defined function code and callback pair

Return values
0 – on success

struct modbus_adu
#include <modbus.h> Frame struct used internally and for raw ADU support.

Public Members

uint16_t trans_id
Transaction Identifier.

uint16_t proto_id
Protocol Identifier.

uint16_t length
Length of the data only (not the length of unit ID + PDU)

uint8_t unit_id
Unit Identifier.

uint8_t fc
Function Code.

uint8_t data[CONFIG_MODBUS_BUFFER_SIZE - 4]
Transaction Data.

uint16_t crc
RTU CRC.

struct modbus_user_callbacks
#include <modbus.h> Modbus Server User Callback structure.
Public Members

int (*coil_rd)(uint16_t addr, bool *state)
Coil read callback.

int (*coil_wr)(uint16_t addr, bool state)
Coil write callback.

int (*discrete_input_rd)(uint16_t addr, bool *state)
Discrete Input read callback.

int (*input_reg_rd)(uint16_t addr, uint16_t *reg)
Input Register read callback.

int (*input_reg_rd_fp)(uint16_t addr, float *reg)
Floating Point Input Register read callback.

int (*holding_reg_rd)(uint16_t addr, uint16_t *reg)
Holding Register read callback.

int (*holding_reg_wr)(uint16_t addr, uint16_t reg)
Holding Register write callback.

int (*holding_reg_rd_fp)(uint16_t addr, float *reg)
Floating Point Holding Register read callback.

int (*holding_reg_wr_fp)(uint16_t addr, float reg)
Floating Point Holding Register write callback.

struct modbus_serial_param
#include <modbus.h> Modbus serial line parameter.

Public Members

uint32_t baud
Baudrate of the serial line.

enum uart_config_parity parity
parity UART's parity setting: UART_CFG_PARITY_NONE, UART_CFG_PARITY_EVEN, UART_CFG_PARITY_ODD

enum uart_config_stop_bits stop_bits_client
stop_bits_client UART's stop bits setting if in client mode:
UART_CFG_STOP_BITS_0, UART_CFG_STOP_BITS_1, UART_CFG_STOP_BITS_1_5, UART_CFG_STOP_BITS_2,

struct modbus_server_param
#include <modbus.h> Modbus server parameter.
### Public Members

```c
struct modbus_user_callbacks *user_cb
    Pointer to the User Callback structure.

uint8_t unit_id
    Modbus unit ID of the server.
```

```c
struct modbus_raw_cb
    #include <modbus.h>
```

```c
struct modbus_iface_param
    #include <modbus.h> User parameter structure to configure Modbus interface as client or server.
```

### Public Members

```c
enum modbus_mode mode
    Mode of the interface.

uint32_t rx_timeout
    Amount of time client will wait for a response from the server.
```

```c
struct modbus_serial_param serial
    Serial support parameter of the interface.

struct modbus_raw_cb rawcb
    Pointer to raw ADU callback function.
```

## 4.17 Modem modules

This service provides modules necessary to communicate with modems. Modems are self-contained devices that implement the hardware and software necessary to perform RF (Radio-Frequency) communication, including GNSS, Cellular, WiFi etc.

The modem modules are inter-connected dynamically using data-in/data-out pipes making them independently testable and highly flexible, ensuring stability and scalability.

### 4.17.1 Modem pipe

This module is used to abstract data-in/data-out communication over a variety of mechanisms, like UART and CMUX DLCI channels, in a thread-safe manner.

A modem backend will internally contain an instance of a modem_pipe structure, alongside any buffers and additional structures required to abstract away its underlying mechanism.

The modem backend will return a pointer to its internal modem_pipe structure when initialized, which will be used to interact with the backend through the modem_pipe API.
group modem_pipe
Modem Pipe.

**Typedefs**

typedef void (*modem_pipe_api_callback)(struct modem_pipe *pipe, enum modem_pipe_event event, void *user_data)

**Enums**

enum modem_pipe_event
Modem pipe event.

*Values:*

- enumerator MODEM_PIPE_EVENT_OPENED = 0
- enumerator MODEM_PIPE_EVENT_RECEIVE_READY
- enumerator MODEM_PIPE_EVENT_TRANSMIT_IDLE
- enumerator MODEM_PIPE_EVENT_CLOSED

**Functions**

int modem_pipe_open(struct modem_pipe *pipe)
Open pipe.

*Parameters*

- pipe – Pipe instance

*Return values*

- 0 – if pipe was successfully opened or was already open
- -errno – code otherwise

int modem_pipe_open_async(struct modem_pipe *pipe)
Open pipe asynchronously.

*Note:* The MODEM_PIPE_EVENT_OPENED event is invoked immediately if pipe is already opened.

*Parameters*

- pipe – Pipe instance

*Return values*

- 0 – if pipe open was called successfully or pipe was already open
- -errno – code otherwise
void *modem_pipe_attach(struct modem_pipe *pipe, modem_pipe_api_callback callback, void *user_data)

Attach pipe to callback.

**Note:** The MODEM_PIPE_EVENT_RECEIVE_READY event is invoked immediately if pipe has pending data ready to receive.

**Parameters**
- **pipe** – Pipe instance
- **callback** – Callback called when pipe event occurs
- **user_data** – Free to use user data passed with callback

int modem_pipe_transmit(struct modem_pipe *pipe, const uint8_t *buf, size_t size)

Transmit data through pipe.

**Warning:** This call must be non-blocking

**Parameters**
- **pipe** – Pipe to transmit through
- **buf** – Destination for received data
- **size** – Capacity of destination for received data

**Returns**
Number of bytes placed in pipe

int modem_pipe_receive(struct modem_pipe *pipe, uint8_t *buf, size_t size)

Reveive data through pipe.

**Warning:** This call must be non-blocking

**Parameters**
- **pipe** – Pipe to receive from
- **buf** – Destination for received data
- **size** – Capacity of destination for received data

**Returns**
Number of bytes received from pipe if any

**Returns**
- EPERM if pipe is closed
- errno code on error

void modem_pipe_release(struct modem_pipe *pipe)

Clear callback.

**Parameters**
- **pipe** – Pipe instance
int modem_pipe_close(struct modem_pipe *pipe)
Close pipe.

Parameters
• pipe – Pipe instance

Return values
• 0 – if pipe open was called closed or pipe was already closed
• -errno – code otherwise

int modem_pipe_close_async(struct modem_pipe *pipe)
Close pipe asynchronously.

Note: The MODEM_PIPE_EVENT_CLOSED event is invoked immediately if pipe is already closed.

Parameters
• pipe – Pipe instance

Return values
• 0 – if pipe close was called successfully or pipe was already closed
• -errno – code otherwise

4.17.2 Modem PPP
This module defines and binds a L2 PPP network interface, described in L2 Layer Management, to a modem backend. The L2 PPP interface sends and receives network packets. These network packets have to be wrapped in PPP frames before being transported via a modem backend. This module performs said wrapping.

group modem_ppp
Modem PPP.

Defines

MODEM_PPP_DEFINE(_name, _init_iface, _prio, _mtu, _buf_size)
Define a modem PPP module and bind it to a network interface.

This macro defines the modem_ppp instance, initializes a PPP L2 network device instance, and binds the modem_ppp instance to the PPP L2 instance.

Parameters
• _name – Name of the statically defined modem_ppp instance
• _init_iface – Hook for the PPP L2 network interface init function
• _prio – Initialization priority of the PPP L2 net iface
• _mtu – Max size of net_pkt data sent and received on PPP L2 net iface
• _buf_size – Size of partial PPP frame transmit and receive buffers
**Typedefs**

typedef void (*modem_ppp_init_iface)(struct net_if *iface)
   L2 network interface init callback.

**Functions**

int modem_ppp_attach(struct modem_ppp *ppp, struct modem_pipe *pipe)
   Attach pipe to instance and connect.

   **Parameters**
   • ppp – Modem PPP instance
   • pipe – Pipe to attach to modem PPP instance

struct net_if *modem_ppp_get_iface(struct modem_ppp *ppp)
   Get network interface modem PPP instance is bound to.

   **Parameters**
   • ppp – Modem PPP instance

   **Returns**
   Pointer to network interface modem PPP instance is bound to

void modem_ppp_release(struct modem_ppp *ppp)
   Release pipe from instance.

   **Parameters**
   • ppp – Modem PPP instance

4.17.3 Modem CMUX

This module is an implementation of CMUX following the 3GPP 27.010 specification. CMUX is a multiplexing protocol, allowing for multiple bi-directional streams of data, called DLCI channels. The module attaches to a single modem backend, exposing multiple modem backends, each representing a DLCI channel.

*group* modem_cmux
   Modem CMUX.

**Typedefs**

typedef void (*modem_cmux_callback)(struct modem_cmux *cmux, enum
   modem_cmux_event event, void *user_data)

**Enums**

enum modem_cmux_event
   Values:
enumerator MODEM_CMUX_EVENT_CONNECTED = 0
enumerator MODEM_CMUX_EVENT_DISCONNECTED

Functions

void modem_cmux_init(struct modem_cmux *cmux, const struct modem_cmux_config *config)

Initialize CMUX instance.

Parameters

• cmux – CMUX instance
• config – Configuration to apply to CMUX instance

struct modem_pipe *modem_cmux_dlci_init(struct modem_cmux *cmux, struct modem_cmux_dlci *dlci, const struct modem_cmux_dlci_config *config)

Initialize DLCI instance and register it with CMUX instance.

Parameters

• cmux – CMUX instance which the DLCI will be registered to
• dlci – DLCI instance which will be registered and configured
• config – Configuration to apply to DLCI instance

int modem_cmux_attach(struct modem_cmux *cmux, struct modem_pipe *pipe)

Attach CMUX instance to pipe.

Parameters

• cmux – CMUX instance
• pipe – Pipe instance to attach CMUX instance to

int modem_cmux_connect(struct modem_cmux *cmux)

Connect CMUX instance.

This will send a CMUX connect request to target on the serial bus. If successful, DLCI channels can be now be opened using modem_pipe_open().

---

Note: When connected, the bus pipe must not be used directly

Parameters

• cmux – CMUX instance

int modem_cmux_connect_async(struct modem_cmux *cmux)

Connect CMUX instance asynchronously.

This will send a CMUX connect request to target on the serial bus. If successful, DLCI channels can be now be opened using modem_pipe_open().

---

Note: When connected, the bus pipe must not be used directly

Parameters
### modem_cmux_disconnect

```c
int modem_cmux_disconnect(struct modem_cmux *cmux)
```

Close down and disconnect CMUX instance.

This will close all open DLCI channels, and close down the CMUX connection.

**Note:** The bus pipe must be released using `modem_cmux_release()` after disconnecting before being reused.

**Parameters**

- `cmux` – CMUX instance

### modem_cmux_disconnect_async

```c
int modem_cmux_disconnect_async(struct modem_cmux *cmux)
```

Close down and disconnect CMUX instance asynchronously.

This will close all open DLCI channels, and close down the CMUX connection.

**Note:** The bus pipe must be released using `modem_cmux_release()` after disconnecting before being reused.

**Parameters**

- `cmux` – CMUX instance

### modem_cmux_release

```c
void modem_cmux_release(struct modem_cmux *cmux)
```

Release CMUX instance from pipe.

Releases the pipe and hard resets the CMUX instance internally. CMUX should be disconnected using `modem_cmux_disconnect()`.

**Note:** The bus pipe can be used directly again after CMUX instance is released.

**Parameters**

- `cmux` – CMUX instance

### modem_cmux_config

```c
#include <cmux.h>
```

Contains CMUX instance configuration data.

#### Public Members

- `modem_cmux_callback` callback
  - Invoked when event occurs.
- `void *user_data`
  - Free to use pointer passed to event handler when invoked.
- `uint8_t *receive_buf`
  - Receive buffer.
uint16_t receive_buf_size
    Size of receive buffer in bytes [127, ...].

uint8_t *transmit_buf
    Transmit buffer.

uint16_t transmit_buf_size
    Size of transmit buffer in bytes [149, ...].

struct modem_cmux_dlci_config
    #include <cmux.h> CMUX DLCI configuration.

Public Members

uint8_t dlci_address
    DLCI channel address.

uint8_t *receive_buf
    Receive buffer used by pipe.

uint16_t receive_buf_size
    Size of receive buffer used by pipe [127, ...].

4.18 Asynchronous Notifications

Zephyr APIs often include async functions where an operation is initiated and the application needs to be informed when it completes, and whether it succeeded. Using k_poll() is often a good method, but some application architectures may be more suited to a callback notification, and operations like enabling clocks and power rails may need to be invoked before kernel functions are available so a busy-wait for completion may be needed.

This API is intended to be embedded within specific subsystems such as On-Off Manager and other APIs that support async transactions. The subsystem wrappers are responsible for extracting operation-specific data from requests that include a notification element, and for invoking callbacks with the parameters required by the API.

A limitation is that this API is not suitable for System Calls because:

• sys_notify is not a kernel object;

• copying the notification content from userspace will break use of CONTAINER_OF in the implementing function;

• neither the spin-wait nor callback notification methods can be accepted from userspace callers.

Where a notification is required for an asynchronous operation invoked from a user mode thread the subsystem or driver should provide a syscall API that uses k_poll_signal for notification.
4.18.1 API Reference

group sys_notify_apis

Typedefs

typedef void (*sys_notify_generic_callback)();

Generic signature used to notify of result completion by callback.

Functions with this role may be invoked from any context including pre-kernel, ISR, or cooperative or pre-emptible threads. Compatible functions must be isr-ok and not sleep.

Parameters that should generally be passed to such functions include:

• a pointer to a specific client request structure, i.e. the one that contains the sys_notify structure.
• the result of the operation, either as passed to sys_notify_finalize() or extracted afterwards using sys_notify_fetch_result(). Expected values are service-specific, but the value shall be non-negative if the operation succeeded, and negative if the operation failed.

Functions

static inline uint32_t sys_notify_get_method(const struct sys_notify *notify)

int sys_notify_validate(struct sys_notify *notify)

Validate and initialize the notify structure.

This should be invoked at the start of any service-specific configuration validation. It ensures that the basic asynchronous notification configuration is consistent, and clears the result.

Note that this function does not validate extension bits (zeroed by async notify API init functions like sys_notify_init_callback()). It may fail to recognize that an uninitialized structure has been passed because only method bits of flags are tested against method settings. To reduce the chance of accepting an uninitialized operation service validation of structures that contain an sys_notify instance should confirm that the extension bits are set or cleared as expected.

Return values

• 0 – on successful validation and reinitialization
• -EINVAL – if the configuration is not valid.

sys_notify_generic_callback sys_notify_finalize(struct sys_notify *notify, int res)

Record and signal the operation completion.

Parameters

• notify – pointer to the notification state structure.
• res – the result of the operation. Expected values are service-specific, but the value shall be non-negative if the operation succeeded, and negative if the operation failed.
Returns
If the notification is to be done by callback this returns the generic version of the function to be invoked. The caller must immediately invoke that function with whatever arguments are expected by the callback. If notification is by spin-wait or signal, the notification has been completed by the point this function returns, and a null pointer is returned.

static inline int sys_notify_fetch_result(const struct sys_notify *notify, int *result)
Check for and read the result of an asynchronous operation.

Parameters
- notify – pointer to the object used to specify asynchronous function behavior and store completion information.
- result – pointer to storage for the result of the operation. The result is stored only if the operation has completed.

Return values
- 0 – if the operation has completed.
- -EAGAIN – if the operation has not completed.

static inline void sys_notify_init_spinwait(struct sys_notify *notify)
Initialize a notify object for spin-wait notification.

Clients that use this initialization receive no asynchronous notification, and instead must periodically check for completion using sys_notify_fetch_result().

On completion of the operation the client object must be reinitialized before it can be re-used.

Parameters
- notify – pointer to the notification configuration object.

static inline void sys_notify_init_signal(struct sys_notify *notify, struct k_poll_signal *sigp)
Initialize a notify object for (k_poll) signal notification.

Clients that use this initialization will be notified of the completion of operations through the provided signal.

On completion of the operation the client object must be reinitialized before it can be re-used.

Note: This capability is available only when CONFIG_POLL is selected.

Parameters
- notify – pointer to the notification configuration object.
- sigp – pointer to the signal to use for notification. The value must not be null. The signal must be reset before the client object is passed to the on-off service API.

static inline void sys_notify_init_callback(struct sys_notify *notify, sys_notify_generic_callback handler)
Initialize a notify object for callback notification.

Clients that use this initialization will be notified of the completion of operations through the provided callback. Note that callbacks may be invoked from various contexts depending on the specific service; see sys_notify_generic_callback.
On completion of the operation the client object must be reinitialized before it can be re-used.

**Parameters**

- **notify** – pointer to the notification configuration object.
- **handler** – a function pointer to use for notification.

```c
static inline bool sys_notify_uses_callback(const struct sys_notify *notify)
```

Detect whether a particular notification uses a callback.

The generic handler does not capture the signature expected by the callback, and the translation to a service-specific callback must be provided by the service. This check allows abstracted services to reject callback notification requests when the service doesn't provide a translation function.

**Returns**

true if and only if a callback is to be used for notification.

```c
struct sys_notify
```

#include <notify.h> State associated with notification for an asynchronous operation.

Objects of this type are allocated by a client, which must use an initialization function (e.g. `sys_notify_init_signal()`) to configure them. Generally the structure is a member of a service-specific client structure, such as `onoff_client`.

Control of the containing object transfers to the service provider when a pointer to the object is passed to a service function that is documented to take control of the object, such as `onoff_service_request()`. While the service provider controls the object the client must not change any object fields. Control reverts to the client:

- if the call to the service API returns an error;
- when operation completion is posted. This may occur before the call to the service API returns.

Operation completion is technically posted when the flags field is updated so that `sys_notify_fetch_result()` returns success. This will happen before the signal is posted or callback is invoked. Note that although the manager will no longer reference the `sys_notify` object past this point, the containing object may have state that will be referenced within the callback. Where callbacks are used control of the containing object does not revert to the client until the callback has been invoked. (Re-use within the callback is explicitly permitted.)

After control has reverted to the client the notify object must be reinitialized for the next operation.

The content of this structure is not public API to clients: all configuration and inspection should be done with functions like `sys_notify_init_callback()` and `sys_notify_fetch_result()`. However, services that use this structure may access certain fields directly.

```c
union method
```

#include <notify.h>

**Public Members**

```c
struct k_poll_signal *signal
```

```c
sys_notify_generic_callback callback
```
4.19  Power Management

Zephyr RTOS power management subsystem provides several means for a system integrator to implement power management support that can take full advantage of the power saving features of SOCs.

4.19.1  Overview

The interfaces and APIs provided by the power management subsystem are designed to be architecture and SOC independent. This enables power management implementations to be easily adapted to different SOCs and architectures.

The architecture and SOC independence is achieved by separating the core infrastructure and the SOC specific implementations. The SOC specific implementations are abstracted to the application and the OS using hardware abstraction layers.

The power management features are classified into the following categories.

- System Power Management
- Device Power Management

4.19.2  System Power Management

The kernel enters the idle state when it has nothing to schedule. If enabled via the `CONFIG_PM` Kconfig option, the Power Management Subsystem can put an idle system in one of the supported power states, based on the selected power management policy and the duration of the idle time allotted by the kernel.

It is an application responsibility to set up a wake up event. A wake up event will typically be an interrupt triggered by one of the SoC peripheral modules such as a SysTick, RTC, counter, or GPIO. Depending on the power mode entered, only some SoC peripheral modules may be active and can be used as a wake up source.

The following diagram describes system power management:
Idle Thread

arch_irq_lock()

CONFIG_PM

no

k_cpu_idle()

yes

pm_system_suspend (ticks)

pm_policy_next_state()

ACTIVE

SUSPEND_TO_RAM...

RUNTIME_IDLE...

pm_suspend_devices()

pm_low_power_devices()

k_schedule_lock()

pm_state_notify()

pm_power_state_set(state)

pm_resume_devices()

pm_state_exit_post_ops()

pm_state_notify()

k_sched_unlock()
Some handful examples using different power management features:

- samples/boards/stm32/power_mgmt/blinky/
- samples/boards/esp32/deep_sleep/
- samples/subsys/pm/device_pm/
- tests/subsys/pm/power_mgmt/
- tests/subsys/pm/power_mgmt_soc/
- tests/subsys/pm/power_states_api/

**Power States**

The power management subsystem contains a set of states based on power consumption and context retention.

The list of available power states is defined by `pm_state`. In general power states with higher indexes will offer greater power savings and have higher wake latencies.

**Power Management Policies**

The power management subsystem supports the following power management policies:

- Residency based
- Application defined

The policy manager is responsible for informing the power subsystem which power state the system should transition to based on states defined by the platform and other constraints such as a list of allowed states.

More details on the states definition can be found in the `zephyr, power-state` binding documentation.

**Residency**  The power management system enters the power state which offers the highest power savings, and with a minimum residency value (see `zephyr, power-state`) less than or equal to the scheduled system idle time duration.

This policy also accounts for the time necessary to become active again. The core logic used by this policy to select the best power state is:

```c
if (time_to_nextcheduled_event >= (state.min_residency_us + state.exit_latency)) {
    return state
}
```

**Application**  The application defines the power management policy by implementing the `pm_policy_next_state()` function. In this policy the application is free to decide which power state the system should transition to based on the remaining time for the next scheduled timeout.

An example of an application that defines its own policy can be found in `tests/subsys/pm/power_mgmt/`.

**Policy and Power States**  The power management subsystem allows different Zephyr components and applications to configure the policy manager to block system from transitioning into certain power states. This can be used by devices when executing tasks in background to prevent the system from going to a specific state where it would lose context.
4.19.3 Device Power Management

Introduction

Device power management (PM) on Zephyr is a feature that enables devices to save energy when they are not being used. This feature can be enabled by setting CONFIG_PM_DEVICE to y. When this option is selected, device drivers implementing power management will be able to take advantage of the device power management subsystem.

Zephyr supports two types of device power management:

- Device Runtime Power Management
- System Power Management

Device Runtime Power Management

In this method, the application or any component that deals with devices directly and has the best knowledge of their use, performs the device power management. This saves power if some devices that are not in use can be turned off or put in power saving mode. This method allows saving power even when the CPU is active. The components that use the devices need to be power aware and should be able to make decisions related to managing device power.

When using this type of device power management, the kernel can change CPU power states quickly when pm_system_suspend() gets called. This is because it does not need to spend time doing device power management if the devices are already put in the appropriate power state by the application or component managing the devices.

For more information, see Device Runtime Power Management.

System Power Management

When using this type, device power management is mostly done inside pm_system_suspend() along with entering a CPU or SOC power state.

If a decision to enter a CPU lower power state is made, the power management subsystem will suspend devices before changing state. The subsystem takes care of suspending devices following their initialization order, ensuring that possible dependencies between them are satisfied. As soon as the CPU wakes up from a sleep state, devices are resumed in the opposite order that they were suspended.

Note: When using System Power Management, device transitions can be run from the idle thread. As functions in this context cannot block, transitions that intend to use blocking APIs must check whether they can do so with k_can_yield().

This type of device power management can be useful when the application is not power aware and does not implement runtime device power management. Though, Device Runtime Power Management is the preferred option for device power management.

Note: When using this type of device power management, the CPU will only enter a low power state only if no device is in the middle of a hardware transaction that cannot be interrupted.

Note: This type of device power management is disabled when CONFIG_PM_DEVICE_RUNTIME_EXCLUSIVE is set to y (that is the default value when CONFIG_PM_DEVICE_RUNTIME is enabled).
Note: Devices are suspended only when the last active core is entering a low power state and devices are resumed by the first core that becomes active.

Device Power Management States

The power management subsystem defines device states in \textit{pm\_device\_state}. This type is used to track power states of a particular device. It is important to emphasize that, although the state is tracked by the subsystem, it is the responsibility of each device driver to handle device actions (\textit{pm\_device\_action}) which change device state.

Each \textit{pm\_device\_action} have a direct unambiguous relationship with a \textit{pm\_device\_state}.

![Device actions x states](image)

As mentioned above, device drivers do not directly change between these states. This is entirely done by the power management subsystem. Instead, drivers are responsible for implementing any hardware-specific tasks needed to handle state changes.

Device Model with Power Management Support

Drivers initialize devices using macros. See \textit{Device Driver Model} for details on how these macros are used. A driver which implements device power management support must provide these macros with arguments that describe its power management implementation.

Use \textit{PM\_DEVICE\_DEFINE} or \textit{PM\_DEVICE\_DT\_DEFINE} to define the power management resources required by a driver. These macros allocate the driver-specific state which is required by the power management subsystem.

Drivers can use \textit{PM\_DEVICE\_GET} or \textit{PM\_DEVICE\_DT\_GET} to get a pointer to this state. These pointers should be passed to \textit{DEVICE\_DEFINE} or \textit{DEVICE\_DT\_DEFINE} to initialize the power management field in each device.

Here is some example code showing how to implement device power management support in a device driver.
define DT_DRV_COMPAT dummy_device

int dummy_driver_pm_action(const struct device *dev, enum pm_device_action action)
{
    switch (action) {
        case PM_DEVICE_ACTION_SUSPEND:
            /* suspend the device */
            ...
            break;
        case PM_DEVICE_ACTION_RESUME:
            /* resume the device */
            ...
            break;
        case PM_DEVICE_ACTION_TURN_ON:
            /*
            * powered on the device, used when the power
            * domain this device belongs is resumed.
            */
            ...
            break;
        case PM_DEVICE_ACTION_TURN_OFF:
            /*
            * power off the device, used when the power
            * domain this device belongs is suspended.
            */
            ...
            break;
        default:
            return -ENOTSUP;
    }
    return 0;
}

PM_DEVICE_DT_INST_DEFINE(0, dummy_driver_pm_action);

DEVICE_DT_INST_DEFINE(0, &dummy_init,
    PM_DEVICE_DT_INST_GET(0), NULL, NULL, POST_KERNEL,
    CONFIG_KERNEL_INIT_PRIORITY_DEFAULT, NULL);

Busy Status Indication

When the system is idle and the SoC is going to sleep, the power management subsystem can suspend devices, as described in System Power Management. This can cause device hardware to lose some states. Suspending a device which is in the middle of a hardware transaction, such as writing to a flash memory, may lead to undefined behavior or inconsistent states. This API guards such transactions by indicating to the kernel that the device is in the middle of an operation and should not be suspended.

When `pm_device_busy_set()` is called, the device is marked as busy and the system will not do power management on it. After the device is no longer doing an operation and can be suspended, it should call `pm_device_busy_clear()`.

Wakeup capability

Some devices are capable of waking the system up from a sleep state. When a device has such capability, applications can enable or disable this feature on a device dynamically using `pm_device_wakeup_enable()`.
This property can be set on device declaring the property `wakeup-source` in the device node in devicetree. For example, this devicetree fragment sets the gpio0 device as a “wakeup” source:

```plaintext
gpio0: gpio0@40022000 {
    compatible = "ti,cc13xx-cc26xx-gpio";
    reg = <0x40022000 0x400>
    interrupts = <0 0>
    status = "disabled"
    label = "GPIO_0"
    gpio-controller;
    wakeup-source;
    #gpio-cells = <2>
};
```

By default, “wakeup” capable devices do not have this functionality enabled during the device initialization. Applications can enable this functionality later calling `pm_device_wakeup_enable()`.

**Note:** This property is only used by the system power management to identify devices that should not be suspended. It is responsibility of driver or the application to do any additional configuration required by the device to support it.

### Power Domain

Power domain on Zephyr is represented as a regular device. The power management subsystem ensures that a domain is resumed before and suspended after devices using it. For more details, see *Power Domain*.

#### 4.19.4 Device Runtime Power Management

**Introduction**

The device runtime power management (PM) framework is an active power management mechanism which reduces the overall system power consumption by suspending the devices which are idle or not used independently of the system state. It can be enabled by setting `CONFIG_PM_DEVICE_RUNTIME`. In this model the device driver is responsible to indicate when it needs the device and when it does not. This information is used to determine when to suspend or resume a device based on usage count.

When device runtime power management is enabled on a device, its state will be initially set to a `PM_DEVICE_STATE_SUSPENDED` indicating it is not used. On the first device request, it will be resumed and put into the `PM_DEVICE_STATE_ACTIVE` state. The device will remain in this state until it is no longer used. At this point, the device will be suspended until the next device request. If the suspension is performed synchronously the device will be immediately put into the `PM_DEVICE_STATE_SUSPENDED` state, whereas if it is performed asynchronously, it will be put into the `PM_DEVICE_STATE_SUSPENDING` state first and then into the `PM_DEVICE_STATE_SUSPENDED` state when the action is run.

For devices on a power domain (via the devicetree ‘power-domain’ property), device runtime power management automatically attempts to request and release the dependent domain in response to `pm_device_runtime_get()` and `pm_device_runtime_put()` calls on the child device.

For the previous to automatically control the power domain state, device runtime PM must be enabled on the power domain device (either through the `zephyr:pm-device-runtime-auto` devicetree property or `pm_device_runtime_enable()`).
The device runtime power management framework has been designed to minimize devices power consumption with minimal application work. Device drivers are responsible for indicating when they need the device to be operational and when they do not. Therefore, applications can not manually suspend or resume a device. An application can, however, decide when to disable or enable runtime power management for a device. This can be useful, for example, if an application wants a particular device to be always active.

**Design principles**

When runtime PM is enabled on a device it will no longer be resumed or suspended during system power transitions. Instead, the device is fully responsible to indicate when it needs a device and when it does not. The device runtime PM API uses reference counting to keep track of device's usage. This allows the API to determine when a device needs to be resumed or suspended. The API uses the `get` and `put` terminology to indicate when a device is needed or not, respectively. This mechanism plays a key role when we account for device dependencies. For example, if a bus device is used by multiple sensors, we can keep the bus active until the last sensor has finished using it.

**Note:** As of today, the device runtime power management API does not manage device dependencies. This effectively means that, if a device depends on other devices to operate (e.g. a sensor may depend on a bus device), the bus will be resumed and suspended on every transaction. In general, it is more efficient to keep parent devices active when their children are used, since the children may perform multiple transactions in a short period of time. Until this feature is added, devices can manually `get` or `put` their dependencies.

The `pm_device_runtime_get()` function can be used by a device driver to indicate it *needs* the device to be active or operational. This function will increase device usage count and resume the device if necessary. Similarly, the `pm_device_runtime_put()` function can be used to indicate that the device is no longer needed. This function will decrease the device usage count and suspend the device if necessary. It is worth to note that in both cases, the operation is carried
The synchronous model is as simple as it gets. However, it may introduce unnecessary delays since the application will not get the operation result until the device is suspended (in case device is no longer used). It will likely not be a problem if the operation is fast, e.g. a register toggle. However, the situation will not be the same if suspension involves sending packets through a slow bus. For this reason the device drivers can also make use of the `pm_device_runtime_put_async()` function. This function will schedule the suspend operation, again, if device is no longer used. The suspension will then be carried out when the system work queue gets the chance to run. The sequence diagram shown below illustrates this scenario.

### Implementation guidelines

In a first place, a device driver needs to implement the PM action callback used by the PM subsystem to suspend or resume devices.

```c
static int mydev_pm_action(const struct device *dev, enum pm_device_action *action)
{
    switch (action) {
    case PM_DEVICE_ACTION_SUSPEND:
        /* suspend the device */
```
Fig. 10: Asynchronous operation on a single device
The PM action callback calls are serialized by the PM subsystem, therefore, no special synchronization is required.

To enable device runtime power management on a device, the driver needs to call `pm_device_runtime_enable()` at initialization time. Note that this function will suspend the device if its state is `PM_DEVICE_STATE_ACTIVE`. In case the device is physically suspended, the init function should call `pm_device_init_suspended()` before calling `pm_device_runtime_enable()`.

```c
/* device driver initialization function */
static int mydev_init(const struct device *dev)
{
    int ret;
    ...

    /* OPTIONAL: mark device as suspended if it is physically suspended */
    pm_device_init_suspended(dev);

    /* enable device runtime power management */
    ret = pm_device_runtime_enable(dev);
    if ((ret < 0) && (ret != -ENOSYS)) {
        return ret;
    }
}
```

Device runtime power management can also be automatically enabled on a device instance by adding the `zephyr,pm-device-runtime-auto` flag onto the corresponding devicetree node. If enabled, `pm_device_runtime_enable()` is called immediately after the init function of the device runs and returns successfully.

```c
foo {
    /* ... */
    zephyr,pm-device-runtime-auto;
};
```

Assuming an example device driver that implements an operation API call, the `get` and `put` operations could be carried out as follows:

```c
static int mydev_operation(const struct device *dev)
{
    int ret;

    /* "get" device (increases usage count, resumes device if suspended) */
    ret = pm_device_runtime_get(dev);
    if (ret < 0) {
        return ret;
    }

    /* do something with the device */
} (continues on next page)
In case the suspend operation is slow, the device driver can use the asynchronous API:

```c
static int mydev_operation(const struct device *dev)
{
    int ret;
    /* "get" device (increases usage count, resumes device if suspended) */
    ret = pm_device_runtime_get(dev);
    if (ret < 0) {
        return ret;
    }
    /* do something with the device */
    ...
    /* "put" device (decreases usage count, schedule suspend if no more users) */
    return pm_device_runtime_put_async(dev, K_NO_WAIT);
}
```

### 4.19.5 Power Domain

**Introduction**

The Zephyr power domain abstraction is designed to support groupings of devices powered by a common source to be notified of power source state changes in a generic fashion. Application code that is using device A does not need to know that device B is on the same power domain and should also be configured into a low power state.

Power domains are optional on Zephyr, to enable this feature the option `CONFIG_PM_DEVICE_POWER_DOMAIN` has to be set.

When a power domain turns itself on or off, it is the responsibility of the power domain to notify all devices using it through their power management callback called with `PM_DEVICE_ACTION_TURN_ON` or `PM_DEVICE_ACTION_TURN_OFF` respectively. This work flow is illustrated in the diagram below.

![Power domain work flow diagram](image-url)
**Internal Power Domains**  Most of the devices in an SoC have independent power control that can be turned on or off to reduce power consumption. But there is a significant amount of static current leakage that can't be controlled only using device power management. To solve this problem, SoCs normally are divided into several regions grouping devices that are generally used together, so that an unused region can be completely powered off to eliminate this leakage. These regions are called “power domains”, can be present in a hierarchy and can be nested.

**External Power Domains**  Devices external to a SoC can be powered from sources other than the main power source of the SoC. These external sources are typically a switch, a regulator, or a dedicated power IC. Multiple devices can be powered from the same source, and this grouping of devices is typically called a “power domain”.

Placing devices on power domains can be done for a variety of reasons, including to enable devices with high power consumption in low power mode to be completely turned off when not in use.

**Implementation guidelines**

In a first place, a device that acts as a power domain needs to declare compatible with power-domain. Taking *Power domain workflow* as example, the following code defines a domain called *gpio_domain*.

```c

gpio_domain: gpio_domain@4 {
    compatible = "power-domain";
    ...
};
```

A power domain needs to implement the PM action callback used by the PM subsystem to turn devices on and off.

```c
static int mydomain_pm_action(const struct device *dev,
   enum pm_device_action *action)
{
    switch (action) {
        case PM_DEVICE_ACTION_RESUME:
            /* resume the domain */
            ...
            /* notify children domain is now powered */
            pm_device_children_action_run(dev, PM_DEVICE_ACTION_TURN_ON, NULL);
            break;
        case PM_DEVICE_ACTION_SUSPEND:
            /* notify children domain is going down */
            pm_device_children_action_run(dev, PM_DEVICE_ACTION_TURN_OFF, NULL);
            /* suspend the domain */
            ...
            break;
        case PM_DEVICE_ACTION_TURN_ON:
            /* turn on the domain (e.g. setup control pins to disabled) */
            ...
            break;
        case PM_DEVICE_ACTION_TURN_OFF:
            /* turn off the domain (e.g. reset control pins to default state) */
            ...
            break;
        default:
            return -ENOTSUP;
    }
    return 0;
}
```

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Devices belonging to this device can be declared referring it in the power-domain node's property. The example below declares devices gpio0 and gpio1 belonging to domain gpio_domain.

```c
&gpio0 {
    compatible = "zephyr,gpio-emul";
    gpio-controller;
    power-domain = <&gpio_domain>;
};

&gpio1 {
    compatible = "zephyr,gpio-emul";
    gpio-controller;
    power-domain = <&gpio_domain>;
};
```

All devices under a domain will be notified when the domain changes state. These notifications are sent as actions in the device PM action callback and can be used by them to do any additional work required. They can safely be ignored though.

```c
static int mydev_pm_action(const struct device *dev,
                            enum pm_device_action *action)
{
    switch (action) {
    case PM_DEVICE_ACTION_SUSPEND:
        /* suspend the device */
        ...
        break;
    case PM_DEVICE_ACTION_RESUME:
        /* resume the device */
        ...
        break;
    case PM_DEVICE_ACTION_TURN_ON:
        /* configure the device into low power mode */
        ...
        break;
    case PM_DEVICE_ACTION_TURN_OFF:
        /* prepare the device for power down */
        ...
        break;
    default:
        return -ENOTSUP;
    }

    return 0;
}
```

**Note:** It is responsibility of driver or the application to set the domain as “wakeup” source if a device depending on it is used as “wakeup” source.

### 4.19.6 Power Management

**System PM APIs**

```c
group subsys_pm_sys
    System Power Management API.
```
Functions

bool pm_state_force(uint8_t cpu, const struct pm_state_info *info)

Force usage of given power state.

This function overrides decision made by PM policy forcing usage of given power state upon next entry of the idle thread.

Note: This function can only run in thread context

Parameters

• cpu – CPU index.
• info – Power state which should be used in the ongoing suspend operation.

void pm_notifier_register(struct pm_notifier *notifier)

Register a power management notifier.

Register the given notifier from the power management notification list.

Parameters

• notifier – pm_notifier object to be registered.

int pm_notifier_unregister(struct pm_notifier *notifier)

Unregister a power management notifier.

Remove the given notifier from the power management notification list. After that this object callbacks will not be called.

Parameters

• notifier – pm_notifier object to be unregistered.

Returns

0 if the notifier was successfully removed, a negative value otherwise.

const struct pm_state_info *pm_state_next_get(uint8_t cpu)

Gets the next power state that will be used.

This function returns the next power state that will be used by the SoC.

Parameters

• cpu – CPU index.

Returns

next pm_state_info that will be used
**Note:** These callbacks can be called from the ISR of the event that caused the kernel exit from idling.

**Note:** It is not allowed to call `pm_notifier_unregister` or `pm_notifier_register` from these callbacks because they are called with the spin locked in those functions.

**Public Members**

```c
void (*state_entry)(enum pm_state state)
```

Application defined function for doing any target specific operations for power state entry.

```c
void (*state_exit)(enum pm_state state)
```

Application defined function for doing any target specific operations for power state exit.

**States**

```c
group subsys_pm_states
```

System Power Management States.

**Defines**

```c
PM_STATE_INFO_DT_INIT(node_id)
```

Initializer for struct `pm_state_info` given a DT node identifier with zephyr::power-state compatible.

**Parameters**

- `node_id` – A node identifier with compatible zephyr::power-state

```c
PM_STATE_DT_INIT(node_id)
```

Initializer for enum `pm_state` given a DT node identifier with zephyr::power-state compatible.

**Parameters**

- `node_id` – A node identifier with compatible zephyr::power-state

```c
DT_NUM_CPU_POWER_STATES(node_id)
```

Obtain number of CPU power states supported and enabled by the given CPU node identifier.

**Parameters**

- `node_id` – A CPU node identifier.

**Returns**

Number of supported and enabled CPU power states.

```c
PM_STATE_INFO_LIST_FROM_DT_CPU(node_id)
```

Initialize an array of struct `pm_state_info` with information from all the states present and enabled in the given CPU node identifier.

Example devicetree fragment:
cpus {
    ...
    cpu0: cpu@0 {
        device_type = "cpu";
        ...
        cpu-power-states = <&state0 &state1>;
    };
    power-states {
        state0: state0 {
            compatible = "zephyr,power-state";
            power-state-name = "suspend-to-idle";
            min-residency-us = <100000>;
            exit-latency-us = <100>;
        };
        state1: state1 {
            compatible = "zephyr,power-state";
            power-state-name = "suspend-to-ram";
            min-residency-us = <50000>;
            exit-latency-us = <500>;
        }
    };
};

Example usage:

```c
const struct pm_state_info states[] =
    PM_STATE_INFO_LIST_FROM_DT_CPU(DT_NODELABEL(cpu0));
```

**Parameters**

- `node_id` – A CPU node identifier.

**PM_STATE_INFO_LIST_FROM_DT_CPU(node_id)**

Initialize an array of struct pm_state with information from all the states present and enabled in the given CPU node identifier.

Example devicetree fragment:

```c
cpus {
    ...
    cpu0: cpu@0 {
        device_type = "cpu";
        ...
        cpu-power-states = <&state0 &state1>;
    };
    power-states {
        state0: state0 {
            compatible = "zephyr,power-state";
            power-state-name = "suspend-to-idle";
            min-residency-us = <100000>;
            exit-latency-us = <100>;
        };
        state1: state1 {
            compatible = "zephyr,power-state";
            power-state-name = "suspend-to-ram";
            min-residency-us = <50000>;
            exit-latency-us = <500>;
        }
    };
};
```

(continues on next page)
Example usage:

```c
const enum pm_state states[] = PM_STATE_LIST_FROM_DT_CPU(DT_NODELABEL(cpu0));
```

**Parameters**

- **node_id** – A CPU node identifier.

### Enums

**enum pm_state**

Power management state.

**Values:**

- **enumerator PM_STATE_ACTIVE**
  
  Runtime active state.
  
  The system is fully powered and active.

  **Note:** This state is correlated with ACPI G0/S0 state

- **enumerator PM_STATE_RUNTIME_IDLE**
  
  Runtime idle state.
  
  Runtime idle is a system sleep state in which all of the cores enter deepest possible idle state and wait for interrupts, no requirements for the devices, leaving them at the states where they are.

  **Note:** This state is correlated with ACPI S0ix state

- **enumerator PM_STATE_SUSPEND_TO_IDLE**
  
  Suspend to idle state.
  
  The system goes through a normal platform suspend where it puts all of the cores in deepest possible idle state and may puts peripherals into low-power states. No operating state is lost (i.e. the cpu core does not lose execution context), so the system can go back to where it left off easily enough.

  **Note:** This state is correlated with ACPI S1 state

- **enumerator PM_STATE_STANDBY**
  
  Standby state.
  
  In addition to putting peripherals into low-power states all non-boot CPUs are powered off. It should allow more energy to be saved relative to suspend to idle, but the resume latency will generally be greater than for that state. But it should be the same state with suspend to idle state on uniprocessor system.
Note: This state is correlated with ACPI S2 state

enumerator PM_STATE_SUSPEND_TO_RAM
Suspend to ram state.
This state offers significant energy savings by powering off as much of the system as possible, where memory should be placed into the self-refresh mode to retain its contents. The state of devices and CPUs is saved and held in memory, and it may require some boot-strapping code in ROM to resume the system from it.

Note: This state is correlated with ACPI S3 state

enumerator PM_STATE_SUSPEND_TO_DISK
Suspend to disk state.
This state offers significant energy savings by powering off as much of the system as possible, including the memory. The contents of memory are written to disk or other non-volatile storage, and on resume it’s read back into memory with the help of boot-strapping code, restores the system to the same point of execution where it went to suspend to disk.

Note: This state is correlated with ACPI S4 state

enumerator PM_STATE_SOFT_OFF
Soft off state.
This state consumes a minimal amount of power and requires a large latency in order to return to runtime active state. The contents of system (CPU and memory) will not be preserved, so the system will be restarted as if from initial power-up and kernel boot.

Note: This state is correlated with ACPI G2/S5 state

enumerator PM_STATE_COUNT
Number of power management states (internal use)

Functions

uint8_t pm_state_cpu_get_all(uint8_t cpu, const struct pm_state_info **states)
Obtain information about all supported states by a CPU.

Parameters

• cpu – CPU index.
• states – Where to store the list of supported states.

Returns

Number of supported states.

#include <state.h>

Information about a power management state.

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Public Members

uint8_t substate_id

Some platforms have multiple states that map to one Zephyr power state. This property allows the platform distinguish them. e.g:

```c
power-states {
    state0: state0 {
        compatible = "zephyr,power-state";
        power-state-name = "suspend-to-idle";
        substate-id = <1>;
        min-residency-us = <10000>;
        exit-latency-us = <100>;
    };
    state1: state1 {
        compatible = "zephyr,power-state";
        power-state-name = "suspend-to-idle";
        substate-id = <2>;
        min-residency-us = <20000>;
        exit-latency-us = <200>;
    };
};
```

uint32_t min_residency_us

Minimum residency duration in microseconds. It is the minimum time for a given idle state to be worthwhile energywise.

**Note:** 0 means that this property is not available for this state.

uint32_t exit_latency_us

Worst case latency in microseconds required to exit the idle state.

**Note:** 0 means that this property is not available for this state.

Policy

`group subsys_pm_sys_policy`

System Power Management Policy API.

Defines

`PM_ALL_SUBSTATES`

Special value for ‘all substates’.

Typedefs
typedef void (*pm_policy_latency_changed_cb_t)(int32_t latency)

Callback to notify when maximum latency changes.

**Param latency**
New maximum latency. Positive value represents latency in microseconds. SYS_FOREVER_US value lifts the latency constraint. Other values are forbidden.

**Functions**

void pm_policy_state_lock_get(enum pm_state state, uint8_t substate_id)

Increase a power state lock counter.

A power state will not be allowed on the first call of pm_policy_state_lock_get(). Subsequent calls will just increase a reference count, thus meaning this API can be safely used concurrently. A state will be allowed again after pm_policy_state_lock_put() is called as many times as pm_policy_state_lock_get().

Note that the PM_STATE_ACTIVE state is always allowed, so calling this API with PM_STATE_ACTIVE will have no effect.

**See also:**

pm_policy_state_lock_put()

**Parameters**

- **state** – Power state.
- **substate_id** – Power substate ID. Use PM_ALL_SUBSTATES to affect all the substates in the given power state.

void pm_policy_state_lock_put(enum pm_state state, uint8_t substate_id)

Decrease a power state lock counter.

**See also:**

pm_policy_state_lock_get()

**Parameters**

- **state** – Power state.
- **substate_id** – Power substate ID. Use PM_ALL_SUBSTATES to affect all the substates in the given power state.

bool pm_policy_state_lock_is_active(enum pm_state state, uint8_t substate_id)

Check if a power state lock is active (not allowed).

**Parameters**

- **state** – Power state.
- **substate_id** – Power substate ID. Use PM_ALL_SUBSTATES to affect all the substates in the given power state.

**Return values**

- **true** – if power state lock is active.
- **false** – if power state lock is not active.
void pm_policy_latency_request_add(struct pm_policy_latency_request *req, uint32_t value_us)

Add a new latency requirement.

The system will not enter any power state that would make the system to exceed the given latency value.

Parameters

• req – Latency request.
• value_us – Maximum allowed latency in microseconds.

void pm_policy_latency_request_update(struct pm_policy_latency_request *req, uint32_t value_us)

Update a latency requirement.

Parameters

• req – Latency request.
• value_us – New maximum allowed latency in microseconds.

void pm_policy_latency_request_remove(struct pm_policy_latency_request *req)

Remove a latency requirement.

Parameters

• req – Latency request.

void pm_policy_latency_changed_subscribe(struct pm_policy_latency_subscription *req, pm_policy_latency_changed_cb_t cb)

Subscribe to maximum latency changes.

Parameters

• req – Subscription request.
• cb – Callback function (NULL to disable).

void pm_policy_latency_changed_unsubscribe(struct pm_policy_latency_subscription *req)

Unsubscribe to maximum latency changes.

Parameters

• req – Subscription request.

void pm_policy_event_register(struct pm_policy_event *evt, uint32_t time_us)

Register an event.

Events in the power-management policy context are defined as any source that will wake up the system at a known time in the future. By registering such event, the policy manager will be able to decide whether certain power states are worth entering or not.

See also:

pm_policy_event_unregister

Note: It is mandatory to unregister events once they have happened by using pm_policy_event_unregister(). Not doing so is an API contract violation, because the system would continue to consider them as valid events in the far future, that is, after the cycle counter rollover.
Parameters

- `evt` – Event.
- `time_us` – When the event will occur, in microseconds from now.

```c
void pm_policy_event_update(struct pm_policy_event *evt, uint32_t time_us)
```
Update an event.

See also:

- `pm_policy_event_register`

Parameters

- `evt` – Event.
- `time_us` – When the event will occur, in microseconds from now.

```c
void pm_policy_event_unregister(struct pm_policy_event *evt)
```
Unregister an event.

See also:

- `pm_policy_event_register`

---

```c
define pm_policy_latency_subscription
#include <policy.h>
Latency change subscription.
```

**Note:** All fields in this structure are meant for private usage.

```c
define pm_policy_latency_request
#include <policy.h>
Latency request.
```

**Note:** All fields in this structure are meant for private usage.

```c
define pm_policy_event
#include <policy.h>
Event.
```

**Note:** All fields in this structure are meant for private usage.

---

**Hooks**

- **group subsys_pm_sys_hooks**
  - System Power Management Hooks.

---

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Functions

void pm_state_set(enum pm_state state, uint8_t substate_id)
Put processor into a power state.
This function implements the SoC specific details necessary to put the processor into available power states.

Parameters

• state – Power state.
• substate_id – Power substate id.

void pm_state_exit_post_ops(enum pm_state state, uint8_t substate_id)
Do any SoC or architecture specific post ops after sleep state exits.
This function is a place holder to do any operations that may be needed to be done after sleep state exits. Currently it enables interrupts after resuming from sleep state. In future, the enabling of interrupts may be moved into the kernel.

Parameters

• state – Power state.
• substate_id – Power substate id.

Device PM APIs

group subsys_pm_device
Device Power Management API.

Defines

PM_DEVICE_ISR_SAFE
Flag indicating that runtime PM API for the device can be called from any context.

If PM_DEVICE_ISR_SAFE flag is used for device definition, it indicates that PM actions are synchronous and can be executed from any context. This approach can be used for cases where suspending and resuming is short as it is executed in the critical section. This mode requires less resources (~80 byte less RAM) and allows to use device runtime PM from any context (including interrupts).

PM_DEVICE_DEFINE(dev_id, pm_action_cb, ...)
Define device PM resources for the given device name.

See also:

PM_DEVICE_DT_DEFINE, PM_DEVICE_DT_INST_DEFINE

Note: This macro is a no-op if CONFIG_PM_DEVICE is not enabled.

Parameters

• dev_id – Device id.
• pm_action_cb – PM control callback.
Zephyr Project Documentation, Release 3.6.0-rc3

- Optional flag to indicate that ISR safe. Use `PM_DEVICE_ISR_SAFE` or 0.

`PM_DEVICE_DT_DEFINE(node_id, pm_action_cb, ...)`
Define device PM resources for the given node identifier.

**See also:**

`PM_DEVICE_DT_INST_DEFINE, PM_DEVICE_DEFINE`

**Note:** This macro is a no-op if `CONFIG_PM_DEVICE` is not enabled.

**Parameters**
- `node_id` – Node identifier.
- `pm_action_cb` – PM control callback.
- ... – Optional flag to indicate that device is isr_ok. Use `PM_DEVICE_ISR_SAFE` or 0.

`PM_DEVICE_DT_INST_DEFINE(idx, pm_action_cb, ...)`
Define device PM resources for the given instance.

**See also:**

`PM_DEVICE_DT_DEFINE, PM_DEVICE_DEFINE`

**Note:** This macro is a no-op if `CONFIG_PM_DEVICE` is not enabled.

**Parameters**
- `idx` – Instance index.
- `pm_action_cb` – PM control callback.
- ... – Optional flag to indicate that device is isr_ok. Use `PM_DEVICE_ISR_SAFE` or 0.

`PM_DEVICE_GET(dev_id)`
Obtain a reference to the device PM resources for the given device.

**Parameters**
- `dev_id` – Device id.

**Returns**
Reference to the device PM resources (NULL if device `CONFIG_PM_DEVICE` is disabled).

`PM_DEVICE_DT_GET(node_id)`
Obtain a reference to the device PM resources for the given node.

**Parameters**
- `node_id` – Node identifier.

**Returns**
Reference to the device PM resources (NULL if device `CONFIG_PM_DEVICE` is disabled).

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PM_DEVICE_DT_INST_GET(idx)

Obtain a reference to the device PM resources for the given instance.

**Parameters**

- idx – Instance index.

**Returns**

Reference to the device PM resources (NULL if device CONFIG_PM_DEVICE is disabled).

**Typedefs**

typedef int (*pm_device_action_cb_t)(const struct device *dev, enum pm_device_action action)

Device PM action callback.

**Param dev**

Device instance.

**Param action**

Requested action.

**Retval 0**

If successful.

**Retval -ENOTSUP**

If the requested action is not supported.

**Retval Errno**

Other negative errno on failure.

typedef bool (*pm_device_action_failed_cb_t)(const struct device *dev, int err)

Device PM action failed callback.

**Param dev**

Device that failed the action.

**Param err**

Return code of action failure.

**Return**

True to continue iteration, false to halt iteration.

** Enums **

**enum pm_device_state**

Device power states.

**Values:**

- enumerator PM_DEVICE_STATE_ACTIVE
  
  Device is in active or regular state.

- enumerator PM_DEVICE_STATE_SUSPENDED
  
  Device is suspended.
enumerator PM_DEVICE_STATE_SUSPENDING
    Device is being suspended.

enumerator PM_DEVICE_STATE_OFF
    Device is turned off (power removed).

Note: Device context is lost.

Functions

const char *pm_device_state_str(enum pm_device_state state)
    Get name of device PM state.

Parameters
    • state – State id which name should be returned

int pm_device_action_run(const struct device *dev, enum pm_device_action action)
    Run a pm action on a device.
    This function calls the device PM control callback so that the device does the necessary
    operations to execute the given action.

Parameters
    • dev – Device instance.
### pm_device_children_action_run

Run a pm action on all children of a device.

**Parameters**
- `dev` – Device instance.
- `action` – Device pm action.
- `failure_cb` – Function to call if a child fails the action, can be NULL.

**Return values**
- 0 – If successful.
- -ENOTSUP – If requested state is not supported.
- -EALREADY – If device is already at the requested state.
- -EBUSY – If device is changing its state.
- -ENOSYS – If device does not support PM.
- -EPERM – If device has power state locked.
- `Errno` – Other negative errno on failure.

```c
void pm_device_children_action_run(const struct device *dev, enum pm_device_action action, pm_device_action_failed_cb_t failure_cb)
```

### pm_device_state_get

Obtain the power state of a device.

**Parameters**
- `dev` – Device instance.
- `state` – Pointer where device power state will be stored.

**Return values**
- 0 – If successful.
- -ENOSYS – If device does not implement power management.

```c
int pm_device_state_get(const struct device *dev, enum pm_device_state *state)
```

### pm_device_init_suspended

Initialize a device state to `PM_DEVICE_STATE_SUSPENDED`.

By default device state is initialized to `PM_DEVICE_STATE_ACTIVE`. However in order to save power some drivers may choose to only initialize the device to the suspended state, or actively put the device into the suspended state. This function can therefore be used to notify the PM subsystem that the device is in `PM_DEVICE_STATE_SUSPENDED` instead of the default.

**Parameters**
- `dev` – Device instance.

```c
static inline void pm_device_init_suspended(const struct device *dev)
```

### pm_device_init_off

Initialize a device state to `PM_DEVICE_STATE_OFF`.

By default device state is initialized to `PM_DEVICE_STATE_ACTIVE`. In general, this makes sense because the device initialization function will resume and configure a device, leaving it operational. However, when power domains are enabled, the device may be connected to a switchable power source, in which case it won't be powered at boot. This function can therefore be used to notify the PM subsystem that the device is in `PM_DEVICE_STATE_OFF` instead of the default.

**Parameters**
- `dev` – Device instance.

```c
static inline void pm_device_init_off(const struct device *dev)
```
Parameters

- dev – Device instance.

void pm_device_busy_set(const struct device *dev)

Mark a device as busy.

Devices marked as busy will not be suspended when the system goes into low-power states. This can be useful if, for example, the device is in the middle of a transaction.

See also:

pm_device_busy_clear()

Parameters

- dev – Device instance.

void pm_device_busy_clear(const struct device *dev)

Clear a device busy status.

See also:

pm_device_busy_set()

Parameters

- dev – Device instance.

bool pm_device_is_any_busy(void)

Check if any device is busy.

Return values

- false – If no device is busy
- true – If one or more devices are busy

bool pm_device_is_busy(const struct device *dev)

Check if a device is busy.

Parameters

- dev – Device instance.

Return values

- false – If the device is not busy
- true – If the device is busy

bool pm_device_wakeup_enable(const struct device *dev, bool enable)

Enable or disable a device as a wake up source.

A device marked as a wake up source will not be suspended when the system goes into low-power modes, thus allowing to use it as a wake up source for the system.

Parameters

- dev – Device instance.
- enable – true to enable or false to disable

Return values

- true – If the wakeup source was successfully enabled.
• false – If the wakeup source was not successfully enabled.

bool pm_device_wakeup_is_enabled(const struct device *dev)
Check if a device is enabled as a wake up source.

Parameters
• dev – Device instance.

Return values
• true – if the wakeup source is enabled.
• false – if the wakeup source is not enabled.

bool pm_device_wakeup_is_capable(const struct device *dev)
Check if a device is wake up capable.

Parameters
• dev – Device instance.

Return values
• true – If the device is wake up capable.
• false – If the device is not wake up capable.

void pm_device_state_lock(const struct device *dev)
Lock current device state.
This function locks the current device power state. Once locked the device power state
will not be changed by system power management or device runtime power manage-
ment until unlocked.

See also:
pm_device_state_unlock

Note: The given device should not have device runtime enabled.

Parameters
• dev – Device instance.

void pm_device_state_unlock(const struct device *dev)
Unlock the current device state.
Unlocks a previously locked device pm.

See also:
pm_device_state_lock

Parameters
• dev – Device instance.

bool pm_device_state_is_locked(const struct device *dev)
Check if the device pm is locked.

Parameters
• dev – Device instance.
Return values
• true – If device is locked.
• false – If device is not locked.

bool pm_device_on_power_domain(const struct device *dev)
Check if the device is on a switchable power domain.

Parameters
• dev – Device instance.

Return values
• true – If device is on a switchable power domain.
• false – If device is not on a switchable power domain.

int pm_device_power_domain_add(const struct device *dev, const struct device *domain)
Add a device to a power domain.

Parameters
• dev – Device to be added to the power domain.
• domain – Power domain.

Return values
• 0 – If successful.
• -EALREADY – If device is already part of the power domain.
• -ENOSYS – If the application was built without power domain support.
• -ENOSPC – If there is no space available in the power domain to add the device.

int pm_device_power_domain_remove(const struct device *dev, const struct device *domain)
Remove a device from a power domain.

Parameters
• dev – Device to be removed from the power domain.
• domain – Power domain.

Return values
• 0 – If successful.
• -ENOSYS – If the application was built without power domain support.
• -ENOENT – If device is not in the given domain.

bool pm_device_is_powered(const struct device *dev)
Check if the device is currently powered.

Parameters
• dev – Device instance.

Return values
• true – If device is currently powered, or is assumed to be powered (i.e. it does not support PM or is not under a PM domain)
• false – If device is not currently powered
int pm_device_driver_init(const struct device *dev, pm_device_action_cb_t action_cb)
    Setup a device driver into the lowest valid power mode.
    This helper function is intended to be called at the end of a driver init function to
    automatically setup the device into the lowest power mode. It assumes that the device
    has been configured as if it is in \textit{PM\_DEVICE\_STATE\_OFF}.

    \textbf{Parameters}
    \begin{itemize}
    \item dev – Device instance.
    \item action\_cb – Device PM control callback function.
    \end{itemize}

    \textbf{Return values}
    \begin{itemize}
    \item 0 – On success.
    \item -\text{errno} – Error code from \textit{action\_cb} on failure.
    \end{itemize}

    \begin{verbatim}
struct pm_device_base
    \#include <device.h> Device PM info.
    Structure holds fields which are common for two PM devices: generic and syn-
   chronous.

    \textbf{Public Members}

atomic\_t flags
    Device PM status flags.

enum pm_device_state state
    Device power state.

\textit{pm\_device\_action\_cb\_t} action\_cb
    Device PM action callback.

uint32\_t usage
    Device usage count.
\end{verbatim}

\begin{verbatim}
struct pm_device
    \#include <device.h> Runtime PM info for device with generic PM.
    Generic PM involves suspending and resuming operations which can be blocking, long
    lasting or asynchronous. Runtime PM API is limited when used from interrupt context.

    \textbf{Public Members}

struct \textit{pm\_device\_base} base
    Base info.

const struct device *dev
    Pointer to the device.
\end{verbatim}
struct k_sem lock
    Lock to synchronize the get/put operations.

struct k_event event
    Event var to listen to the sync request events.

struct k_work_delayable work
    Work object for asynchronous calls.

struct pm_device_isr
    #include <device.h> Runtime PM info for device with synchronous PM.

Synchronous PM can be used with devices which suspend and resume operations can be performed in the critical section as they are short and non-blocking. Runtime PM API can be used from any context in that case.

Public Members

struct pm_device_base base
    Base info.

struct k_spinlock lock
    Lock to synchronize the synchronous get/put operations.

Device Runtime PM APIs

group subsys_pm_device_runtime
    Device Runtime Power Management API.

Functions

int pm_device_runtime_auto_enable(const struct device *dev)
    Automatically enable device runtime based on devicetree properties.

Note: Must not be called from application code. See the zephyr:pm-device-runtime-auto property in pm.yaml and z_sys_init_run_level.

Parameters

- dev – Device instance.

Return values

- 0 – If the device runtime PM is enabled successfully or it has not been requested for this device in devicetree.
- -errno – Other negative errno, result of enabled device runtime PM.
int pm_device_runtime_enable(const struct device *dev)
    Enable device runtime PM.
    This function will enable runtime PM on the given device. If the device is in
    PM_DEVICE_STATE_ACTIVE state, the device will be suspended.

See also:
    pm_device_init_suspended()

Function properties (list may not be complete)
    pre-kernel-ok

Parameters
    • dev – Device instance.

Return values
    • 0 – If the device runtime PM is enabled successfully.
    • -EPERM – If device has power state locked.
    • -ENOTSUP – If the device does not support PM.
    • -errno – Other negative errno, result of suspending the device.

int pm_device_runtime_disable(const struct device *dev)
    Disable device runtime PM.
    If the device is currently suspended it will be resumed.

Function properties (list may not be complete)
    pre-kernel-ok

Parameters
    • dev – Device instance.

Return values
    • 0 – If the device runtime PM is disabled successfully.
    • -ENOTSUP – If the device does not support PM.
    • -errno – Other negative errno, result of resuming the device.

int pm_device_runtime_get(const struct device *dev)
    Resume a device based on usage count.
    This function will resume the device if the device is suspended (usage count equal to
    0). In case of a resume failure, usage count and device state will be left unchanged. In
    all other cases, usage count will be incremented.
    If the device is still being suspended as a result of calling
    pm_device_runtime_put_async(), this function will wait for the operation to finish
    to then resume the device.

Function properties (list may not be complete)
    pre-kernel-ok
Note: It is safe to use this function in contexts where blocking is not allowed, e.g. ISR, provided the device PM implementation does not block.

Parameters
- dev – Device instance.

Return values
- 0 – If it succeeds. In case device runtime PM is not enabled or not available this function will be a no-op and will also return 0.
- -EWOUDDBLOCK – If call would block but it is not allowed (e.g. in ISR).
- -errno – Other negative errno, result of the PM action callback.

int pm_device_runtime_put(const struct device *dev)
Suspend a device based on usage count.
This function will suspend the device if the device is no longer required (usage count equal to 0). In case of suspend failure, usage count and device state will be left unchanged. In all other cases, usage count will be decremented (down to 0).

See also:
pm_device_runtime_put_async()

Function properties (list may not be complete)
pre-kernel-ok

Parameters
- dev – Device instance.

Return values
- 0 – If it succeeds. In case device runtime PM is not enabled or not available this function will be a no-op and will also return 0.
- -EALREADY – If device is already suspended (can only happen if get/put calls are unbalanced).
- -errno – Other negative errno, result of the action callback.

int pm_device_runtime_put_async(const struct device *dev, k_timeout_t delay)
Suspend a device based on usage count (asynchronously).
This function will schedule the device suspension if the device is no longer required (usage count equal to 0). In all other cases, usage count will be decremented (down to 0).

See also:
pm_device_runtime_put()

Function properties (list may not be complete)
pre-kernel-ok, async, isr-ok
Note: Asynchronous operations are not supported when in pre-kernel mode. In this case, the function will be blocking (equivalent to `pm_device_runtime_put()`).

Parameters

- **dev** – Device instance.
- **delay** – Minimum amount of time before triggering the action.

Return values

- **0** – If it succeeds. In case device runtime PM is not enabled or not available this function will be a no-op and will also return 0.
- **-EBUSY** – If the device is busy.
- **-EALREADY** – If device is already suspended (can only happen if get/put calls are unbalanced).

```c
bool pm_device_runtime_is_enabled(const struct device *dev)
```

Check if device runtime is enabled for a given device.

See also:

- `pm_device_runtime_enable()`

Function properties (list may not be complete)

- **pre-kernel-ok**

Parameters

- **dev** – Device instance.

Return values

- **true** – If device has device runtime PM enabled.
- **false** – If the device has device runtime PM disabled.

### 4.20 OS Abstraction

OS abstraction layers (OSAL) provide wrapper function APIs that encapsulate common system functions offered by any operating system. These APIs make it easier and quicker to develop for, and port code to multiple software and hardware platforms.

These sections describe the software and hardware abstraction layers supported by the Zephyr RTOS.

#### 4.20.1 POSIX

**Overview**

The Portable Operating System Interface (POSIX) is a family of standards specified by the IEEE Computer Society for maintaining compatibility between operating systems. Zephyr implements a subset of the standard POSIX API specified by IEEE 1003.1-2017 (also known as POSIX-1.2017).
**Note:** This page does not document Zephyr's POSIX architecture, which is used to run Zephyr as a native application under the host operating system for prototyping, test, and diagnostic purposes.

With the POSIX support available in Zephyr, an existing POSIX conformant application can be ported to run on the Zephyr kernel, and therefore leverage Zephyr features and functionality. Additionally, a library designed to be POSIX conformant can be ported to Zephyr kernel based applications with no changes.

The POSIX API is an increasingly popular OSAL (operating system abstraction layer) for IoT and embedded applications, as can be seen in Zephyr, AWS:FreeRTOS, TI-RTOS, and NuttX.

Benefits of POSIX support in Zephyr include:

- Offering a familiar API to non-embedded programmers, especially from Linux
- Enabling reuse (portability) of existing libraries based on POSIX APIs
- Providing an efficient API subset appropriate for small (MCU) embedded systems

**POSIX Subprofiles** While Zephyr supports running multiple threads (<threads_v2> (possibly in an SMP <smp_arch> configuration), as well as Virtual Memory and MMUs <memory_management_api>, Zephyr code and data normally share a common address space. The Zephyr kernel executable code and the application executable code are typically compiled into the same binary artifact. From that perspective, Zephyr apps can be seen as running in the context of a single process.

While multi-purpose operating systems (OS) offer full POSIX conformance, Real-Time Operating Systems (RTOS) such as Zephyr typically serve a fixed-purpose, have limited hardware resources, and experience limited user interaction. In such systems, full POSIX conformance can be impractical and unnecessary.

For that reason, POSIX defined the following Application Environment Profiles (AEP) as part of IEEE 1003.13-2003 (also known as POSIX.13-2003).

- Minimal Realtime System Profile (<PSE51>)
- Realtime Controller System Profile (<PSE52>)
Zephyr Project Documentation, Release 3.6.0-rc3

- Dedicated Realtime System Profile (PSE53)
- Multi-Purpose Realtime System (PSE54)

POSIX.13-2003 AEP were formalized in 2003 via “Units of Functionality” but the specification is now inactive (for reference only). Nevertheless, the intent is still captured as part of POSIX-1.2017 via Options and Option Groups.

For more information, please see IEEE 1003.1-2017, Section E, Subprofiling Considerations.

**POSIX Applications in Zephyr** A POSIX app in Zephyr is built like any other app and therefore requires the usual prj.conf, CMakeLists.txt, and source code. For example, the app below leverages the nanosleep() and perror() POSIX functions.

**Listing 1: prj.conf** for a simple POSIX app in Zephyr

```
CONFIG_POSIX_API=y
```

**Listing 2: A simple app that uses Zephyr's POSIX API**

```c
#include <stddef.h>
#include <stdio.h>
#include <time.h>

void megasleep(size_t megaseconds)
{
    struct timespec ts = {
        .tv_sec = megaseconds * 1000000,
        .tv_nsec = 0,
    };

    printf("See you in a while!\n");
    if (nanosleep(&ts, NULL) == -1) {
        perror("nanosleep");
    }
}

int main()
{
    megasleep(42);
    return 0;
}
```

For more examples of POSIX applications, please see the POSIX sample applications.

**Configuration** Like most features in Zephyr, POSIX features are highly configurable but disabled by default. Users must explicitly choose to enable POSIX options via Kconfig selection. Indeed, there are many Kconfig options in Zephyr for the POSIX API to allow for feature selection at various levels of granularity.

Alternatively, users may enable one of the Kconfig options below as a shortcut to enable multiple Option Groups.

- CONFIG_POSIX_API
- CONFIG_PTHREAD_IPC

**Note:** Since the POSIX environment in Zephyr is fully configurable via Kconfig, configurations that require modifying features should not be made if strict compliance is required (POSIX-1.2017, section 2.1.3.1).
POSIX Conformance

As per IEEE 1003.1-2017, this section details Zephyr's POSIX conformance.

Note: As per POSIX 1003.13, single process mode is supported directly by both PSE51 and PSE52 profiles. While Zephyr includes support for many features found in PSE53, PSE53 itself requires supporting multiple processes. Since supporting multiple processes is beyond the scope of Zephyr's current design, some features requiring multi-process capabilities may exhibit undefined behaviour, which we denote with the † (obelus) symbol.

Note: Features listed in various POSIX Options or Option Groups may be provided in whole or in part by a conformant C library implementation. This includes (but is not limited to) POSIX Extensions to the ISO C Standard (CX).

POSIX System Interfaces

Table 5: POSIX System Interfaces

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Support</th>
<th>Remarks</th>
</tr>
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<tbody>
<tr>
<td>_POSIX_CHOWN_RESTRICTED</td>
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<td>_POSIX_NO_TRUNC</td>
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<td>_POSIX_VDISABLE</td>
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Table 6: POSIX System Interfaces

<table>
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<th>Symbol</th>
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<th>Remarks</th>
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<tbody>
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<td>_POSIX_JOB_CONTROL</td>
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<td>_POSIX_REGEXP</td>
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<td>†</td>
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<td>_POSIX_SAVED_IDS</td>
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<td>†</td>
</tr>
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<td>_POSIX_SHELL</td>
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Table 7: POSIX System Interfaces

<table>
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<th>Symbol</th>
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<tbody>
<tr>
<td>_POSIX_VERSION</td>
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</tr>
<tr>
<td>_POSIX_BARRIERS</td>
<td>200809!</td>
<td>CONFIG_PTHREAD_BARRIER</td>
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<tr>
<td>_POSIX_CLOCK_SELECTION</td>
<td>200809!</td>
<td>CONFIG_POSIX_CLOCK</td>
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<tr>
<td>_POSIX_MAPPED_FILES</td>
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<td>†</td>
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<td>_POSIX_MEMORY_PROTECTION</td>
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<td>_POSIX_REALTIME_SIGNALS</td>
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<tr>
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<td>_POSIX2_C_BIND</td>
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### Table 8: POSIX System Interfaces (Optional)

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<td>_POSIX_FSYNC</td>
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<td>_POSIX_IPV6</td>
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<td>_POSIX_MEMLOCK_RANGE</td>
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<td>_POSIX_MESSAGE_PASSING</td>
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<td>CONFIG_POSIX_MQUEUE</td>
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<tr>
<td>_POSIX_MONOTONIC_CLOCK</td>
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<td>CONFIG_POSIX_CLOCK</td>
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<td>_POSIX_PRIORITY_SCHEDULING</td>
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<td>CONFIG_POSIX_PRIORITY_SCHEDULING (will fail with ENOSYS/)</td>
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<td>_POSIX_TRACE_LOG</td>
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<td>_XOPEN_UNIX</td>
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**POSIX Shell and Utilities**  Zephyr does not support a POSIX shell or utilities at this time.
Table 9: POSIX Shell and Utilities

<table>
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<td>_POSIX2_FORT_DEV</td>
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<td>_POSIX2_LOCALEDEF</td>
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<td>_POSIX2_PBS</td>
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<td>_POSIX2_PBS_ACCOUNTING</td>
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<td>_POSIX2_PBS_LOCATE</td>
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<td>_POSIX2_PBS_MESSAGE</td>
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<td>_POSIX2_SW_DEV</td>
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<td>_POSIX2_UPE</td>
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<td>_POSIX2_UNIX</td>
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<td>_POSIX2_UUCP</td>
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</table>

XSI Conformance

XSI System Interfaces

Table 10: XSI System Interfaces

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<tr>
<th>Symbol</th>
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<tbody>
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<td>_POSIX_THREAD_ATTR_STACKSIZE</td>
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<td>CONFIG_PTHREAD</td>
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<td>_POSIX_THREAD_PROCESS_SHARED</td>
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</table>

POSIX Application Environment Profiles (AEP)

Although inactive, IEEE 1003.13-2003 defined a number of AEP that inspired the modern subprofiling options of IEEE 1003.1-2017. The single-purpose realtime system profiles are listed below, for reference, in terms that agree with the current POSIX-1 standard. PSE54 is not considered at this time.

Minimal Realtime System Profile (PSE51)

Table 11: PSE51 System Interfaces

<table>
<thead>
<tr>
<th>Symbol</th>
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### Table 12: PSE51 Option Groups

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<tr>
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<td>POSIX_DEVICE_IO</td>
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<tr>
<td>POSIX_FILE_LOCKING</td>
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</tr>
<tr>
<td>POSIX_SIGNALS</td>
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<tr>
<td>POSIX_SINGLE_PROCESS</td>
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</tr>
<tr>
<td>POSIX_THREADS_BASE</td>
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<tr>
<td>XSI_THREADS_EXT</td>
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### Table 13: PSE51 Option Requirements

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<th>Symbol</th>
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<tbody>
<tr>
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<td>_POSIX_FSYNC</td>
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</tr>
<tr>
<td>_POSIX_MEMLOCK</td>
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</tr>
<tr>
<td>_POSIX_MEMLOCK_RANGE</td>
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<td></td>
</tr>
<tr>
<td>_POSIX_MONOTONIC_CLOCK</td>
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<td>CONFIG_POSIX_CLOCK</td>
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<tr>
<td>_POSIX_REALTIME_SIGNALS</td>
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</tr>
<tr>
<td>_POSIX_SEMAPHORES</td>
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<tr>
<td>_POSIX_SHARED_MEMORY_OBJECTS</td>
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<td>_POSIX_SYNCHRONIZED_IO</td>
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</tr>
<tr>
<td>_POSIX_THREAD_ATTR_STACKADDR</td>
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<td>CONFIG_PTHREAD</td>
</tr>
<tr>
<td>_POSIX_THREAD_ATTR_STACKSIZE</td>
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<td>CONFIG_PTHREAD</td>
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<td>_POSIX_THREAD_CPUTIME</td>
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<td>_POSIX_THREAD_PRIO_INHERIT</td>
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<td>_POSIX_THREAD_PRIO_PROTECT</td>
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<tr>
<td>_POSIX_THREAD_PRIORITY_SCHEDULING</td>
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<td>CONFIG_POSIX_PRIORITY_SCHEDULING (will fail with ENOSYS!)</td>
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<td>_POSIX_THREAD_SPORADIC_SERVER</td>
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<td>_POSIX_TIMEOUTS</td>
<td>200809l</td>
<td>CONFIG_PTHREAD_IPC</td>
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### Realtime Controller System Profile (PSE52)

#### Table 14: PSE52 System Interfaces

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<tr>
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Table 15: PSE52 Option Groups

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<tbody>
<tr>
<td>POSIX_C_LANG_JUMP</td>
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<td>POSIX_C_LANG_JUMP</td>
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<tr>
<td>POSIX_C_LANG_MATH</td>
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<td>POSIX_C_LANG_SUPPORT</td>
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<td>POSIX_DEVICE_IO</td>
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<td>POSIX_FD_MGMT</td>
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<tr>
<td>POSIX_FILE_LOCKING</td>
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<td>POSIX_FILE_SYSTEM</td>
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<td>POSIX_SIGNALS</td>
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<td>POSIX_THREADS_BASE</td>
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<td>XSI_THREADS_EXT</td>
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Table 16: PSE52 Option Requirements

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<tr>
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<td>_POSIX_MAPPED_FILES</td>
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<td>_POSIX_MEMLOCK</td>
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<td>_POSIX_MEMLOCK_RANGE</td>
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<td>_POSIX_MESSAGE_PASSING</td>
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<td>CONFIG_POSIX_MQUEUE</td>
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<td>_POSIX_MONOTONIC_CLOCK</td>
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<td>CONFIG_PTHREAD_IPC</td>
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<td>CONFIG_PTHREAD_IPC</td>
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<td>_POSIX_TIMERS</td>
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Dedicated Realtime System Profile (PSE53)

Table 17: PSE53 System Interfaces

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### Table 18: PSE53 Option Groups

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<tr>
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</tr>
<tr>
<td>POSIX_SIGNALS</td>
<td>†</td>
<td></td>
</tr>
<tr>
<td>POSIX_SIGNAL_JUMP</td>
<td>†</td>
<td></td>
</tr>
<tr>
<td>POSIX_SINGLE_PROCESS</td>
<td>†</td>
<td></td>
</tr>
<tr>
<td>POSIX_THREADS_BASE</td>
<td>yes</td>
<td>†</td>
</tr>
<tr>
<td>XSI_THREADS_EXT</td>
<td>yes</td>
<td>†</td>
</tr>
</tbody>
</table>

### Table 19: PSE53 Option Requirements

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Support</th>
<th>Remarks</th>
</tr>
</thead>
<tbody>
<tr>
<td>_POSIXASYNCHRONOUS_IO</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_CLOCK_SELECTION</td>
<td>200809L</td>
<td>CONFIG_POSIX_CLOCK</td>
</tr>
<tr>
<td>_POSIX_CPU_TIME</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_FSYNC</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_MAPPED_FILES</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_MEMLOCK</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_MEMLOCK_RANGE</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_MEMORY_PROTECTION</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_MESSAGE_PASSING</td>
<td>200809L</td>
<td>CONFIG_POSIX_MQUEUE</td>
</tr>
<tr>
<td>_POSIX_MONOTONIC_CLOCK</td>
<td>200809L</td>
<td>CONFIG_POSIX_CLOCK</td>
</tr>
<tr>
<td>_POSIX_PRIORITY_SCHEDULING</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_PREFERRED_SCHEDULING</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_RAW_SOCKETS</td>
<td>200809L</td>
<td>CONFIG_NET_SOCKETS</td>
</tr>
<tr>
<td>_POSIX_REALTIME_SIGNALS</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_SEMAPHORES</td>
<td>200809L</td>
<td>CONFIG_PTHREAD_IPC</td>
</tr>
<tr>
<td>_POSIX_SHARED_MEMORY_OBJECTS</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_SPAWN</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_SPORADIC_SERVER</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_SPAWN</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_SYNCHRONIZED_IO</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_THREAD_ATTR_STACKADDR</td>
<td>200809L</td>
<td>CONFIG_PTHREAD</td>
</tr>
<tr>
<td>_POSIX_THREAD_ATTR_STACKSIZE</td>
<td>200809L</td>
<td>CONFIG_PTHREAD</td>
</tr>
<tr>
<td>_POSIX_THREAD_CPUTIME</td>
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<tr>
<td>_POSIX_THREAD_PRIORITY_INHERIT</td>
<td>200809L</td>
<td>CONFIG_PTHREAD_MUTEX</td>
</tr>
<tr>
<td>_POSIX_THREAD_PRIORITY_PROTECT</td>
<td>-1</td>
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<tr>
<td>_POSIX_THREAD_PRIORITY_SCHEDULING</td>
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<td></td>
</tr>
<tr>
<td>_POSIX_THREAD_PROCESS_SHARED</td>
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</tr>
<tr>
<td>_POSIX_THREAD_SPORADIC_SERVER</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_TIMEOUTS</td>
<td>200809L</td>
<td>CONFIG_PTHREAD_IPC</td>
</tr>
<tr>
<td>_POSIX_TIMERS</td>
<td>200809L</td>
<td>CONFIG_POSIX_CLOCK</td>
</tr>
<tr>
<td>_POSIX_TRACE</td>
<td>-1</td>
<td></td>
</tr>
<tr>
<td>_POSIX_TRACE_EVENT_FILTER</td>
<td>-1</td>
<td></td>
</tr>
</tbody>
</table>

continues on next page
Implementation Details

In many ways, Zephyr provides support like any POSIX OS; API bindings are provided in the C programming language, POSIX headers are available in the standard include path, when configured.

Unlike other multi-purpose POSIX operating systems

- Zephyr is not “a POSIX OS”. The Zephyr kernel was not designed around the POSIX standard, and POSIX support is an opt-in feature
- Zephyr apps are not linked separately, nor do they execute as subprocesses
- Zephyr, libraries, and application code are compiled and linked together, running similarly to a single-process application, in a single (possibly virtual) address space
- Zephyr does not provide a POSIX shell, compiler, utilities, and is not self-hosting.

Note: Unlike the Linux kernel or FreeBSD, Zephyr does not maintain a static table of system call numbers for each supported architecture, but instead generates system calls dynamically at build time. See System Calls <syscalls> for more information.

Design

As a library, Zephyr's POSIX API implementation makes an effort to be a thin abstraction layer between the application, middleware, and the Zephyr kernel.

Some general design considerations:

- The POSIX interface and implementations should be part of Zephyr's POSIX library, and not elsewhere, unless required both by the POSIX API implementation and some other feature. An example where the implementation should remain part of the POSIX implementation is getopt(). Examples where the implementation should be part of separate libraries are multithreading and networking.
- When the POSIX API and another Zephyr subsystem both rely on a feature, the implementation of that feature should be as a separate Zephyr library that can be used by both the POSIX API and the other library or subsystem. This reduces the likelihood of dependency cycles in code. When practical, that rule should expand to include macros. In the example below, libposix depends on libzfoo for the implementation of some functionality “foo” in Zephyr. If libzfoo also depends on libposix, then there is a dependency cycle. The cycle can be removed via mutual dependency, libcommon.
- POSIX API calls should be provided as regular callable C functions; if a Zephyr System Call <syscalls> is needed as part of the implementation, the declaration and the implementation of that system call should be hidden behind the POSIX API.

Subprofiling Option Groups

POSIX_THREADS_BASE  The basic assumption in this profile is that the system consists of a single (implicit) process with multiple threads. Therefore, the standard requires all basic thread services, except those related to multiple processes.
Fig. 13: Dependency cycle between POSIX and another Zephyr library

Fig. 14: Mutual dependencies between POSIX and other Zephyr libraries

Table 20: POSIX_THREADS_BASE

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_atfork()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getdetachstate()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getschedparam()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setdetachstate()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setschedparam()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrier_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrier_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrier_wait()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrierattr_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrierattr_getpshared()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrierattr_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrierattr_setpshared()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cancel()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cleanup_pop()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cleanup_push()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_broadcast()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_signal()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_timedwait()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_wait()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_condattr_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_condattr_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_create()</td>
<td>yes</td>
</tr>
</tbody>
</table>

continues on next page
Table 20 – continued from previous page

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_detach()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_equal()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_exit()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_getspecific()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_join()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_key_create()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_key_delete()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_kill()</td>
<td></td>
</tr>
<tr>
<td>pthread_mutex_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_lock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_trylock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_unlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutexattr_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutexattr_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_once()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_self()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_setcancelstate()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_setspecific()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_sigmask()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_testcancel()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**POSIX_THREADS_EXT**  This table lists service support status in Zephyr:

Table 21: POSIX_THREADS_EXT

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_attr_getguardsize()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setguardsize()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutexattr_gettype()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutexattr_settype()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**XSI_THREADS_EXT**  The XSI_THREADS_EXT option group is required because it provides functions to control a thread’s stack. This is considered useful for any real-time application.

This table lists service support status in Zephyr:

Table 22: XSI_THREADS_EXT

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_attr_getstack()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setstack()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_getconcurrency()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_setconcurrency()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**POSIX_C_LANG_JUMP**  The POSIX_C_LANG_JUMP Option Group is included in the ISO C standard.

**Note:** When using Newlib, Picolibc, or other C libraries conforming to the ISO C Standard, the POSIX_C_LANG_JUMP Option Group is considered supported.
Table 23: POSIX_C_LANG_JUMP

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>setjmp()</td>
<td>yes</td>
</tr>
<tr>
<td>longjmp()</td>
<td>yes</td>
</tr>
</tbody>
</table>

POSIX_C_LANG_MATH  The POSIX_C_LANG_MATH Option Group is included in the ISO C standard.

**Note:** When using Newlib, Picolibc, or other C libraries conforming to the ISO C Standard, the POSIX_C_LANG_MATH Option Group is considered supported.

Please refer to Subprofiling Considerations for details on the POSIX_C_LANG_MATH Option Group.

POSIX_C_LANG_SUPPORT  The POSIX_C_LANG_SUPPORT option group contains the general ISO C Library.

**Note:** When using Newlib, Picolibc, or other C libraries conforming to the ISO C Standard, the entire POSIX_C_LANG_SUPPORT Option Group is considered supported.

Please refer to Subprofiling Considerations for details on the POSIX_C_LANG_SUPPORT Option Group.

For more information on developing Zephyr applications in the C programming language, please refer to details.

POSIX_SINGLE_PROCESS  The POSIX_SINGLE_PROCESS option group contains services for single process applications.

Table 24: POSIX_SINGLE_PROCESS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>confstr()</td>
<td></td>
</tr>
<tr>
<td>environ</td>
<td></td>
</tr>
<tr>
<td>errno</td>
<td>yes</td>
</tr>
<tr>
<td>getenv()</td>
<td></td>
</tr>
<tr>
<td>setenv()</td>
<td></td>
</tr>
<tr>
<td>sysconf()</td>
<td>yes</td>
</tr>
<tr>
<td>uname()</td>
<td>yes</td>
</tr>
<tr>
<td>unsetenv()</td>
<td></td>
</tr>
</tbody>
</table>

POSIX_SIGNALS  Signal services are a basic mechanism within POSIX-based systems and are required for error and event handling.
### Table 25: POSIX_SIGNALS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>abort()</td>
<td>yes</td>
</tr>
<tr>
<td>alarm()</td>
<td></td>
</tr>
<tr>
<td>kill()</td>
<td></td>
</tr>
<tr>
<td>pause()</td>
<td></td>
</tr>
<tr>
<td>sigaction()</td>
<td></td>
</tr>
<tr>
<td>sigaddset()</td>
<td>yes</td>
</tr>
<tr>
<td>sigdelset()</td>
<td>yes</td>
</tr>
<tr>
<td>sigemptyset()</td>
<td>yes</td>
</tr>
<tr>
<td>sigfillset()</td>
<td>yes</td>
</tr>
<tr>
<td>sigismember()</td>
<td>yes</td>
</tr>
<tr>
<td>signal()</td>
<td></td>
</tr>
<tr>
<td>sigpending()</td>
<td></td>
</tr>
<tr>
<td>sigprocmask()</td>
<td>yes</td>
</tr>
<tr>
<td>sigsuspend()</td>
<td></td>
</tr>
<tr>
<td>sigwait()</td>
<td></td>
</tr>
<tr>
<td>strsignal()</td>
<td>yes</td>
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</table>

### POSIX_DEVICE_IO

Table 26: POSIX_DEVICE_IO

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>FD_CLR()</td>
<td>yes</td>
</tr>
<tr>
<td>FD_ISSET()</td>
<td>yes</td>
</tr>
<tr>
<td>FD_SET()</td>
<td>yes</td>
</tr>
<tr>
<td>FD_ZERO()</td>
<td>yes</td>
</tr>
<tr>
<td>clearerr()</td>
<td>yes</td>
</tr>
<tr>
<td>close()</td>
<td>yes</td>
</tr>
<tr>
<td>fclose()</td>
<td></td>
</tr>
<tr>
<td>fdopen()</td>
<td></td>
</tr>
<tr>
<td>feof()</td>
<td></td>
</tr>
<tr>
<td>ferror()</td>
<td></td>
</tr>
<tr>
<td>fflush()</td>
<td></td>
</tr>
<tr>
<td>fgetc()</td>
<td></td>
</tr>
<tr>
<td>fgets()</td>
<td></td>
</tr>
<tr>
<td>fileno()</td>
<td></td>
</tr>
<tr>
<td>fopen()</td>
<td></td>
</tr>
<tr>
<td>fprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>fputc()</td>
<td>yes</td>
</tr>
<tr>
<td>fputs()</td>
<td>yes</td>
</tr>
<tr>
<td>fread()</td>
<td></td>
</tr>
<tr>
<td>freopen()</td>
<td></td>
</tr>
<tr>
<td>fscanf()</td>
<td></td>
</tr>
<tr>
<td>fwrite()</td>
<td>yes</td>
</tr>
<tr>
<td>getc()</td>
<td></td>
</tr>
<tr>
<td>getchar()</td>
<td></td>
</tr>
<tr>
<td>gets()</td>
<td></td>
</tr>
<tr>
<td>open()</td>
<td>yes</td>
</tr>
<tr>
<td>perror()</td>
<td>yes</td>
</tr>
<tr>
<td>poll()</td>
<td>yes</td>
</tr>
<tr>
<td>printf()</td>
<td>yes</td>
</tr>
</tbody>
</table>

continues on next page
Table 26 – continued from previous page

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pread()</td>
<td>yes</td>
</tr>
<tr>
<td>pselect()</td>
<td></td>
</tr>
<tr>
<td>putc()</td>
<td></td>
</tr>
<tr>
<td>putchar()</td>
<td>yes</td>
</tr>
<tr>
<td>puts()</td>
<td>yes</td>
</tr>
<tr>
<td>pwrite()</td>
<td></td>
</tr>
<tr>
<td>read()</td>
<td>yes</td>
</tr>
<tr>
<td>scanf()</td>
<td></td>
</tr>
<tr>
<td>select()</td>
<td>yes</td>
</tr>
<tr>
<td>setbuf()</td>
<td></td>
</tr>
<tr>
<td>setvbuf()</td>
<td></td>
</tr>
<tr>
<td>stderr</td>
<td></td>
</tr>
<tr>
<td>stdin</td>
<td></td>
</tr>
<tr>
<td>stdout</td>
<td></td>
</tr>
<tr>
<td>ungetc()</td>
<td></td>
</tr>
<tr>
<td>vfprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>vfscanf()</td>
<td></td>
</tr>
<tr>
<td>vprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>vscanf()</td>
<td></td>
</tr>
<tr>
<td>write()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**POSIX_BARRIERS**

Table 27: POSIX_BARRIERS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_barrier_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrier_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrier_wait()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrierattr_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_barrierattr_init()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**POSIX_CLOCK_SELECTION**

Table 28: POSIX_CLOCK_SELECTION

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_condattr_getclock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_condattr_setclock()</td>
<td>yes</td>
</tr>
<tr>
<td>clock_nanosleep()</td>
<td>yes</td>
</tr>
</tbody>
</table>
**POSIX_SEMAPHORES**

Table 29: POSIX_SEMAPHORES

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>sem_close()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_getvalue()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_init()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_open()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_post()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_trywait()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_unlink()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_wait()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**POSIX_SPIN_LOCKS**

Table 30: POSIX_SPIN_LOCKS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_spin_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_spin_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_spin_lock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_spin_trylock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_spin_unlock()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**POSIX_TIMERS**

Table 31: POSIX_TIMERS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>clock_getres()</td>
<td></td>
</tr>
<tr>
<td>clock_gettime()</td>
<td>yes</td>
</tr>
<tr>
<td>clock_settime()</td>
<td>yes</td>
</tr>
<tr>
<td>nanosleep()</td>
<td>yes</td>
</tr>
<tr>
<td>timer_create()</td>
<td></td>
</tr>
<tr>
<td>timer_delete()</td>
<td>yes</td>
</tr>
<tr>
<td>timer_gettime()</td>
<td>yes</td>
</tr>
<tr>
<td>timer_getoverrun</td>
<td>yes</td>
</tr>
<tr>
<td>timer_settime()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**Additional POSIX Options**
### _POSIX_MESSAGE_PASSING

Table 32: _POSIX_MESSAGE_PASSING

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>mq_close()</td>
<td>yes</td>
</tr>
<tr>
<td>mq_getattr()</td>
<td>yes</td>
</tr>
<tr>
<td>mq_notify()</td>
<td>yes</td>
</tr>
<tr>
<td>mq_open()</td>
<td>yes</td>
</tr>
<tr>
<td>mq_receive()</td>
<td>yes</td>
</tr>
<tr>
<td>mq_send()</td>
<td>yes</td>
</tr>
<tr>
<td>mq_setattr()</td>
<td>yes</td>
</tr>
<tr>
<td>mq_unlink()</td>
<td>yes</td>
</tr>
</tbody>
</table>

### _POSIX_PRIORITY_SCHEDULING

Table 33: _POSIX_PRIORITY_SCHEDULING

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>sched_get_priority_max()</td>
<td>yes</td>
</tr>
<tr>
<td>sched_get_priority_min()</td>
<td>yes</td>
</tr>
<tr>
<td>sched_getparam()</td>
<td>yes</td>
</tr>
<tr>
<td>sched_getscheduler()</td>
<td>yes</td>
</tr>
<tr>
<td>sched_rr_get_interval()</td>
<td>yes</td>
</tr>
<tr>
<td>sched_setparam()</td>
<td>yes</td>
</tr>
<tr>
<td>sched_setscheduler()</td>
<td>yes</td>
</tr>
<tr>
<td>sched_yield()</td>
<td>yes</td>
</tr>
</tbody>
</table>

### _POSIX_READER_WRITER_LOCKS

Table 34: _POSIX_READER_WRITER_LOCKS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_rwlock_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlock_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlock_rdlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlock_tryrdlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlock_trywrlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlock_unlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlock_wrlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlockattr_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlockattr_getpshared()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlockattr_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlockattr_setpshared()</td>
<td>yes</td>
</tr>
</tbody>
</table>

### _POSIX_THREAD_ATTR_STACKADDR

Table 35: _POSIX_THREAD_ATTR_STACKADDR

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_attr_getstackaddr()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setstackaddr()</td>
<td>yes</td>
</tr>
</tbody>
</table>
### _POSIX_THREAD_ATTR_STACKSIZE

Table 36: _POSIX_THREAD_ATTR_STACKSIZE

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_attr_getstacksize()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setstacksize()</td>
<td>yes</td>
</tr>
</tbody>
</table>

### _POSIX_THREAD_PRIORITY_SCHEDULING

Table 37: _POSIX_THREAD_PRIORITY_SCHEDULING

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_attr_getinheritsched()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getschedpolicy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getscope()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getsetinheritsched()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getsetschedpolicy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getsetschedscope()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setschedulers()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setschedpolicy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setschedprio()</td>
<td>yes</td>
</tr>
</tbody>
</table>

### _POSIX_THREAD_SAFE_FUNCTIONS

Table 38: _POSIX_THREAD_SAFE_FUNCTIONS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>asctime_r()</td>
<td>yes</td>
</tr>
<tr>
<td>ctime_r()</td>
<td>yes</td>
</tr>
<tr>
<td>flockfile()</td>
<td>yes</td>
</tr>
<tr>
<td>ftrylockfile()</td>
<td>yes</td>
</tr>
<tr>
<td>funlockfile()</td>
<td>yes</td>
</tr>
<tr>
<td>getc_unlocked()</td>
<td>yes</td>
</tr>
<tr>
<td>getchar_unlocked()</td>
<td>yes</td>
</tr>
<tr>
<td>getgrgid_r()</td>
<td>yes</td>
</tr>
<tr>
<td>getgrnam_r()</td>
<td>yes</td>
</tr>
<tr>
<td>getpwnam_r()</td>
<td>yes</td>
</tr>
<tr>
<td>getpwuid_r()</td>
<td>yes</td>
</tr>
<tr>
<td>gmtime_r()</td>
<td>yes</td>
</tr>
<tr>
<td>localtime_r()</td>
<td>yes</td>
</tr>
<tr>
<td>putc_unlocked()</td>
<td>yes</td>
</tr>
<tr>
<td>putchar_unlocked()</td>
<td>yes</td>
</tr>
<tr>
<td>rand_r()</td>
<td>yes</td>
</tr>
<tr>
<td>readdir_r()</td>
<td>yes</td>
</tr>
<tr>
<td>strerror_r()</td>
<td>yes</td>
</tr>
<tr>
<td>strtok_r()</td>
<td>yes</td>
</tr>
<tr>
<td>strftime_r()</td>
<td>yes</td>
</tr>
</tbody>
</table>
**_POSIX_TIMEOUTS**

Table 39: _POSIX_TIMEOUTS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>mq_timedreceive()</td>
<td>yes</td>
</tr>
<tr>
<td>mq_timedsend()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_timedlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlock_timedrdlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_rwlock_timedwrlock()</td>
<td>yes</td>
</tr>
<tr>
<td>sem_timedwait()</td>
<td>yes</td>
</tr>
<tr>
<td>posix_trace_timedgetnext_event()</td>
<td></td>
</tr>
</tbody>
</table>

**_XOPEN_STREAMS**

Table 40: _XOPEN_STREAMS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>fattach()</td>
<td></td>
</tr>
<tr>
<td>fdetach()</td>
<td></td>
</tr>
<tr>
<td>getmsg()</td>
<td></td>
</tr>
<tr>
<td>getpmsg()</td>
<td></td>
</tr>
<tr>
<td>ioctl()</td>
<td>yes</td>
</tr>
<tr>
<td>isastream()</td>
<td></td>
</tr>
<tr>
<td>putmsg()</td>
<td></td>
</tr>
<tr>
<td>putpmsg()</td>
<td></td>
</tr>
</tbody>
</table>

**Configuration Options**

This is a non-exhaustive list of specific Configuration System (Kconfig) options relating to Zephyr’s implementation of the POSIX API.

- `CONFIG_EVENTFD`
- `CONFIG_EVENTFD_MAX`
- `CONFIG_FDTABLE`
- `CONFIG_FNMATCH`
- `CONFIG_GETOPT`
- `CONFIG_GETOPT_LONG`
- `CONFIG_MAX_PTHREAD_BARRIER_COUNT`
- `CONFIG_MAX_PTHREAD_COUNT`
- `CONFIG_MAX_PTHREAD_KEY_COUNT`
- `CONFIG_MAX_PTHREAD_MUTEX_COUNT`
- `CONFIG_MAX_PTHREAD_SPINLOCK_COUNT`
- `CONFIG_MAX_TIMER_COUNT`
- `CONFIG_MQUEUE_NAMELEN_MAX`
- `CONFIG_MSG_COUNT_MAX`
- `CONFIG_MSG_SIZE_MAX`
- `CONFIG_NET_SOCKETPAIR`
4.20.2 CMSIS RTOS v1

Cortex-M Software Interface Standard (CMSIS) RTOS is a vendor-independent hardware abstraction layer for the ARM Cortex-M processor series and defines generic tool interfaces. Though it was originally defined for ARM Cortex-M microcontrollers alone, it could be easily extended to other microcontrollers making it generic. For more information on CMSIS RTOS v1, please refer to [CMSIS-RTOS2 Documentation](http://www.keil.com/pack/doc/CMSIS/RTOS/html/index.html).

4.20.3 CMSIS RTOS v2

Cortex-M Software Interface Standard (CMSIS) RTOS is a vendor-independent hardware abstraction layer for the ARM Cortex-M processor series and defines generic tool interfaces. Though it was originally defined for ARM Cortex-M microcontrollers alone, it could be easily extended to other microcontrollers making it generic. For more information on CMSIS RTOS v2, please refer to the CMSIS-RTOS2 Documentation.
Features not supported in Zephyr implementation

**Kernel**

- `osKernelGetState`, `osKernelSuspend`, `osKernelResume`, `osKernelInitialize` and `osKernelStart` are not supported.

**Mutex**

- `osMutexPrioInherit` is supported by default and is not configurable, you cannot select/unselect this attribute.
- `osMutexRecursive` is also supported by default. If this attribute is not set, an error is thrown when the same thread tries to acquire it the second time.
- `osMutexRobust` is not supported in Zephyr.

Return values not supported in the Zephyr implementation

- `osKernelUnlock`, `osKernelLock`, `osKernelRestoreLock`
  - `osError` (Unspecified error) is not supported.
- `osSemaphoreDelete`
  - `osErrorResource` (the semaphore specified by parameter `semaphore_id` is in an invalid semaphore state) is not supported.
- `osMutexDelete`
  - `osErrorResource` (mutex specified by parameter `mutex_id` is in an invalid mutex state) is not supported.
- `osTimerDelete`
  - `osErrorResource` (the timer specified by parameter `timer_id` is in an invalid timer state) is not supported.
- `osMessageQueueReset`
  - `osErrorResource` (the message queue specified by parameter `msgq_id` is in an invalid message queue state) is not supported.
- `osMessageQueueDelete`
  - `osErrorResource` (the message queue specified by parameter `msgq_id` is in an invalid message queue state) is not supported.
- `osMemoryPoolFree`
  - `osErrorResource` (the memory pool specified by parameter `mp_id` is in an invalid memory pool state) is not supported.
- `osMemoryPoolDelete`
  - `osErrorResource` (the memory pool specified by parameter `mp_id` is in an invalid memory pool state) is not supported.
- `osEventFlagsSet`, `osEventFlagsClear`
  - `osFlagsErrorUnknown` (Unspecified error) and `osFlagsErrorResource` (Event flags object specified by parameter `ef_id` is not ready to be used) are not supported.
- `osEventFlagsDelete`
  - `osErrorParameter` (the value of the parameter `ef_id` is incorrect) is not supported.
- `osThreadFlagsSet`
  - `osFlagsErrorUnknown` (Unspecified error) and `osFlagsErrorResource` (Thread specified by parameter `thread_id` is not active to receive flags) are not supported.
- `osThreadFlagsClear`
  - `osFlagsErrorResource` (Running thread is not active to receive flags) is not supported.
- `osDelayUntil`
  - `osParameter` (the time cannot be handled) is not supported.
4.21 Power off

*group sys_poweroff*

**Functions**

```c
FUNC_NORETURN void sys_poweroff(void)

Perform a system power off.
```

This function will perform an immediate power off of the system. It is the responsibility of the caller to ensure that the system is in a safe state to be powered off. Any required wake up sources must be enabled before calling this function.

**CONFIG_POWEROFF** needs to be enabled to use this API.

4.22 Shell

- **Overview**
  - Connecting to Segger RTT via TCP (on macOS, for example)
  - Telnet Backend
- **Commands**
  - Creating commands
  - Dictionary commands
  - Commands execution
  - Built-in commands
- **Tab Feature**
- **History Feature**
- **Wildcards Feature**
- **Meta Keys Feature**
- **Getopt Feature**
- **Obscured Input Feature**
- **Shell Logger Backend Feature**
- **RTT Backend Channel Selection**
- **Usage**
- **API Reference**

4.22.1 Overview

This module allows you to create and handle a shell with a user-defined command set. You can use it in examples where more than simple button or LED user interaction is required. This module is a Unix-like shell with these features:

- Support for multiple instances.
• Advanced cooperation with the *Logging*.
• Support for static and dynamic commands.
• Support for dictionary commands.
• Smart command completion with the Tab key.
• Built-in commands: `clear`, `shell`, `colors`, `echo`, `history` and `resize`.
• Viewing recently executed commands using keys: ↑ ↓ or meta keys.
• Text edition using keys: ← →, Backspace, Delete, End, Home, Insert.
• Support for ANSI escape codes: `VT100` and `ESC[n~` for cursor control and color printing.
• Support for editing multiline commands.
• Built-in handler to display help for the commands.
• Support for wildcards: * and ?.
• Support for meta keys.
• Support for getopt and getopt_long.
• Kconfig configuration to optimize memory usage.

**Note:** Some of these features have a significant impact on RAM and flash usage, but many can be disabled when not needed. To default to options which favor reduced RAM and flash requirements instead of features, you should enable `CONFIG_SHELL_MINIMAL` and selectively enable just the features you want.

The module can be connected to any transport for command input and output. At this point, the following transport layers are implemented:

• MQTT
• Segger RTT
• SMP
• Telnet
• UART
• USB
• DUMMY - not a physical transport layer.

**Connecting to Segger RTT via TCP (on macOS, for example)**

On macOS JLinkRTTClient won’t let you enter input. Instead, please use following procedure:

• Open a first Terminal window and enter:

```
JLinkRTTLogger -Device NRF52840_XXAA -RTTChannel 1 -if SWD -Speed 4000 ~/rtt.log
```

(change device if required)

• Open a second Terminal window and enter:

```
nc localhost 19021
```

• Now you should have a network connection to RTT that will let you enter input to the shell.
Telnet Backend

Enabling CONFIG_SHELL_BACKEND_TELNET will allow users to use telnet as a shell backend. Connecting to it can be done using PuTTY or any telnet client. For example:

telnet <ip address> <port>

By default the telnet client won’t handle telnet commands and configuration. Although command support can be enabled with CONFIG_SHELL_TELNET_SUPPORT_COMMAND. This will give the telnet client access to a very limited set of supported commands but still can be turned on if needed. One of the command options it supports is the ECHO option. This will allow the client to be in character mode (character at a time), similar to a UART backend in that regard. This will make the client send a character as soon as it is typed having the effect of increasing the network traffic considerably. For that cost, it will enable the line editing, tab completion, and history features of the shell.

4.22.2 Commands

Shell commands are organized in a tree structure and grouped into the following types:

- Root command (level 0): Gathered and alphabetically sorted in a dedicated memory section.
- Static subcommand (level > 0): Number and syntax must be known during compile time. Created in the software module.
- Dynamic subcommand (level > 0): Number and syntax does not need to be known during compile time. Created in the software module.

Creating commands

Use the following macros for adding shell commands:

- SHELL_CMD_REGISTER - Create root command. All root commands must have different name.
- SHELL_COND_CMD_REGISTER - Conditionally (if compile time flag is set) create root command. All root commands must have different name.
- SHELL_CMD_ARG_REGISTER - Create root command with arguments. All root commands must have different name.
- SHELL_COND_CMD_ARG_REGISTER - Conditionally (if compile time flag is set) create root command with arguments. All root commands must have different name.
- SHELL_CMD - Initialize a command.
- SHELL_COND_CMD - Initialize a command if compile time flag is set.
- SHELL_EXPR_CMD - Initialize a command if compile time expression is non-zero.
- SHELL_CMD_ARG - Initialize a command with arguments.
- SHELL_COND_CMD_ARG - Initialize a command with arguments if compile time flag is set.
- SHELL_EXPR_CMD_ARG - Initialize a command with arguments if compile time expression is non-zero.
- SHELL_STATIC_SUBCMD_SET_CREATE - Create a static subcommands array.
- SHELL_SUBCMD_DICT_SET_CREATE - Create a dictionary subcommands array.
- SHELL_DYNAMIC_CMD_CREATE - Create a dynamic subcommands array.

Commands can be created in any file in the system that includes include/zephyr/shell/shell.h. All created commands are available for all shell instances.
**Static commands**  Example code demonstrating how to create a root command with static subcommands.

```c
/* Creating subcommands (level 1 command) array for command "demo". */
SHELL_STATIC_SUBCMD_SET_CREATE(sub_demo,
    SHELL_CMD(params, NULL, "Print params command.", cmd_demo_params),
    SHELL_CMD(ping, NULL, "Ping command.", cmd_demo_ping),
    SHELL_SUBCMD_SET_END
);
/* Creating root (level 0) command "demo" */
SHELL_CMD_REGISTER(demo, &sub_demo, "Demo commands", NULL);

Example implementation can be found under following location: samples/subsys/shell/shell_module/src/main.c.
```

**Dictionary commands**

This is a special kind of static commands. Dictionary commands can be used every time you want to use a pair: (string <-> corresponding data) in a command handler. The string is usually a verbal description of a given data. The idea is to use the string as a command syntax that can be prompted by the shell and corresponding data can be used to process the command.

Let's use an example. Suppose you created a command to set an ADC gain. It is a perfect place where a dictionary can be used. The dictionary would be a set of pairs: (string: gain_value, int: value) where int value could be used with the ADC driver API.

Abstract code for this task would look like this:

```c
static int gain_cmd_handler(const struct shell *sh,
    size_t argc, char **argv, void *data)
{
    int gain;

    /* data is a value corresponding to called command syntax */
    gain = (int)data;
    adc_set_gain(gain);

    shell_print(sh, "ADC gain set to: \%s\n"
        "Value send to ADC driver: \%d",
        argv[0],
        gain);

    return 0;
}

SHELL_SUBCMD_DICT_SET_CREATE(sub_gain, gain_cmd_handler,
    (gain_1, 1, "gain 1"), (gain_2, 2, "gain 2"),
```

(continues on next page)
This is how it would look like in the shell:

```
uart:~$ gain ga
  gain_1  gain_2  gain_1_2  gain_1_4
uart:~$ gain gain_1
ADC gain set to: gain_1
Value send to ADC driver: 1
uart:~$ gain gain_2
ADC gain set to: gain_2
Value send to ADC driver: 2
uart:~$ gain gain_1_2
ADC gain set to: gain_1_2
Value send to ADC driver: 3
uart:~$ gain gain_1_4
ADC gain set to: gain_1_4
Value send to ADC driver: 4
uart:~$
```

**Dynamic commands**  Example code demonstrating how to create a root command with static and dynamic subcommands. At the beginning dynamic command list is empty. New commands can be added by typing:

```
dynamic add <new_dynamic_command>
```

Newly added commands can be prompted or autocompleted with the Tab key.

```
/* Buffer for 10 dynamic commands */
static char dynamic_cmd_buffer[10][50];
```
/* commands counter */
static uint8_t dynamic_cmd_cnt;
/* Function returning command dynamically created *
* in dynamic_cmd_buffer. */
static void dynamic_cmd_get(size_t idx, 
    struct shell_static_entry *entry)
{
    if (idx < dynamic_cmd_cnt) {
        entry->syntax = dynamic_cmd_buffer[idx];
        entry->handler = NULL;
        entry->subcmd = NULL;
        entry->help = "Show dynamic command name."
    } else {
        /* if there are no more dynamic commands available
         * syntax must be set to NULL. */
        entry->syntax = NULL;
    }
}

SHELL_DYNAMIC_CMD_CREATE(m_sub_dynamic_set, dynamic_cmd_get);
SHELL_STATIC_SUBCMD_SET_CREATE(m_sub_dynamic,
    SHELL_CMD(add, NULL,"Add new command to dynamic_cmd_buffer and"
        "sort them alphabetically.",
        cmd_dynamic_add),
    SHELL_CMD(execute, &m_sub_dynamic_set,
        "Execute a command.", cmd_dynamic_execute),
    SHELL_CMD(remove, &m_sub_dynamic_set,
        "Remove a command from dynamic_cmd_buffer.",
        cmd_dynamic_remove),
    SHELL_CMD(show, NULL,
        "Show all commands in dynamic_cmd_buffer.",
        cmd_dynamic_show),
    SHELL_SUBCMD_SET_END
);
SHELL_CMD_REGISTER(dynamic, &m_sub_dynamic,
    "Demonstrate dynamic command usage.", cmd_dynamic);

Example implementation can be found under following location: samples/subsys/shell/shell_module/src/dynamic_cmd.c.

**Commands execution**

Each command or subcommand may have a handler. The shell executes the handler that is found deepest in the command tree and further subcommands (without a handler) are passed as arguments. Characters within parentheses are treated as one argument. If shell won’t find a handler it will display an error message.

Commands can be also executed from a user application using any active backend and a function `shell_execute_cmd()`, as shown in this example:

```c
int main(void)
{
    /* Below code will execute "clear" command on a DUMMY backend */
    shell_execute_cmd(NULL, "clear");

    /* Below code will execute "shell colors off" command on
```
Enable the DUMMY backend by setting the Kconfig `CONFIG_SHELL_BACKEND_DUMMY` option.

**Commands execution example**  Let's assume a command structure as in the following figure, where:

- `root_cmd` - root command without a handler
- `cmd_xxx_h` - command has a handler
- `cmd_xxx` - command does not have a handler

- **Example 1**  Sequence: `root_cmd cmd_1_h cmd_12_h cmd_121_h parameter` will execute command `cmd_121_h` and `parameter` will be passed as an argument.

- **Example 2**  Sequence: `root_cmd cmd_2 cmd_22_h parameter1 parameter2` will execute command `cmd_22_h` and `parameter1 parameter2` will be passed as arguments.

- **Example 3**  Sequence: `root_cmd cmd_1_h parameter1 cmd_121_h parameter2` will execute command `cmd_1_h` and `parameter1 cmd_121_h` and `parameter2` will be passed as arguments.

- **Example 4**  Sequence: `root_cmd parameter cmd_121_h parameter2` will not execute any command.
Command handler  Simple command handler implementation:

```c
static int cmd_handler(const struct shell *sh, size_t argc, char **argv)
{
    ARG_UNUSED(argc);
    ARG_UNUSED(argv);

    shell_fprintf(shell, SHELL_INFO, "Print info message\n");
    shell_print(sh, "Print simple text.");
    shell_warn(sh, "Print warning text.");
    shell_error(sh, "Print error text.");
    return 0;
}
```

Function `shell_fprintf()` or the shell print macros: `shell_print`, `shell_info`, `shell_warn` and `shell_error` can be used from the command handler or from threads, but not from an interrupt context. Instead, interrupt handlers should use `Logging` for printing.

**Command help**  Every user-defined command or subcommand can have its own help description. The help for commands and subcommands can be created with respective macros: `SHELL_CMD_REGISTER`, `SHELL_CMD_ARG_REGISTER`, `SHELL_CMD`, and `SHELL_CMD_ARG`.

Shell prints this help message when you call a command or subcommand with `-h` or `--help` parameter.

**Parent commands**  In the subcommand handler, you can access both the parameters passed to commands or the parent commands, depending on how you index `argv`.

- When indexing `argv` with positive numbers, you can access the parameters.
- When indexing `argv` with negative numbers, you can access the parent commands.
- The subcommand to which the handler belongs has the `argv` index of 0.

```c
static int cmd_handler(const struct shell *sh, size_t argc, char **argv)
{
    ARG_UNUSED(argc);

    /* If it is a subcommand handler parent command syntax
    * can be found using argv[-1].
    */
    shell_print(sh, "This command has a parent command: %s", argv[-1]);

    /* Print this command syntax */
    shell_print(sh, "This command syntax is: %s", argv[0]);

    /* Print first argument */
    shell_print(sh, "%s", argv[1]);

    return 0;
}
```
**Built-in commands**

These commands are activated by `CONFIG_SHELL_CMDS` set to **y**.

- **clear** - Clears the screen.
- **history** - Shows the recently entered commands.
- **resize** - Must be executed when terminal width is different than 80 characters or after each change of terminal width. It ensures proper multiline text display and →, ←, End, Home keys handling. Currently this command works only with UART flow control switched on. It can be also called with a subcommand:
  - **default** - Shell will send terminal width = 80 to the terminal and assume successful delivery.

These command needs extra activation: `CONFIG_SHELL_CMDS_RESIZE` set to **y**.

- **select** - It can be used to set new root command. Exit to main command tree is with alt+r. This command needs extra activation: `CONFIG_SHELL_CMDS_SELECT` set to **y**.
- **shell** - Root command with useful shell-related subcommands like:
  - **echo** - Toggles shell echo.
  - **colors** - Toggles colored syntax. This might be helpful in case of Bluetooth shell to limit the amount of transferred bytes.
  - **stats** - Shows shell statistics.

### 4.22.3 Tab Feature

The Tab button can be used to suggest commands or subcommands. This feature is enabled by `CONFIG_SHELL_TAB` set to **y**. It can also be used for partial or complete auto-completion of commands. This feature is activated by `CONFIG_SHELL_TAB_AUTOCOMPLETION` set to **y**. When user starts writing a command and presses the Tab button then the shell will do one of 3 possible things:

- Autocomplete the command.
- Prompts available commands and if possible partly completes the command.
- Will not do anything if there are no available or matching commands.

```plaintext
uart:~$ log
    backend disable enable go halt
list_backends status
uart:~$ log enable
dbg err inf none wrn
uart:~$ log enable err
    app app_test log os
    shell.shell_uart shell_uart
uart:~$ log enable err shell
    shell.shell_uart shell_uart
uart:~$ log enable err shell
```

### 4.22.4 History Feature

This feature enables commands history in the shell. It is activated by: `CONFIG_SHELL_HISTORY` set to **y**. History can be accessed using keys: ↑ ↓ or Ctrl+n and Ctrl+p if meta keys are active. Number of commands that can be stored depends on size of `CONFIG_SHELL_HISTORY_BUFFER` parameter.
4.22.5 Wildcards Feature

The shell module can handle wildcards. Wildcards are interpreted correctly when expanded command and its subcommands do not have a handler. For example, if you want to set logging level to `err` for the `app` and `app_test` modules you can execute the following command:

```
log enable err a*
```

This feature is activated by `CONFIG_SHELL_WILDCARD` set to `y`.

4.22.6 Meta Keys Feature

The shell module supports the following meta keys:

<table>
<thead>
<tr>
<th>Meta keys</th>
<th>Action</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ctrl+a</td>
<td>Moves the cursor to the beginning of the line.</td>
</tr>
<tr>
<td>Ctrl+b</td>
<td>Moves the cursor backward one character.</td>
</tr>
<tr>
<td>Ctrl+c</td>
<td>Preserves the last command on the screen and starts a new command in a new line.</td>
</tr>
<tr>
<td>Ctrl+d</td>
<td>Deletes the character under the cursor.</td>
</tr>
<tr>
<td>Ctrl+e</td>
<td>Moves the cursor to the end of the line.</td>
</tr>
<tr>
<td>Ctrl+f</td>
<td>Moves the cursor forward one character.</td>
</tr>
<tr>
<td>Ctrl+k</td>
<td>Deletes from the cursor to the end of the line.</td>
</tr>
<tr>
<td>Ctrl+l</td>
<td>Clears the screen and leaves the currently typed command at the top of the screen.</td>
</tr>
<tr>
<td>Ctrl+n</td>
<td>Moves in history to next entry.</td>
</tr>
<tr>
<td>Ctrl+p</td>
<td>Moves in history to previous entry.</td>
</tr>
<tr>
<td>Ctrl+u</td>
<td>Clears the currently typed command.</td>
</tr>
<tr>
<td>Ctrl+w</td>
<td>Removes the word or part of the word to the left of the cursor. Words separated by period instead of space are treated as one word.</td>
</tr>
<tr>
<td>Alt+b</td>
<td>Moves the cursor backward one word.</td>
</tr>
<tr>
<td>Alt+f</td>
<td>Moves the cursor forward one word.</td>
</tr>
</tbody>
</table>

This feature is activated by `CONFIG_SHELL_METAKEYS` set to `y`. 
4.22.7 Getopt Feature

Some shell users apart from subcommands might need to use options as well. The arguments string, looking for supported options. Typically, this task is accomplished by the getopt family functions.

For this purpose shell supports the getopt and getopt_long libraries available in the FreeBSD project. This feature is activated by: CONFIG_GETOPT set to y and CONFIG_GETOPT_LONG set to y.

This feature can be used in thread safe as well as non thread safe manner. The former is full compatible with regular getopt usage while the latter a bit differs.

An example non-thread safe usage:

```c
char *cvalue = NULL;
while ((char c = getopt(argc, argv, "abhc:")) != -1) {
    switch (c) {
        case 'c':
            cvalue = optarg;
            break;
        default:
            break;
    }
}
```

An example thread safe usage:

```c
char *cvalue = NULL;
struct getopt_state *state;
while ((char c = getopt(argc, argv, "abhc:")) != -1) {
    state = getopt_state_get();
    switch (c) {
        case 'c':
            cvalue = state->optarg;
            break;
        default:
            break;
    }
}
```

Thread safe getopt functionality is activated by CONFIG_SHELL_GETOPT set to y.

4.22.8 Obscured Input Feature

With the obscured input feature, the shell can be used for implementing a login prompt or other user interaction whereby the characters the user types should not be revealed on screen, such as when entering a password.

Once the obscured input has been accepted, it is normally desired to return the shell to normal operation. Such runtime control is possible with the shell_obscure_set function.

An example of login and logout commands using this feature is located in samples/subsys/shell/shell_module/src/main.c and the config file samples/subsys/shell/shell_module/prj_login.conf.

This feature is activated upon startup by CONFIG_SHELL_START_OBSCURED set to y. With this set either way, the option can still be controlled later at runtime. CONFIG_SHELL_CMDS_SELECT is useful to prevent entry of any other command besides a login command, by means of the shell_set_root_cmd function. Likewise, CONFIG_SHELL_PROMPT_UART allows you to set the prompt upon startup, but it can be changed later with the shell_prompt_change function.
4.22.9  Shell Logger Backend Feature

Shell instance can act as the Logging backend. Shell ensures that log messages are correctly multiplexed with shell output. Log messages from logger thread are enqueued and processed in the shell thread. Logger thread will block for configurable amount of time if queue is full, blocking logger thread context for that time. Oldest log message is removed from the queue after timeout and new message is enqueued. Use the shell stats show command to retrieve number of log messages dropped by the shell instance. Log queue size and timeout are \texttt{SHELL\_DEFINE} arguments.

This feature is activated by: \texttt{CONFIG\_SHELL\_LOG\_BACKEND} set to \texttt{y}.

\textbf{Warning:} Enqueuing timeout must be set carefully when multiple backends are used in the system. The shell instance could have a slow transport or could block, for example, by a UART with hardware flow control. If timeout is set too high, the logger thread could be blocked and impact other logger backends.

\textbf{Warning:} As the shell is a complex logger backend, it can not output logs if the application crashes before the shell thread is running. In this situation, you can enable one of the simple logging backends instead, such as UART (\texttt{CONFIG\_LOG\_BACKEND\_UART}) or RTT (\texttt{CONFIG\_LOG\_BACKEND\_RTT}), which are available earlier during system initialization.

4.22.10  RTT Backend Channel Selection

Instead of using the shell as a logger backend, RTT shell backend and RTT log backend can also be used simultaneously, but over different channels. By separating them, the log can be captured or monitored without shell output or the shell may be scripted without log interference. Enabling both the Shell RTT backend and the Log RTT backend does not work by default, because both default to channel 0. There are two options:

1. The Shell buffer can use an alternate channel, for example using \texttt{CONFIG\_SHELL\_BACKEND\_RTT\_BUFFER} set to 1. This allows monitoring the log using JLinkRTTViewer while a script interfaces over channel 1.

2. The Log buffer can use an alternate channel, for example using \texttt{CONFIG\_LOG\_BACKEND\_RTT\_BUFFER} set to 1. This allows interactive use of the shell through JLinkRTTViewer, while the log is written to file.

\textbf{Warning:} Regardless of the channel selection, the RTT log backend must be explicitly enabled using \texttt{CONFIG\_LOG\_BACKEND\_RTT} set to \texttt{y}, because it defaults to \texttt{n} when the Shell RTT backend is also enabled using \texttt{CONFIG\_SHELL\_BACKEND\_RTT} being set to \texttt{y}.

4.22.11  Usage

To create a new shell instance user needs to activate requested backend using menuconfig.

The following code shows a simple use case of this library:

\begin{verbatim}
int main(void)
{
}
\end{verbatim}

(continues on next page)
static int cmd_demo_ping(const struct shell *sh, size_t argc, char **argv)
{
    ARG_UNUSED(argc);
    ARG_UNUSED(argv);
    shell_print(sh, "pong");
    return 0;
}

static int cmd_demo_params(const struct shell *sh, size_t argc, char **argv)
{
    int cnt;

    shell_print(sh, "argc = \%d", argc);
    for (cnt = 0; cnt < argc; cnt++) {
        shell_print(sh, " argv[%d] = %s", cnt, argv[cnt]);
    }
    return 0;
}

/* Creating subcommands (level 1 command) array for command "demo". */
SHELL_STATIC_SUBCMD_SET_CREATE(sub_demo,
    SHELL_CMD(params, NULL, "Print params command.",
        cmd_demo_params),
    SHELL_CMD(ping, NULL, "Ping command.", cmd_demo_ping),
    SHELL_SUBCMD_SET_END)
); /* Creating root (level 0) command "demo" without a handler */
SHELL_CMD_REGISTER(demo, &sub_demo, "Demo commands", NULL);

/* Creating root (level 0) command "version" */
SHELL_CMD_REGISTER(version, NULL, "Show kernel version", cmd_version);

Users may use the Tab key to complete a command/subcommand or to see the available subcommands for the currently entered command level. For example, when the cursor is positioned at the beginning of the command line and the Tab key is pressed, the user will see all root (level 0) commands:

clear  demo  shell  history  log  resize  version

**Note:** To view the subcommands that are available for a specific command, you must first type a space after this command and then hit Tab.

These commands are registered by various modules, for example:

- **clear, shell, history, and resize** are built-in commands which have been registered by subsys/shell/shell.c
- **demo and version** have been registered in example code above by main.c
- **log** has been registered by subsys/logging/log_cmds.c

Then, if a user types a `demo` command and presses the Tab key, the shell will only print the subcommands registered for this command:

params  ping
4.22.12 API Reference

Related code samples

Telnet console
Access Zephyr shell over telnet.

\texttt{group shell_api}
Shell API.

\textbf{Defines}

\texttt{SHELL_CMD_ARG_REGISTER(\texttt{syntax}, \texttt{subcmd}, \texttt{help}, \texttt{handler}, \texttt{mandatory}, \texttt{optional})}
Macro for defining and adding a root command (level 0) with required number of arguments.

\textbf{Note:} Each root command shall have unique syntax. If a command will be called with wrong number of arguments shell will print an error message and command handler will not be called.

\textbf{Parameters}

- \texttt{syntax} – [\texttt{in}] Command syntax (for example: history).
- \texttt{subcmd} – [\texttt{in}] Pointer to a subcommands array.
- \texttt{help} – [\texttt{in}] Pointer to a command help string.
- \texttt{handler} – [\texttt{in}] Pointer to a function handler.
- \texttt{mandatory} – [\texttt{in}] Number of mandatory arguments including command name.
- \texttt{optional} – [\texttt{in}] Number of optional arguments.

\texttt{SHELL_COND_CMD_ARG_REGISTER(\texttt{flag}, \texttt{syntax}, \texttt{subcmd}, \texttt{help}, \texttt{handler}, \texttt{mandatory}, \texttt{optional})}
Macro for defining and adding a conditional root command (level 0) with required number of arguments.

Macro can be used to create a command which can be conditionally present. It is an alternative to \texttt{#ifdef}s around command registration and command handler. If command is disabled handler and subcommands are removed from the application.

\textbf{See also:}
\texttt{SHELL_CMD_ARG_REGISTER} for details.

\textbf{Parameters}

- \texttt{flag} – [\texttt{in}] Compile time flag. Command is present only if flag exists and equals 1.
- \texttt{syntax} – [\texttt{in}] Command syntax (for example: history).
- \texttt{subcmd} – [\texttt{in}] Pointer to a subcommands array.
- \texttt{help} – [\texttt{in}] Pointer to a command help string.
• **handler** – **[in]** Pointer to a function handler.
• **mandatory** – **[in]** Number of mandatory arguments including command name.
• **optional** – **[in]** Number of optional arguments.

**SHELL_CMD_REGISTER**(syntax, subcmd, help, handler)
Macro for defining and adding a root command (level 0) with arguments.

**Note:** All root commands must have different name.

**Parameters**
- **syntax** – **[in]** Command syntax (for example: history).
- **subcmd** – **[in]** Pointer to a subcommands array.
- **help** – **[in]** Pointer to a command help string.
- **handler** – **[in]** Pointer to a function handler.

**SHELL_COND_CMD_REGISTER**(flag, syntax, subcmd, help, handler)
Macro for defining and adding a conditional root command (level 0) with arguments.

**See also:**
**SHELL_COND_CMD_ARG_REGISTER**.

**Parameters**
- **flag** – **[in]** Compile time flag. Command is present only if flag exists and equals 1.
- **syntax** – **[in]** Command syntax (for example: history).
- **subcmd** – **[in]** Pointer to a subcommands array.
- **help** – **[in]** Pointer to a command help string.
- **handler** – **[in]** Pointer to a function handler.

**SHELL_STATIC_SUBCMD_SET_CREATE**(name, ...)
Macro for creating a subcommand set.
It must be used outside of any function body.

**Example usage:**

```c
SHELL_STATIC_SUBCMD_SET_CREATE(
    foo,
    SHELL_CMD(abc, ...),
    SHELL_CMD(def, ...),
    SHELL_SUBCMD_SET_END
)
```

**Parameters**
- **name** – **[in]** Name of the subcommand set.
- **...** – **[in]** List of commands created with **SHELL_CMD_ARG** or or **SHELL_CMD**
SHELL_SUBCMD_SET_CREATE(_name, _parent)
Create set of subcommands.
Commands to this set are added using SHELL_SUBCMD_ADD and SHELL_SUBCMD_COND_ADD. Commands can be added from multiple files.

Parameters

- _name – [in] Name of the set. _name is used to refer the set in the parent command.
- _parent – [in] Set of comma separated parent commands in parenthesis, e.g. (foo_cmd) if subcommands are for the root command “foo_cmd”.

SHELL_SUBCMD_COND_ADD(_flag, _parent, _syntax, _subcmd, _help, _handler, _mand, _opt)
Conditionally add command to the set of subcommands.
Add command to the set created with SHELL_SUBCMD_SET_CREATE.

Note: The name of the section is formed as concatenation of number of parent commands, names of all parent commands and own syntax. Number of parent commands is added to ensure that section prefix is unique. Without it subcommands of (foo) and (foo, cmd1) would mix.

Parameters

- _flag – [in] Compile time flag. Command is present only if flag exists and equals 1.
- _handler – [in] Pointer to a function handler.
- _mand – [in] Number of mandatory arguments including command name.

SHELL_SUBCMD_ADD(_parent, _syntax, _subcmd, _help, _handler, _mand, _opt)
Add command to the set of subcommands.
Add command to the set created with SHELL_SUBCMD_SET_CREATE.

Parameters

- _handler – [in] Pointer to a function handler.
- _mand – [in] Number of mandatory arguments including command name.
Define ending subcommands set.

Macro for creating a dynamic entry.

**Parameters**

- **name** – [in] Name of the dynamic entry.
- **get** – [in] Pointer to the function returning dynamic commands array

Initializes a shell command with arguments.

**Parameters**

- **syntax** – [in] Command syntax (for example: history).
- **subcmd** – [in] Pointer to a subcommands array.
- **help** – [in] Pointer to a command help string.
- **handler** – [in] Pointer to a function handler.
- **mand** – [in] Number of mandatory arguments including command name.
- **opt** – [in] Number of optional arguments.

See also:

**SHELL_COND_CMD_ARG.** Based on the flag, creates a valid entry or an empty command which is ignored by the `shell`. It is an alternative to #ifdefs around command registration and command handler. However, empty structure is present in the flash even if command is disabled (subcommands and handler are removed). Macro internally handles case if flag is not defined so flag must be provided without any wrapper, e.g.: `SHELL_COND_CMD_ARG(CONFIG_FOO, ...)`

**Parameters**

- **flag** – [in] Compile time flag. Command is present only if flag exists and equals 1.
- **syntax** – [in] Command syntax (for example: history).
- **subcmd** – [in] Pointer to a subcommands array.
- **help** – [in] Pointer to a command help string.
- **handler** – [in] Pointer to a function handler.
- **mand** – [in] Number of mandatory arguments including command name.
- **opt** – [in] Number of optional arguments.

Note: If a command will be called with wrong number of arguments shell will print an error message and command handler will not be called.
SHELL_EXPR_CMD_ARG( _expr, _syntax, _subcmd, _help, _handler, _mand, _opt)
Initializes a conditional shell command with arguments if expression gives non-zero result at compile time.

See also:
SHELL_CMD_ARG. Based on the expression, creates a valid entry or an empty command which is ignored by the shell. It should be used instead of SHELL_COND_CMD_ARG if condition is not a single configuration flag, e.g.: SHELL_EXPR_CMD_ARG(IS_ENABLED(CONFIG_FOO) && IS_ENABLED(CONFIG_FOO_SETTING_1), ...)

Parameters
• _syntax – [in] Command syntax (for example: history).
• _subcmd – [in] Pointer to a subcommands array.
• _help – [in] Pointer to a command help string.
• _handler – [in] Pointer to a function handler.
• _mand – [in] Number of mandatory arguments including command name.
• _opt – [in] Number of optional arguments.

SHELL_CMD( _syntax, _subcmd, _help, _handler)
Initializes a shell command.

Parameters
• _syntax – [in] Command syntax (for example: history).
• _subcmd – [in] Pointer to a subcommands array.
• _help – [in] Pointer to a command help string.
• _handler – [in] Pointer to a function handler.

SHELL_COND_CMD( _flag, _syntax, _subcmd, _help, _handler)
Initializes a conditional shell command.

See also:
SHELL_COND_CMD_ARG.

Parameters
• _flag – [in] Compile time flag. Command is present only if flag exists and equals 1.
• _syntax – [in] Command syntax (for example: history).
• _subcmd – [in] Pointer to a subcommands array.
• _help – [in] Pointer to a command help string.
• _handler – [in] Pointer to a function handler.
SHELL_EXPR_CMD(_expr, _syntax, _subcmd, _help, _handler)
Initializes shell command if expression gives non-zero result at compile time.

See also:
SHELL_EXPR_CMD_ARG.

Parameters
- _expr – [in] Compile time expression. Command is present only if expression is non-zero.
- _handler – [in] Pointer to a function handler.

SHELL_CMD_DICT_CREATE(_data, _handler)
SHELL_SUBCMD_DICT_SET_CREATE(_name, _handler, ...)
Initializes shell dictionary commands.
This is a special kind of static commands. Dictionary commands can be used every time you want to use a pair: (string <-> corresponding data) in a command handler. The string is usually a verbal description of a given data. The idea is to use the string as a command syntax that can be prompted by the shell and corresponding data can be used to process the command.

Example usage:
```c
static int my_handler(const struct shell *sh,
        size_t argc, char **argv, void *data)
{
    int val = (int)data;
    shell_print(sh, "(syntax, value) : (%s, %d)", argv[0], val);
    return 0;
}

SHELL_SUBCMD_DICT_SET_CREATE(sub_dict_cmds, my_handler,
    (value_0, 0, "value 0"), (value_1, 1, "value 1"),
    (value_2, 2, "value 2"), (value_3, 3, "value 3")
);
SHELL_CMD_REGISTER(dictionary, &sub_dict_cmds, NULL, NULL);
```

See also:
shell_dict_cmd_handler

Parameters
- _name – [in] Name of the dictionary subcommand set
- ... – [in] Dictionary triplets: (command_syntax, value, helper). Value will be passed to the _handler as user data.
SHELL_DEFAULT_BACKEND_CONFIG_FLAGS

SHELL_DEFINE(_name, _prompt, _transport_iface, _log_queue_size, _log_timeout, _shell_flag)

Macro for defining a shell instance.

Parameters

- _name – [in] Instance name.
- _log_timeout – [in] Logger thread timeout in milliseconds on full log queue. If queue is full logger thread is blocked for given amount of time before log message is dropped.

SHELL_NORMAL

Terminal default text color for shell_fprintf function.

SHELL_INFO

Green text color for shell_fprintf function.

SHELL_OPTION

Cyan text color for shell_fprintf function.

SHELL_WARNING

Yellow text color for shell_fprintf function.

SHELL_ERROR

Red text color for shell_fprintf function.

shell_info(_sh, _ft, ...)

Print info message to the shell.

See shell_fprintf.

Parameters

- ... – [in] List of parameters to print.

shell_print(_sh, _ft, ...)

Print normal message to the shell.

See shell_fprintf.

Parameters

- ... – [in] List of parameters to print.
shell_warn(_sh, _ft, ...)  
Print warning message to the shell.  
See shell_fprintf.

Parameters  
• _sh – [in] Pointer to the shell instance.  
• ... – [in] List of parameters to print.

shell_error(_sh, _ft, ...)  
Print error message to the shell.  
See shell_fprintf.

Parameters  
• _sh – [in] Pointer to the shell instance.  
• ... – [in] List of parameters to print.

SHELL_CMD_HELP_PRINTED  
Command's help has been printed.

Typedefs

typedef void (*shell_dynamic_get)(size_t idx, struct shell_static_entry *entry)  
Shell dynamic command descriptor.

Function shall fill the received shell_static_entry structure with requested (idx) dynamic subcommand data. If there is more than one dynamic subcommand available, the function shall ensure that the returned commands: entry->syntax are sorted in alphabetical order. If idx exceeds the available dynamic subcommands, the function must write to entry->syntax NULL value. This will indicate to the shell module that there are no more dynamic commands to read.

typedef int (*shell_cmd_handler)(const struct shell *sh, size_t argc, char **argv)  
Shell command handler prototype.

Param sh  
Shell instance.

Param argc  
Arguments count.

Param argv  
Arguments.

Retval 0  
Successful command execution.

Retval 1  
Help printed and command not executed.

Retval -EINVAL  
Argument validation failed.

Retval -ENOEXEC  
Command not executed.
typedef int (*shell_dict_cmd_handler)(const struct shell *sh, size_t argc, char **argv, void *data)

Shell dictionary command handler prototype.

**Param sh**
Shell instance.

**Param argc**
Arguments count.

**Param argv**
Arguments.

**Param data**
Pointer to the user data.

**Retval 0**
Successful command execution.

**Retval 1**
Help printed and command not executed.

**Retval -EINVAL**
Argument validation failed.

**Retval -ENOEXEC**
Command not executed.

typedef void (*shell_transport_handler_t)(enum shell_transport_evt evt, void *context)

typedef void (*shell_uninit_cb_t)(const struct shell *sh, int res)

typedef void (*shell_bypass_cb_t)(const struct shell *sh, uint8_t *data, size_t len)

Bypass callback.

**Param sh**
Shell instance.

**Param data**
Raw data from transport.

**Param len**
Data length.

** Enums **

enum shell_receive_state

**Values:**

enumerator SHELL_RECEIVE_DEFAULT

enumerator SHELL_RECEIVE_ESC

enumerator SHELL_RECEIVE_ESC_SEQ

enumerator SHELL_RECEIVE_TILDE_EXP
enum shell_state

Values:

enumerator SHELL_STATE_UNINITIALIZED
enumerator SHELL_STATE_INITIALIZED
enumerator SHELL_STATE_ACTIVE
enumerator SHELL_STATE_PANIC_MODE_ACTIVE
   Panic activated.
enumerator SHELL_STATE_PANIC_MODE_INACTIVE
   Panic requested, not supported.

enum shell_transport_evt

Shell transport event.

Values:

enumerator SHELL_TRANSPORT_EVT_RX_RDY
enumerator SHELL_TRANSPORT_EVT_TX_RDY

enum shell_signal

Values:

enumerator SHELL_SIGNAL_RXRDY
enumerator SHELL_SIGNAL_LOG_MSG
enumerator SHELL_SIGNAL_KILL
enumerator SHELL_SIGNAL_TXDONE
enumerator SHELL_SIGNALS

enum shell_flag

Flags for setting shell output newline sequence.

Values:

enumerator SHELL_FLAG_CRLF_DEFAULT = (1 « 0)
   Do not map CR or LF.
enumerator SHELL_FLAG_OLF_CRLF = (1 « 1)
   Map LF to CRLF on output.
Functions

cnst struct device *shell_device_lookup(size_t idx, const char *prefix)

Get by index a device that matches.

This can be used, for example, to identify I2C_1 as the second I2C device.

Devices that failed to initialize or do not have a non-empty name are excluded from
the candidates for a match.

Parameters

• idx – the device number starting from zero.
• prefix – optional name prefix used to restrict candidate devices. Indexing is done relative to devices with names that start with this text. Pass null if no prefix match is required.

int shell_init(const struct shell *sh, const void *transport_config, struct
shell_backend_config_flags cfg_flags, bool log_backend, uint32_t
init_log_level)

Function for initializing a transport layer and internal shell state.

Parameters

• sh – [in] Pointer to shell instance.
• cfg_flags – [in] Initial backend configuration flags. Shell will copy this data.
• log_backend – If true, the console will be used as logger backend.
• init_log_level – [in] Default severity level for the logger.

Returns

Standard error code.

void shell_uninit(const struct shell *sh, shell_uninit_cb_t cb)

Uninitializes the transport layer and the internal shell state.

Parameters

• sh – Pointer to shell instance.
• cb – Callback called when uninitialization is completed.

int shell_start(const struct shell *sh)

Function for starting shell processing.

Parameters

• sh – Pointer to the shell instance.

Returns

Standard error code.

int shell_stop(const struct shell *sh)

Function for stopping shell processing.

Parameters

• sh – Pointer to shell instance.

Returns

Standard error code.
void shell_fprintf(const struct shell *sh, enum shell_vt100_color color, const char *fmt, ...)
printf-like function which sends formatted data stream to the shell.
This function can be used from the command handler or from threads, but not from an interrupt context.

**Parameters**
- **sh** – ![in] Pointer to the shell instance.
- **color** – ![in] Printed text color.
- **fmt** – ![in] Format string.
- **...** – ![in] List of parameters to print.

void shell_vfprintf(const struct shell *sh, enum shell_vt100_color color, const char *fmt, va_list args)
vprintf-like function which sends formatted data stream to the shell.
This function can be used from the command handler or from threads, but not from an interrupt context. It is similar to shell_fprintf() but takes a va_list instead of variable arguments.

**Parameters**
- **sh** – ![in] Pointer to the shell instance.
- **color** – ![in] Printed text color.
- **fmt** – ![in] Format string.
- **args** – ![in] List of parameters to print.

void shell_hexdump_line(const struct shell *sh, unsigned int offset, const uint8_t *data, size_t len)
Print a line of data in hexadecimal format.
Each line shows the offset, bytes and then ASCII representation.
For example:
00008010: 20 25 00 20 2f 48 00 08 80 05 00 20 46 00 | %. /H.. ..F |

**Parameters**
- **sh** – ![in] Pointer to the shell instance.
- **offset** – ![in] Offset to show for this line.
- **data** – ![in] Pointer to data.
- **len** – ![in] Length of data.

void shell_hexdump(const struct shell *sh, const uint8_t *data, size_t len)
Print data in hexadecimal format.

**Parameters**
- **sh** – ![in] Pointer to the shell instance.
- **data** – ![in] Pointer to data.
- **len** – ![in] Length of data.

void shell_process(const struct shell *sh)
Process function, which should be executed when data is ready in the transport interface.
To be used if shell thread is disabled.
Parameters


int shell_prompt_change(const struct shell *sh, const char *prompt)
Change displayed shell prompt.

Parameters


Returns

0 Success.

Returns

EINVAL Pointer to new prompt is not correct.

void shell_help(const struct shell *sh)
Prints the current command help.

Function will print a help string with: the currently entered command and subcommands (if they exist).

Parameters


int shell_execute_cmd(const struct shell *sh, const char *cmd)
Execute command.

Pass command line to shell to execute.

Note: This by no means makes any of the commands a stable interface, so this function should only be used for debugging/diagnostic.

This function must not be called from shell command context!

Parameters

- sh – [in] Pointer to the shell instance. It can be NULL when the CONFIG_SHELL_BACKEND_DUMMY option is enabled.
- cmd – [in] Command to be executed.

Returns

Result of the execution

int shell_set_root_cmd(const char *cmd)
Set root command for all shell instances.

It allows setting from the code the root command. It is an equivalent of calling select command with one of the root commands as the argument (e.g “select log”) except it sets command for all shell instances.

Parameters

- cmd – String with one of the root commands or null pointer to reset.

Return values

- 0 – if root command is set.
- EINVAL – if invalid root command is provided.

void shell_set_bypass(const struct shell *sh, shell_bypass_cb_t bypass)
Set bypass callback.

Bypass callback is called whenever data is received. Shell is bypassed and data is passed directly to the callback. Use null to disable bypass functionality.
Parameters

- bypass – [in] Bypass callback or null to disable.

bool shell_ready(const struct shell *sh)

Get shell readiness to execute commands.

Parameters


Return values

- true – Shell backend is ready to execute commands.
- false – Shell backend is not initialized or not started.

int shell_insert_mode_set(const struct shell *sh, bool val)

Allow application to control text insert mode.

Value is modified atomically and the previous value is returned.

Parameters


Return values

- 0 – or 1: previous value
- -EINVAL – if shell is NULL.

int shell_use_colors_set(const struct shell *sh, bool val)

Allow application to control whether terminal output uses colored syntax.

Value is modified atomically and the previous value is returned.

Parameters


Return values

- 0 – or 1: previous value
- -EINVAL – if shell is NULL.

int shell_use_vt100_set(const struct shell *sh, bool val)

Allow application to control whether terminal is using vt100 commands.

Value is modified atomically and the previous value is returned.

Parameters


Return values

- 0 – or 1: previous value
- -EINVAL – if shell is NULL.
int shell_echo_set(const struct shell *sh, bool val)
Allow application to control whether user input is echoed back.
Value is modified atomically and the previous value is returned.

Parameters
• sh – [in] Pointer to the shell instance.
• val – [in] Echo mode.

Return values
• 0 – or 1: previous value
• -EINVAL – if shell is NULL.

int shell_obscure_set(const struct shell *sh, bool obscure)
Allow application to control whether user input is obscured with asterisks.
useful for implementing passwords.
Value is modified atomically and the previous value is returned.

Parameters
• sh – [in] Pointer to the shell instance.
• obscure – [in] Obscure mode.

Return values
• 0 – or 1: previous value.
• -EINVAL – if shell is NULL.

int shell_mode_delete_set(const struct shell *sh, bool val)
Allow application to control whether the delete key backspaces or deletes.
Value is modified atomically and the previous value is returned.

Parameters
• sh – [in] Pointer to the shell instance.
• val – [in] Delete mode.

Return values
• 0 – or 1: previous value
• -EINVAL – if shell is NULL.

int shell_get_return_value(const struct shell *sh)
Retrieve return value of most recently executed shell command.

Parameters
• sh – [in] Pointer to the shell instance

Return values
return – value of previous command

Variables

const struct log_backend_api log_backend_shell_api

union shell_cmd_entry
# include <shell.h> Shell command descriptor.
Public Members

`shell_dynamic_get` \texttt{dynamic_get}

Pointed to function returning dynamic commands.

\begin{verbatim}
const struct shell_static_entry *entry
\end{verbatim}

Pointer to array of static commands.

\begin{verbatim}
struct shell_static_args
#include <shell.h>
\end{verbatim}

Public Members

\begin{verbatim}
uint8_t mandatory
\end{verbatim}

Number of mandatory arguments.

\begin{verbatim}
uint8_t optional
\end{verbatim}

Number of optional arguments.

\begin{verbatim}
struct shell_static_entry
#include <shell.h>
\end{verbatim}

Public Members

\begin{verbatim}
const char *syntax
\end{verbatim}

Command syntax strings.

\begin{verbatim}
const char *help
\end{verbatim}

Command help string.

\begin{verbatim}
const union shell_cmd_entry *subcmd
\end{verbatim}

Pointer to subcommand.

\begin{verbatim}
shell_cmd_handler handler
\end{verbatim}

Command handler.

\begin{verbatim}
struct shell_static_args args
\end{verbatim}

Command arguments.

\begin{verbatim}
struct shell_transport_api
#include <shell.h> Unified shell transport interface.
\end{verbatim}

Public Members
int (*init)(const struct shell_transport *transport, const void *config, shell_transport_handler_t evt_handler, void *context)
  Function for initializing the shell transport interface.
  Param transport
    [in] Pointer to the transfer instance.
  Param config
    [in] Pointer to instance configuration.
  Param evt_handler
  Param context
    [in] Pointer to the context passed to event handler.
  Return
    Standard error code.

int (*uninit)(const struct shell_transport *transport)
  Function for uninitializing the shell transport interface.
  Param transport
    [in] Pointer to the transfer instance.
  Return
    Standard error code.

int (*enable)(const struct shell_transport *transport, bool blocking_tx)
  Function for enabling transport in given TX mode.
  Function can be used to reconfigure TX to work in blocking mode.
  Param transport
    Pointer to the transfer instance.
  Param blocking_tx
    If true, the transport TX is enabled in blocking mode.
  Return
    NRF_SUCCESS on successful enabling, error otherwise (also if not supported).

int (*write)(const struct shell_transport *transport, const void *data, size_t length, size_t *cnt)
  Function for writing data to the transport interface.
  Param transport
    [in] Pointer to the transfer instance.
  Param data
    [in] Pointer to the source buffer.
  Param length
    [in] Source buffer length.
  Param cnt
    [out] Pointer to the sent bytes counter.
  Return
    Standard error code.

int (*read)(const struct shell_transport *transport, void *data, size_t length, size_t *cnt)
  Function for reading data from the transport interface.
  Param transport
    [in] Pointer to the transfer instance.
  Param data
    [in] Pointer to the destination buffer.
  Param length
    [in] Destination buffer length.
**Param cnt**

[out] Pointer to the received bytes counter.

**Return**

Standard error code.

```c
void (*update)(const struct shell_transport *transport)
```

Function called in shell thread loop.

Can be used for backend operations that require longer execution time

**Param transport**

[in] Pointer to the transfer instance.

```c
struct shell_transport
#include <shell.h>
```

```c
struct shell_stats
#include <shell.h> Shell statistics structure.
```

**Public Members**

```c
atomic_t log_lost_cnt
Lost log counter.
```

```c
struct shell_backend_config_flags
#include <shell.h>
```

**Public Members**

```c
uint32_t insert_mode
Controls insert mode for text introduction.
```

```c
uint32_t echo
Controls shell echo.
```

```c
uint32_t obscure
If echo on, print asterisk instead.
```

```c
uint32_t mode_delete
Operation mode of backspace key.
```

```c
uint32_t use_colors
Controls colored syntax.
```

```c
uint32_t use_vt100
Controls VT100 commands usage in shell.
```

```c
struct shell_backend_ctx_flags
#include <shell.h>
```

4.22. Shell
Public Members

uint32_t processing
    Shell is executing process function.

uint32_t history_exit
    Request to exit history mode.

uint32_t last_nl
    Last received new line character.

uint32_t cmd_ctx
    Shell is executing command.

uint32_t print_noinit
    Print request from not initialized shell.

uint32_t sync_mode
    Shell in synchronous mode.

uint32_t handle_log
    Shell is handling logger backend.

union shell_backend_cfg
    
    #include <shell.h>

Public Members

atomic_t value

struct shell_backend_config_flags flags

union shell_backend_ctx
    
    #include <shell.h>

Public Members

uint32_t value

struct shell_backend_ctx_flags flags

struct shell_ctx
    
    #include <shell.h> Shell instance context.
Public Members

const char *prompt
    shell current prompt.

enum shell_state state
    Internal module state.

enum shell_receive_state receive_state
    Escape sequence indicator.

struct shell_static_entry active_cmd
    Currently executed command.

const struct shell_static_entry *selected_cmd
    New root command.
    If NULL shell uses default root commands.

struct shell_vt100_ctx vt100_ctx
    VT100 color and cursor position, terminal width.

shell_uninit_cb_t uninit_cb
    Callback called from shell thread context when unitialization is completed just be-
    fore aborting shell thread.

shell_bypass_cb_t bypass
    When bypass is set, all incoming data is passed to the callback.
    Logging level for a backend.

uint16_t cmd_buff_len
    Command length.

uint16_t cmd_buff_pos
    Command buffer cursor position.

uint16_t cmd_tmp_buff_len
    Command length in tmp buffer.

char cmdBuff[0]
    Command input buffer.

char tempBuff[0]
    Command temporary buffer.

char printf_buff[0]
    Printf buffer size.
struct \textit{k_poll_event} \texttt{events[\textit{SHELL\_SIG\_NAL\_S\_IG\_N\_ALS}]}

Events that should be used only internally by shell thread.
Event for \textit{SHELL\_SIG\_NAL\_TX\_DONE} is initialized but unused.

struct \textit{shell}  
 \texttt{#include <shell.h>} Shell instance internals.

### Public Members

const char *\texttt{default\_prompt}

Shell default prompt.

const struct \texttt{shell\_transport} *\texttt{iface}

Transport interface.

struct \texttt{shell\_ctx} *\texttt{ctx}

Internal context.

## 4.23 Settings

The settings subsystem gives modules a way to store persistent per-device configuration and runtime state. A variety of storage implementations are provided behind a common API using FCB, NVS, or a file system. These different implementations give the application developer flexibility to select an appropriate storage medium, and even change it later as needs change. This subsystem is used by various Zephyr components and can be used simultaneously by user applications.

Settings items are stored as key-value pair strings. By convention, the keys can be organized by the package and subtree defining the key, for example the key \texttt{id/serial} would define the \texttt{serial} configuration element for the package \texttt{id}.

Convenience routines are provided for converting a key value to and from a string type.

For an example of the settings subsystem refer to settings sample.

\textbf{Note:} As of Zephyr release 2.1 the recommended backend for non-filesystem storage is \texttt{NVS}.

### 4.23.1 Handlers

Settings handlers for subtree implement a set of handler functions. These are registered using a call to \texttt{settings_register()}.

\textbf{h\_get}

This gets called when asking for a settings element value by its name using \texttt{settings\_runtime\_get()} from the runtime backend.

\textbf{h\_set}

This gets called when the value is loaded from persisted storage with \texttt{settings\_load()}, or when using \texttt{settings\_runtime\_set()} from the runtime backend.
**h_commit**  
This gets called after the settings have been loaded in full. Sometimes you don't want an individual setting value to take effect right away, for example if there are multiple settings which are interdependent.

**h_export**  
This gets called to write all current settings. This happens when settings_save() tries to save the settings or transfer to any user-implemented back-end.

### 4.23.2 Backends

Backends are meant to load and save data to/from setting handlers, and implement a set of handler functions. These are registered using a call to settings_src_register() for backends that can load data, and/or settings_dst_register() for backends that can save data. The current implementation allows for multiple source backends but only a single destination backend.

**csi_load**  
This gets called when loading values from persistent storage using settings_load().

**csi_save**  
This gets called when saving a single setting to persistent storage using settings_save_one().

**csi_save_start**  
This gets called when starting a save of all current settings using settings_save().

**csi_save_end**  
This gets called after having saved of all current settings using settings_save().

### 4.23.3 Zephyr Storage Backends

Zephyr has three storage backends: a Flash Circular Buffer (CONFIG_SETTINGS_FCB), a file in the filesystem (CONFIG_SETTINGS_FILE), or non-volatile storage (CONFIG_SETTINGS_NVS).

You can declare multiple sources for settings; settings from all of these are restored when settings_load() is called.

There can be only one target for writing settings; this is where data is stored when you call settings_save(), or settings_save_one().

FCB read target is registered using settings_fcb_src(), and write target using settings_fcb_dst(). As a side-effect, settings_fcb_src() initializes the FCB area, so it must be called before calling settings_fcb_dst(). File read target is registered using settings_file_src(), and write target by using settings_file_dst(). Non-volatile storage read target is registered using settings_nvs_src(), and write target by using settings_nvs_dst().

### 4.23.4 Storage Location

The FCB and non-volatile storage (NVS) backends both look for a fixed partition with label “storage” by default. A different partition can be selected by setting the zephyr,settings-partition property of the chosen node in the devicetree.

The file path used by the file backend to store settings is selected via the option CONFIG_SETTINGS_FILE_PATH.
4.23.5 Loading data from persisted storage

A call to `settings_load()` uses an `h_set` implementation to load settings data from storage to volatile memory. After all data is loaded, the `h_commit` handler is issued, signalling the application that the settings were successfully retrieved.

Technically FCB and file backends may store some history of the entities. This means that the newest data entity is stored after any older existing data entities. Starting with Zephyr 2.1, the back-end must filter out all old entities and call the callback with only the newest entity.

4.23.6 Storing data to persistent storage

A call to `settings_save_one()` uses a backend implementation to store settings data to the storage medium. A call to `settings_save()` uses an `h_export` implementation to store different data in one operation using `settings_save_one()`. A key need to be covered by a `h_export` only if it is supposed to be stored by `settings_save()` call.

For both FCB and file back-end only storage requests with data which changes most actual key's value are stored, therefore there is no need to check whether a value changed by the application. Such a storage mechanism implies that storage can contain multiple value assignments for a key, while only the last is the current value for the key.

Garbage collection

When storage becomes full (FCB) or consumes too much space (file), the backend removes non-recent key-value pairs records and unnecessary key-delete records.

4.23.7 Secure domain settings

Currently settings doesn't provide scheme of being secure, and non-secure configuration storage simultaneously for the same instance. It is recommended that secure domain uses its own settings instance and it might provide data for non-secure domain using dedicated interface if needed (case dependent).

4.23.8 Example: Device Configuration

This is a simple example, where the settings handler only implements `h_set` and `h_export`. `h_set` is called when the value is restored from storage (or when set initially), and `h_export` is used to write the value to storage thanks to `storage_func()`. The user can also implement some other export functionality, for example, writing to the shell console).

```c
#define DEFAULT_FOO_VAL_VALUE 1

static int8 foo_val = DEFAULT_FOO_VAL_VALUE;

static int foo_settings_set(const char *name, size_t len, settings_read_cb read_cb, void *cb_arg)
{
    const char *next;
    int rc;

    if (settings_name_steq(name, "bar", &next) && !next) {
        if (len != sizeof(foo_val)) {
            return -EINVAL;
        }
```
```c
static int foo_settings_set(const char *name, size_t len, settings_read_cb read_cb, void *cb_arg)
{
    const char *next;
    int rc;
    if (settings_name_steq(name, "bar", &next)
            && !next)
    {
        if (len != sizeof(foo_val)) {
            return -EINVAL;
        }
        rc = read_cb(cb_arg, &foo_val, sizeof(foo_val));
        if (rc >= 0) {
            /* key-value pair was properly read.
             * rc contains value length.
             */
            return 0;
        }
        /* read-out error */
        return rc;
    }
    return -ENOENT;
}
static int foo_settings_export(int (*storage_func)(const char *name, const void *value, size_t val_len))
{
    return storage_func("foo/bar", &foo_val, sizeof(foo_val));
}
struct settings_handler my_conf = {
    .name = "foo",
    .h_set = foo_settings_set,
    .h_export = foo_settings_export
};
```

4.23.9 Example: Persist Runtime State

This is a simple example showing how to persist runtime state. In this example, only \texttt{h\_set} is defined, which is used when restoring value from persisted storage.

In this example, the main function increments \texttt{foo\_val}, and then persists the latest number. When the system restarts, the application calls \texttt{settings\_load()} while initializing, and \texttt{foo\_val} will continue counting up from where it was before restart.

```c
#include <zephyr/kernel.h>
#include <zephyr/sys/reboot.h>
#include <zephyr/settings/settings.h>
#include <zephyr/sys/printk.h>
#include <inttypes.h>
#define DEFAULT_FOO_VAL_VALUE 0
static uint8_t foo_val = DEFAULT_FOO_VAL_VALUE;
static int foo_settings_set(const char *name, size_t len, settings_read_cb read_cb, void *cb_arg)
{
    const char *next;
    int rc;
    if (settings_name_steq(name, "bar", &next) && !next) {
        if (len != sizeof(foo_val)) {
            return -EINVAL;
        }
        rc = read_cb(cb_arg, &foo_val, sizeof(foo_val));
    }
}
```
rc = read_cb(cb_arg, &foo_val, sizeof(foo_val));
if (rc >= 0) {
    return 0;
}

return rc;

return -ENOENT;

struct settings_handler my_conf = {
    .name = "foo",
    .h_set = foo_settings_set
};

int main(void)
{
    settings_subsys_init();
    settings_register(&my_conf);
    settings_load();
    foo_val++;
    settings_save_one("foo/bar", &foo_val, sizeof(foo_val));
    printk("foo: %d\n", foo_val);
    k_msleep(1000);
    sys_reboot(SYS_REBOOT_COLD);
}

4.23.10 Example: Custom Backend Implementation

This is a simple example showing how to register a simple custom backend handler (CONFIG_SETTINGS_CUSTOM).

```c
static int settings_custom_load(struct settings_store *cs,
    const struct settings_load_arg *arg)
{
    //...
}

static int settings_custom_save(struct settings_store *cs, const char *name,
    const char *value, size_t val_len)
{
    //...
}

/* custom backend interface */
static struct settings_store_itf settings_custom_itf = {
    .csi_load = settings_custom_load,
    .csi_save = settings_custom_save,
};

/* custom backend node */
static struct settings_store settings_custom_store = {
    .cs_itf = &settings_custom_itf
};
```
```c
int settings_backend_init(void)
{
    /* register custom backend */
    settings_dst_register(&settings_custom_store);
    settings_src_register(&settings_custom_store);
    return 0;
}
```

### 4.23.11 API Reference

The Settings subsystem APIs are provided by `settings.h`:

#### API for general settings usage

**Related code samples**

**Settings API**

Load and save configuration values using the settings API.

```c
group settings

Defines

SETTINGS_MAX_DIR_DEPTH

SETTINGS_MAX_NAME_LEN

SETTINGS_MAX_VAL_LEN

SETTINGS_NAME_SEPARATOR

SETTINGS_NAME_END

SETTINGS_EXTRA_LEN

SETTINGS_STATIC_HANDLER_DEFINE(_hname, _tree, _get, _set, _commit, _export)

Define a static handler for settings items.

This creates a variable *hname prepended by* `settings_handler`.

**Parameters**

- `_hname` – handler name
- `_tree` – subtree name
- `_get` – get routine (can be NULL)
- `_set` – set routine (can be NULL)
• _commit – commit routine (can be NULL)
• _export – export routine (can be NULL)

Typedefs

typedef ssize_t (*settings_read_cb)(void *cb_arg, void *data, size_t len)
Function used to read the data from the settings storage in h_set handler implementations.

Param cb_arg
[in] arguments for the read function. Appropriate cb_arg is transferred to h_set handler implementation by the backend.

Param data
[out] the destination buffer

Param len
[in] length of read

Return
positive: Number of bytes read, 0: key-value pair is deleted. On error returns -ERRNO code.

typedef int (*settings_load_direct_cb)(const char *key, size_t len, settings_read_cb read_cb, void *cb_arg, void *param)
Callback function used for direct loading.
Used by settings_load_subtree_direct function.

Param key
[in] the name with skipped part that was used as name in handler registration

Param len
[in] the size of the data found in the backend.

Param read_cb
[in] function provided to read the data from the backend.

Param cb_arg
[inout] arguments for the read function provided by the backend.

Param param
[inout] parameter given to the settings_load_subtree_direct function.

Return
When nonzero value is returned, further subtree searching is stopped.

Functions

int settings_subsys_init(void)
Initialization of settings and backend.
Can be called at application startup. In case the backend is a FS Remember to call it after the FS was mounted. For FCB backend it can be called without such a restriction.

Returns
0 on success, non-zero on failure.
int settings_register(struct settings_handler *cf)

Register a handler for settings items stored in RAM.

**Parameters**

- cf – Structure containing registration info.

**Returns**

0 on success, non-zero on failure.

int settings_load(void)

Load serialized items from registered persistence sources.

Handlers for serialized item subtrees registered earlier will be called for encountered values.

**Returns**

0 on success, non-zero on failure.

int settings_load_subtree(const char *subtree)

Load limited set of serialized items from registered persistence sources.

Handlers for serialized item subtrees registered earlier will be called for encountered values that belong to the subtree.

**Parameters**

- subtree – [in] name of the subtree to be loaded.

**Returns**

0 on success, non-zero on failure.

int settings_load_subtree_direct(const char *subtree, settings_load_direct_cb cb, void *param)

Load limited set of serialized items using given callback.

This function bypasses the normal data workflow in settings module. All the settings values that are found are passed to the given callback.

**Note:** This function does not call commit function. It works as a blocking function, so it is up to the user to call any kind of commit function when this operation ends.

**Parameters**

- subtree – [in] subtree name of the subtree to be loaded.
- param – [inout] parameter to be passed when callback function is called.

**Returns**

0 on success, non-zero on failure.

int settings_save(void)

Save currently running serialized items.

All serialized items which are different from currently persisted values will be saved.

**Returns**

0 on success, non-zero on failure.

int settings_save_one(const char *name, const void *value, size_t val_len)

Write a single serialized value to persisted storage (if it has changed value).

**Parameters**
• **name** – Name/key of the settings item.

• **value** – Pointer to the value of the settings item. This value will be transferred to the `settings_handler::h_export` handler implementation.

• **val_len** – Length of the value.

**Returns**
0 on success, non-zero on failure.

```c
int settings_delete(const char *name)
```
Delete a single serialized in persisted storage.
Deleting an existing key-value pair in the settings mean to set its value to NULL.

**Parameters**
• **name** – Name/key of the settings item.

**Returns**
0 on success, non-zero on failure.

```c
int settings_commit(void)
```
Call commit for all settings handler.
This should apply all settings which has been set, but not applied yet.

**Returns**
0 on success, non-zero on failure.

```c
int settings_commit_subtree(const char *subtree)
```
Call commit for settings handler that belong to subtree.
This should apply all settings which has been set, but not applied yet.

**Parameters**
• **subtree** – [in] name of the subtree to be committed.

**Returns**
0 on success, non-zero on failure.

```c
struct settings_handler
```
#include `<settings.h>` Config handlers for subtree implement a set of handler functions.
These are registered using a call to `settings_register`.

**Public Members**

```c
c const char *name
```
Name of subtree.

```c
int (*h_get)(const char *key, char *val, int val_len_max)
```
Get values handler of settings items identified by keyword names.

**Parameters:**
• **key**[in] the name with skipped part that was used as name in handler registration
• **val**[out] buffer to receive value.
• **val_len_max**[in] size of that buffer.

**Return:** length of data read on success, negative on failure.
int (*h_set)(const char *key, size_t len, settings_read_cb read_cb, void *cb_arg)
    Set value handler of settings items identified by keyword names.
    Parameters:
    • key[in] the name with skipped part that was used as name in handler registration
    • len[in] the size of the data found in the backend.
    • read_cb[in] function provided to read the data from the backend.
    • cb_arg[in] arguments for the read function provided by the backend.
    Return: 0 on success, non-zero on failure.

int (*h_commit)(void)
    This handler gets called after settings has been loaded in full.
    User might use it to apply setting to the application.
    Return: 0 on success, non-zero on failure.

int (*h_export)(int (*export_func)(const char *name, const void *val, size_t val_len))
    This gets called to dump all current settings items.
    This happens when settings_save tries to save the settings. Parameters:
    • export_func: the pointer to the internal function which appends a single key-value pair to persisted settings. Don't store duplicated value. The name is subtree/key string, val is the string with value.
    Return: 0 on success, non-zero on failure.

**Remark**

The User might limit a implementations of handler to serving only one keyword at one call - what will impose limit to get/set values using full subtree/key name.

sys_snod_t node
    Linked list node info for module internal usage.

struct settings_handler_static
    #include <settings.h> Config handlers without the node element, used for static handlers.
    These are registered using a call to SETTINGS_STATIC_HANDLER_DEFINE().

**Public Members**

const char *name
    Name of subtree.

int (*h_get)(const char *key, char *val, int val_len_max)
    Get values handler of settings items identified by keyword names.
    Parameters:
    • key[in] the name with skipped part that was used as name in handler registration
    • val[out] buffer to receive value.
• `val_len_max` size of that buffer.
Return: length of data read on success, negative on failure.

```c
int (*h_set)(const char *key, size_t len, settings_read_cb read_cb, void *cb_arg)
```
Set value handler of settings items identified by keyword names.

Parameters:
• `key` the name with skipped part that was used as name in handler registration
• `len` the size of the data found in the backend.
• `read_cb` function provided to read the data from the backend.
• `cb_arg` arguments for the read function provided by the backend.
Return: 0 on success, non-zero on failure.

```c
int (*h_commit)(void)
```
This handler gets called after settings has been loaded in full.
User might use it to apply setting to the application.

```c
int (*h_export)(int (*export_func)(const char *name, const void *val, size_t val_len))
```
This gets called to dump all current settings items.
This happens when `settings_save` tries to save the settings. Parameters:
• `export_func` the pointer to the internal function which appends a single key-value pair to persisted settings. Don't store duplicated value. The name is subtree/key string, val is the string with value.

Return: 0 on success, non-zero on failure.

**Remark**
The User might limit a implementations of handler to serving only one keyword at one call - what will impose limit to get/set values using full subtree/key name.

---

**API for key-name processing**

**Related code samples**

**Settings API**
Load and save configuration values using the settings API.

```
group settings_name_proc
```
API for const name processing.

**Functions**

```c
int settings_nameステq(const char *name, const char *key, const char **next)
```
Compares the start of name with a key.

Some examples:
```c
settings_nameステq("bt/btmesh/iv", "b", &next) returns 1,
next="t/btmesh/iv" settings_nameステq("bt/btmesh/iv", "bt", &next) returns 1,
```
next="btmesh/iv" settings_name_steq("bt/btmesh/iv", "bt/", &next) returns 0,  
next=NULL settings_name_steq("bt/btmesh/iv", "bta", &next) returns 0, next=NULL

REMARK: This routine could be simplified if the settings_handler names would include a separator at the end.

**Parameters**
- **name** – [in] in string format
- **key** – [in] comparison string
- **next** – [out] pointer to remaining of name, when the remaining part starts with a separator the separator is removed from next

**Returns**
- 0: no match
- 1: match, next can be used to check if match is full

```c
int settings_name_next(const char *name, const char **next)
```

determine the number of characters before the first separator

**Parameters**
- **name** – [in] in string format
- **next** – [out] pointer to remaining of name (excluding separator)

**Returns**
- index of the first separator, in case no separator was found this is the size of name

### API for runtime settings manipulation

#### Related code samples

**Settings API**
Load and save configuration values using the settings API.

**group settings_rt**

API for runtime settings.

**Functions**

```c
int settings_runtime_set(const char *name, const void *data, size_t len)
```
Set a value with a specific key to a module handler.

**Parameters**
- **name** – Key in string format.
- **data** – Binary value.
- **len** – Value length in bytes.

**Returns**
- 0 on success, non-zero on failure.

```c
int settings_runtime_get(const char *name, void *data, size_t len)
```
Get a value corresponding to a key from a module handler.

**Parameters**
- **name** – Key in string format.
• **data** – Returned binary value.
• **len** – requested value length in bytes.

**Returns**
length of data read on success, negative on failure.

```c
int settings_runtime_commit(const char *name)
```
Apply settings in a module handler.

**Parameters**
• **name** – Key in string format.

**Returns**
0 on success, non-zero on failure.

### API of backend interface

**Group** settings_backend

**Settings**

#### Functions

```c
void settings_src_register(struct settings_store *cs)
```
Register a backend handler acting as source.

**Parameters**
• **cs** – Backend handler node containing handler information.

```c
void settings_dst_register(struct settings_store *cs)
```
Register a backend handler acting as destination.

**Parameters**
• **cs** – Backend handler node containing handler information.

```c
struct settings_handler_ *settings_parse_and_lookup(const char *name, const char **next)
```
Parses a key to an array of elements and locate corresponding module handler.

**Parameters**
• **name** – [in] in string format
• **next** – [out] remaining of name after matched handler

**Returns**
settings_handler_static on success, NULL on failure.

```c
int settings_call_set_handler(const char *name, size_t len, settings_read_cb read_cb, void *read_cb_arg, const struct settings_load_arg *load_arg)
```
Calls settings handler.

**Parameters**
• **name** – [in] The name of the data found in the backend.
• **len** – [in] The size of the data found in the backend.
• **read_cb** – [in] Function provided to read the data from the backend.
• `read_cb_arg` – **[inout]** Arguments for the read function provided by the backend.
• `load_arg` – **[inout]** Arguments for data loading.

**Returns**
0 or negative error code

```c
struct settings_store
#include <settings.h> Backend handler node for storage handling.
```

**Public Members**

```c
sys_snode_t cs_next
  Linked list node info for internal usage.
```

```c
const struct settings_store_itf *cs_itf
  Backend handler structure.
```

```c
struct settings_load_arg
#include <settings.h> Arguments for data loading.
  Holds all parameters that changes the way data should be loaded from backend.
```

**Public Members**

```c
const char *subtree
  Name of the subtree to be loaded.
  If NULL, all values would be loaded.
```

```c
settings_load_direct_cb cb
  Pointer to the callback function.
  If NULL then matching registered function would be used.
```

```c
void *param
  Parameter for callback function.
  Parameter to be passed to the callback function.
```

```c
struct settings_store_itf
#include <settings.h> Backend handler functions.
```

Sources are registered using a call to `settings_src_register`. Destinations are registered using a call to `settings_dst_register`.

**Public Members**

```c
int (*csi_load)(struct settings_store *cs, const struct settings_load_arg *arg)
  Loads values from storage limited to subtree defined by subtree.
  Parameters:
```
• cs - Corresponding backend handler node,
• arg - Structure that holds additional data for data loading.

**Note:** Backend is expected not to provide duplicates of the entities. It means that if the backend does not contain any functionality to really delete old keys, it has to filter out old entities and call load callback only on the final entity.

```c
int (*csi_save_start)(struct settings_store *cs)
```

Handler called before an export operation.
Parameters:
• cs - Corresponding backend handler node

```c
int (*csi_save)(struct settings_store *cs, const char *name, const char *value, size_t val_len)
```

Save a single key-value pair to storage.
Parameters:
• cs - Corresponding backend handler node
• name - Key in string format
• value - Binary value
• val_len - Length of value in bytes.

```c
int (*csi_save_end)(struct settings_store *cs)
```

Handler called after an export operation.
Parameters:
• cs - Corresponding backend handler node

Get pointer to the storage instance used by the backend.
Parameters:
• cs - Corresponding backend handler node

### 4.24 State Machine Framework

#### 4.24.1 Overview

The State Machine Framework (SMF) is an application agnostic framework that provides an easy way for developers to integrate state machines into their application. The framework can be added to any project by enabling the `CONFIG_SMF` option.

#### 4.24.2 State Creation

A state is represented by three functions, where one function implements the Entry actions, another function implements the Run actions, and the last function implements the Exit actions. The prototype for these functions is as follows: `void funct(void *obj)`, where the obj parameter is a user defined structure that has the state machine context, `struct smf_ctx`, as its first member. For example:

```c
struct user_object {
    struct smf_ctx ctx;
    /* All User Defined Data Follows */
};
```
The struct `smf_ctx` member must be first because the state machine framework's functions casts the user defined object to the struct `smf_ctx` type with the following macro: `SMF_CTX(o)`.

For example instead of doing this `(struct smf_ctx *)&user_obj`, you could use `SMF_CTX(&user_obj)`.

By default, a state can have no ancestor states, resulting in a flat state machine. But to enable the creation of a hierarchical state machine, the `CONFIG_SMF_ANCESTOR_SUPPORT` option must be enabled.

The following macro can be used for easy state creation:

- `SMF_CREATE_STATE` Create a state

**NOTE:** The `SMF_CREATE_STATE` macro takes an additional parameter when `CONFIG_SMF_ANCESTOR_SUPPORT` is enabled.

### 4.24.3 State Machine Creation

A state machine is created by defining a table of states that's indexed by an enum. For example, the following creates three flat states:

```c
enum demo_state { S0, S1, S2 };
const struct smf_state demo_states[] = {
    [S0] = SMF_CREATE_STATE(s0_entry, s0_run, s0_exit),
    [S1] = SMF_CREATE_STATE(s1_entry, s1_run, s1_exit),
    [S2] = SMF_CREATE_STATE(s2_entry, s2_run, s2_exit)
};
```

And this example creates three hierarchical states:

```c
enum demo_state { S0, S1, S2 }; const struct smf_state demo_states[] = {
    [S0] = SMF_CREATE_STATE(s0_entry, s0_run, s0_exit, parent_s0),
    [S1] = SMF_CREATE_STATE(s1_entry, s1_run, s1_exit, parent_s12),
    [S2] = SMF_CREATE_STATE(s2_entry, s2_run, s2_exit, parent_s12)
};
```

To set the initial state, the `smf_set_initial` function should be called. It has the following prototype: `void smf_set_initial(smf_ctx *ctx, smf_state *state)`.

To transition from one state to another, the `smf_set_state` function is used and it has the following prototype: `void smf_set_state(smf_ctx *ctx, smf_state *state)`

**NOTE:** While the state machine is running, `smf_set_state` should only be called from the Entry and Run functions. Calling `smf_set_state` from the Exit functions doesn't make sense and will generate a warning.

### 4.24.4 State Machine Execution

To run the state machine, the `smf_run_state` function should be called in some application dependent way. An application should cease calling `smf_run_state` if it returns a non-zero value. The function has the following prototype: `int32_t smf_run_state(smf_ctx *ctx)`

### 4.24.5 State Machine Termination

To terminate the state machine, the `smf_terminate` function should be called. It can be called from the entry, run, or exit action. The function takes a non-zero user defined value that's
returned by the `smf_run_state` function. The function has the following prototype: `void
smf_terminate(smf_ctx *ctx, int32_t val)`

4.24.6 Flat State Machine Example

This example turns the following state diagram into code using the SMF, where the initial state
is S0.

![Flat state machine diagram](image)

**Fig. 15: Flat state machine diagram**

**Code:ICTUREocked on next page**
static void s0_run(void *o) {
    smf_set_state(SMF_CTX(&s_obj), &demo_states[S1]);
}

static void s0_exit(void *o) {
    /* Do something */
}

/* State S1 */
static void s1_run(void *o) {
    smf_set_state(SMF_CTX(&s_obj), &demo_states[S2]);
}

static void s1_exit(void *o) {
    /* Do something */
}

/* State S2 */
static void s2_entry(void *o) {
    /* Do something */
}

static void s2_run(void *o) {
    smf_set_state(SMF_CTX(&s_obj), &demo_states[S0]);
}

/* Populate state table */
static const struct smf_state demo_states[] = {
    [S0] = SMF_CREATE_STATE(s0_entry, s0_run, s0_exit),
    /* State S1 does not have an entry action */
    [S1] = SMF_CREATE_STATE(NULL, s1_run, s1_exit),
    /* State S2 does not have an exit action */
    [S2] = SMF_CREATE_STATE(s2_entry, s2_run, NULL),
};

int main(void) {
    int32_t ret;

    /* Set initial state */
    smf_set_initial(SMF_CTX(&s_obj), &demo_states[S0]);

    /* Run the state machine */
    while(1) {
        /* State machine terminates if a non-zero value is returned */
        ret = smf_run_state(SMF_CTX(&s_obj));
        if (ret) {
            /* handle return code and terminate state machine */
            break;
        }
        k_msleep(1000);
    }
}
4.24.7 Hierarchical State Machine Example

This example turns the following state diagram into code using the SMF, where S0 and S1 share a parent state and S0 is the initial state.

![Hierarchical state machine diagram](image)

**Fig. 16: Hierarchical state machine diagram**

**Code:**

```c
#include <zephyr/smf.h>

/* Forward declaration of state table */
static const struct smf_state demo_states[];

/* List of demo states */
enum demo_state { PARENT, S0, S1, S2 };

/* User defined object */
struct s_object {
  /* This must be first */
  struct smf_ctx ctx;
  /* Other state specific data add here */
} s_obj;

/* Parent State */
static void parent_entry(void *o)
{
  /* Do something */
}
static void parent_exit(void *o)
{
  /* Do something */
}
```

(continues on next page)
When designing hierarchical state machines, the following should be considered:

- Ancestor entry actions are executed before the sibling entry actions. For example, the parent_entry function is called before the s0_entry function.
- Transitioning from one sibling to another with a shared ancestry does not re-execute the ancestor's entry action or execute the exit action. For example, the parent_entry function is not called when transitioning from S0 to S1, nor is the parent_exit function called.
- Ancestor exit actions are executed after the sibling exit actions. For example, the s1_exit function is called before the parent_exit function is called.
• The parent_run function only executes if the child_run function returns without transitioning to another state, i.e., calling smf_set_state.

4.24.8 Event Driven State Machine Example

Events are not explicitly part of the State Machine Framework but an event driven state machine can be implemented using Zephyr Events.

![Event driven state machine diagram](image)

Fig. 17: Event driven state machine diagram

Code:

```c
#include <zephyr/kernel.h>
#include <zephyr/drivers/gpio.h>
#include <zephyr/smf.h>
#define SW0_NODE DT_ALIAS(sw0)

/* List of events */
#define EVENT_BTN_PRESS BIT(0)

static const struct gpio_dt_spec button =
    GPIO_DT_SPEC_GET_OR(SW0_NODE, gpios, {0});

static struct gpio_callback button_cb_data;

/* Forward declaration of state table */
static const struct smf_state demo_states[];

/* List of demo states */
enum demo_state { S0, S1 };

/* User defined object */
struct s_object {
    /* This must be first */
    struct smf_ctx ctx;
```

(continues on next page)
/* Events */
struct k_event smf_event;
int32_t events;
/* Other state specific data add here */
}s_obj;

/* State S0 */
static void s0_entry(void *o)
{
    printk("STATE0\n");
}
static void s0_run(void *o)
{
    struct s_object *s = (struct s_object *)o;
    /* Change states on Button Press Event */
    if (s->events & EVENT_BTN_PRESS) {
        smf_set_state(SMF_CTX(&s_obj), &demo_states[S1]);
    }
}

/* State S1 */
static void s1_entry(void *o)
{
    printk("STATE1\n");
}
static void s1_run(void *o)
{
    struct s_object *s = (struct s_object *)o;
    /* Change states on Button Press Event */
    if (s->events & EVENT_BTN_PRESS) {
        smf_set_state(SMF_CTX(&s_obj), &demo_states[S0]);
    }
}

/* Populate state table */
static const struct smf_state demo_states[] = {
    [S0] = SMF_CREATE_STATE(s0_entry, s0_run, NULL),
    [S1] = SMF_CREATE_STATE(s1_entry, s1_run, NULL),
};

void button_pressed(const struct device *dev,
    struct gpio_callback *cb, uint32_t pins)
{
    /* Generate Button Press Event */
    k_event_post(&s_obj.smf_event, EVENT_BTN_PRESS);
}

int main(void)
{
    int ret;
    if (!gpio_is_ready_dt(&button)) {
        printk("Error: button device %s is not ready\n",
                button.port->name);
        return;
    }
}
ret = gpio_pin_configure_dt(&button, GPIO_INPUT);
if (ret != 0) {
    printk("Error %d: failed to configure %s pin %d\n",
           ret, button.port->name, button.pin);
    return;
}

ret = gpio_pin_interrupt_configure_dt(&button, 
        GPIO_INT_EDGE_TO_ACTIVE);
if (ret != 0) {
    printk("Error %d: failed to configure interrupt on %s pin %d\n",
           ret, button.port->name, button.pin);
    return;
}

gpio_init_callback(&button_cb_data, button_pressed, BIT(button.pin));
gpio_add_callback(button.port, &button_cb_data);

/* Initialize the event */
k_event_init(&s_obj.smf_event);

/* Set initial state */
smf_set_initial(SMF_CTX(&s_obj), &demo_states[S0]);

/* Run the state machine */
while(1) {
    /* Block until an event is detected */
    s_obj.events = k_event_wait(&s_obj.smf_event, 
            EVENTBTN_PRESS, true, K_FOREVER);

    /* State machine terminates if a non-zero value is returned */
    ret = smf_run_state(SMF_CTX(&s_obj));
    if (ret) {
        /* handle return code and terminate state machine */
        break;
    }
}

4.25 Storage

4.25.1 Non-Volatile Storage (NVS)

Elements, represented as id-data pairs, are stored in flash using a FIFO-managed circular buffer. The flash area is divided into sectors. Elements are appended to a sector until storage space in the sector is exhausted. Then a new sector in the flash area is prepared for use (erased). Before erasing the sector it is checked that identifier - data pairs exist in the sectors in use, if not the id-data pair is copied.

The id is a 16-bit unsigned number. NVS ensures that for each used id there is at least one id-data pair stored in flash at all time.

NVS allows storage of binary blobs, strings, integers, longs, and any combination of these.

Each element is stored in flash as metadata (8 byte) and data. The metadata is written in a table starting from the end of a nvs sector; the data is written one after the other from the start of the sector. The metadata consists of: id, data offset in sector, data length, part (unused), and a CRC. The CRC is only calculated over the metadata and only ensures that a write has been completed.
The actual data of the element is not protected by a CRC. It is encouraged to include a CRC as part of the data and to take appropriate corrective actions when the data CRC does not match its expected value.

A write of data to nvs always starts with writing the data, followed by a write of the metadata. Data that is written in flash without metadata is ignored during initialization.

During initialization NVS will verify the data stored in flash, if it encounters an error it will ignore any data with missing/incorrect metadata.

NVS checks the id-data pair before writing data to flash. If the id-data pair is unchanged no write to flash is performed.

To protect the flash area against frequent erases it is important that there is sufficient free space. NVS has a protection mechanism to avoid getting in an endless loop of flash page erases when there is limited free space. When such a loop is detected NVS returns that there is no more space available.

For NVS the file system is declared as:

```c
static struct nvs_fs fs = {
    .flash_device = NVS_FLASH_DEVICE,
    .sector_size = NVS_SECTOR_SIZE,
    .sector_count = NVS_SECTOR_COUNT,
    .offset = NVS_STORAGE_OFFSET,
};
```

where

- NVS_FLASH_DEVICE is a reference to the flash device that will be used. The device needs to be operational.
- NVS_SECTOR_SIZE is the sector size, it has to be a multiple of the flash erase page size and a power of 2.
- NVS_SECTOR_COUNT is the number of sectors, it is at least 2, one sector is always kept empty to allow copying of existing data.
- NVS_STORAGE_OFFSET is the offset of the storage area in flash.

**Flash wear**

When writing data to flash a study of the flash wear is important. Flash has a limited life which is determined by the number of times flash can be erased. Flash is erased one page at a time and the pagesize is determined by the hardware. As an example a nRF51822 device has a pagesize of 1024 bytes and each page can be erased about 20,000 times.

**Calculating expected device lifetime** Suppose we use a 4 bytes state variable that is changed every minute and needs to be restored after reboot. NVS has been defined with a sector_size equal to the pagesize (1024 bytes) and 2 sectors have been defined.

Each write of the state variable requires 12 bytes of flash storage: 8 bytes for the metadata and 4 bytes for the data. When storing the data the first sector will be full after 1024/12 = 85.33 minutes. After another 85.33 minutes, the second sector is full. When this happens, because we’re using only two sectors, the first sector will be used for storage and will be erased after 171 minutes of system time. With the expected device life of 20,000 writes, with two sectors writing every 171 minutes, the device should last about 171 * 20,000 minutes, or about 6.5 years.

More generally then, with

- \( NS \) as the number of storage requests per minute,
- \( DS \) as the data size in bytes,
SECTOR_SIZE in bytes, and
- PAGE_ERASES as the number of times the page can be erased,
the expected device life (in minutes) can be calculated as:

\[
\text{SECTOR_COUNT} \times \text{SECTOR_SIZE} \times \text{PAGE_ERASES} / (\text{NS} \times (\text{DS}+8)) \text{ minutes}
\]

From this formula it is also clear what to do in case the expected life is too short: increase \text{SECTOR_COUNT} or \text{SECTOR_SIZE}.

Flash write block size migration

It is possible that during a DFU process, the flash driver used by the NVS changes the supported minimal write block size. The NVS in-flash image will stay compatible unless the physical ATE size changes. Especially, migration between 1,2,4,8-bytes write block sizes is allowed.

Sample

A sample of how NVS can be used is supplied in \texttt{samples/subsys/nvs}.

Troubleshooting

**MPU fault while using NVS, or -ETIMEDOUT error returned**

NVS can use the internal flash of the SoC. While the MPU is enabled, the flash driver requires MPU RWX access to flash memory, configured using \texttt{CONFIG_MPU_ALLOW_FLASH_WRITE}. If this option is disabled, the NVS application will get an MPU fault if it references the internal SoC flash and it's the only thread running. In a multi-threaded application, another thread might intercept the fault and the NVS API will return an -ETIMEDOUT error.

API Reference

The NVS subsystem APIs are provided by \texttt{nvs.h}:

**group nvs_data_structures**

Non-volatile Storage Data Structures.

\texttt{struct nvs_fs}

\texttt{#include <nvs.h>} Non-volatile Storage File system structure.

**Public Members**

\texttt{off_t offset}

File system offset in flash.

\texttt{uint32_t ate_wra}

Allocation table entry write address.

Addresses are stored as uint32_t:
- high 2 bytes correspond to the sector
- low 2 bytes are the offset in the sector
uint32_t data_wra
    Data write address.

uint16_t sector_size
    File system is split into sectors, each sector must be multiple of erase-block-size.

uint16_t sector_count
    Number of sectors in the file system.

bool ready
    Flag indicating if the file system is initialized.

struct k_mutex nvs_lock
    Mutex.

const struct device *flash_device
    Flash device runtime structure.

const struct flash_parameters *flash_parameters
    Flash memory parameters structure.

---

**Related code samples**

**Non-Volatile Storage (NVS)**

Store and retrieve data from flash using the NVS API.

**group nvs_high_level_api**

Non-volatile Storage APIs.

**Functions**

`int nvs_mount(struct nvs_fs *fs)`

Mount an NVS file system onto the flash device specified in `fs`

**Parameters**

- `fs` – Pointer to file system

**Return values**

- `0` – Success
- `ERRNO` – errno code if error

`int nvs_clear(struct nvs_fs *fs)`

Clear the NVS file system from flash.

**Parameters**

- `fs` – Pointer to file system

**Return values**

- `0` – Success
- `ERRNO` – errno code if error
ssize_t nvs_write(struct nvs_fs *fs, uint16_t id, const void *data, size_t len)
Write an entry to the file system.

**Note:** When len parameter is equal to 0 then entry is effectively removed (it is equivalent to calling of nvs_delete). Any calls to nvs_read for entries with data of length 0 will return error.
It is not possible to distinguish between deleted entry and entry with data of length 0.

**Parameters**
- fs – Pointer to file system
- id – Id of the entry to be written
- data – Pointer to the data to be written
- len – Number of bytes to be written

**Returns**
Number of bytes written. On success, it will be equal to the number of bytes requested to be written. When a rewrite of the same data already stored is attempted, nothing is written to flash, thus 0 is returned. On error, returns negative value of errno.h defined error codes.

int nvs_delete(struct nvs_fs *fs, uint16_t id)
Delete an entry from the file system.

**Parameters**
- fs – Pointer to file system
- id – Id of the entry to be deleted

**Return values**
- 0 – Success
- -ERRNO – errno code if error

ssize_t nvs_read(struct nvs_fs *fs, uint16_t id, void *data, size_t len)
Read an entry from the file system.

**Parameters**
- fs – Pointer to file system
- id – Id of the entry to be read
- data – Pointer to data buffer
- len – Number of bytes to be read

**Returns**
Number of bytes read. On success, it will be equal to the number of bytes requested to be read. When the return value is larger than the number of bytes requested to read this indicates not all bytes were read, and more data is available. On error, returns negative value of errno.h defined error codes.

ssize_t nvs_read_hist(struct nvs_fs *fs, uint16_t id, void *data, size_t len, uint16_t cnt)
Read a history entry from the file system.

**Parameters**
- fs – Pointer to file system
• id – Id of the entry to be read
• data – Pointer to data buffer
• len – Number of bytes to be read
• cnt – History counter: 0: latest entry, 1: one before latest ...

Returns
Number of bytes read. On success, it will be equal to the number of bytes requested to be read. When the return value is larger than the number of bytes requested to read this indicates not all bytes were read, and more data is available. On error, returns negative value of errno.h defined error codes.

```
ssize_t nvs_calc_free_space(struct nvs_fs *fs)
```

Calculate the available free space in the file system.

Parameters
• fs – Pointer to file system

Returns
Number of bytes free. On success, it will be equal to the number of bytes that can still be written to the file system. Calculating the free space is a time consuming operation, especially on spi flash. On error, returns negative value of errno.h defined error codes.

4.25.2 Disk Access

Overview
The disk access API provides access to storage devices.

SD Card support
Zephyr has support for some SD card controllers and support for interfacing SD cards via SPI. These drivers use disk driver interface and a file system can access the SD cards via disk access API. Both standard and high-capacity SD cards are supported.

Note: The system does not support inserting or removing cards while the system is running. The cards must be present at boot and must not be removed. This may be fixed in future releases. FAT filesystems are not power safe so the filesystem may become corrupted if power is lost or if the card is removed.

4.25. Storage
&spi1 {
    status = "okay";
    cs-gpios = &porta 27 GPIO_ACTIVE_LOW;
    sdhc0: sdhc@0 {
        compatible = "zephyr,spidev-slot";
        reg = <0>;
        status = "okay";
        mmc {
            compatible = "zephyr,spi mmc";
            status = "okay";
        };
        spi-max-frequency = <24000000>;
    }
};

The SD card will be automatically detected and initialized by the filesystem driver when the board boots.

To read and write files and directories, see the `File Systems` in include/zephyr/fs/fs.h such as `fs_open()`, `fs_read()`, and `fs_write()`.

**eMMC Device Support**

Zephyr also has support for eMMC devices using the Disk Access API. MMC in zephyr is implemented using the SD subsystem because the MMC bus shares a lot of similarity with the SD bus. MMC controllers also use the SDHC device driver API.

**Emulated block device on flash partition support**

Zephyr flashdisk driver makes it possible to use flash memory partition as a block device. The flashdisk instances are defined in devicetree:

```
/ {
    msc_disk0 {
        compatible = "zephyr,flash-disk";
        partition = &storage_partition;
        disk-name = "NAND";
        cache-size = <4096>;
    };
}
```

The cache size specified in `zephyr,flash-disk` node should be equal to backing partition minimum erasable block size.

**NVMe disk support**  NVMe disks are also supported

**NVMe**  NVMe is a standardized logical device interface on PCIe bus exposing storage devices. NVMe controllers and disks are supported. Disks can be accessed via the `Disk Access API` they expose and thus be used through the `File System API`.

**Driver design**  The driver is sliced up in 3 main parts: - NVMe controller drivers/disk/nvme/nvme_controller.c - NVMe commands drivers/disk/nvme/nvme_cmd.c - NVMe namespace drivers/disk/nvme/nvme_namespace.c
Where the NVMe controller is the root of the device driver. This is the one that will get device driver instances. Note that this is only what DTS describes: the NVMe controller, and none of its namespaces (disks). The NVMe command is the generic logic used to communicate with the controller and the namespaces it exposes. Finally the NVMe namespace is the dedicated part to deal with an actual namespace which, in turn, enables applications accessing each ones through the Disk Access API drivers/disk/nvme/nvme_disk.c.

If a controller exposes more than 1 namespace (disk), it will be possible to raise the amount of built-in namespace support by tweaking the configuration option CONFIG_NVME_MAX_NAMESPACES (see below).

Each exposed disk, via it's related disk_info structure, will be distinguished by its name which is inherited from it's related namespace. As such, the disk name follows NVMe naming which is nvme<k>n<n> where k is the controller number and n the namespace number. Most of the time, if only one NVMe disk is plugged into the system, one will see ‘nvme0n0’ as an exposed disk.

### NVMe configuration

#### DTS

Any board exposing an NVMe disk should provide a DTS overlay to enable its use within Zephyr

```c
#include <zephyr/dt-bindings/pcie/pcie.h>
/
{  
  pcie0 {
    nvme0: nvme0 {
      compatible = "nvme-controller";
      vendor-id = <VENDOR_ID>;
      device-id = <DEVICE_ID>;
      status = "okay";
    }
  }
};
```

Where VENDOR_ID and DEVICE_ID are the ones from the exposed NVMe controller.

#### Options

- CONFIG_NVME

Note that NVME requires the target to support PCIe multi-vector MSI-X in order to function.

- CONFIG_NVME_MAX_NAMESPACES

**Important note for users** NVMe specifications mandate the data buffer to be placed in a dword (4 bytes) aligned address. While this is not a problem for advanced OS managing virtual memory and dynamic allocations below the user processes, this can become an issue in Zephyr as soon as buffer addresses map directly to physical memory.

At this stage then, it is up to the user to make sure the buffer address being provided to `disk_access_read()` and `disk_access_write()` are dword aligned.

#### Disk Access API Configuration Options

Related configuration options:

- CONFIG_DISK_ACCESS
File system manipulation

Use file system API with various filesystems and storage devices.

**group disk_access_interface**

Disk Access APIs.

**Functions**

`int disk_access_init(const char *pdrv)`

perform any initialization

This call is made by the consumer before doing any IO calls so that the disk or the backing device can do any initialization.

**Parameters**

- `pdrv` – [in] Disk name

**Returns**

0 on success, negative errno code on fail

`int disk_access_status(const char *pdrv)`

Get the status of disk.

This call is used to get the status of the disk

**Parameters**

- `pdrv` – [in] Disk name

**Returns**

DISK_STATUS_OK or other DISK_STATUS_*s

`int disk_access_read(const char *pdrv, uint8_t *data_buf, uint32_t start_sector, uint32_t num_sector)`

read data from disk

Function to read data from disk to a memory buffer.

Note: if the disk is of NVMe type, user will need to ensure data_buf pointer is 4-bytes aligned.

**Parameters**

- `pdrv` – [in] Disk name
- `data_buf` – [in] Pointer to the memory buffer to put data.
- `start_sector` – [in] Start disk sector to read from
- `num_sector` – [in] Number of disk sectors to read

**Returns**

0 on success, negative errno code on fail
int disk_access_write(const char *pdrv, const uint8_t *data_buf, uint32_t start_sector, uint32_t num_sector)

write data to disk
Function write data from memory buffer to disk.
Note: if the disk is of NVMe type, user will need to ensure data_buf pointer is 4-bytes aligned.

Parameters
  • pdrv – [in] Disk name
  • data_buf – [in] Pointer to the memory buffer
  • start_sector – [in] Start disk sector to write to
  • num_sector – [in] Number of disk sectors to write

Returns
0 on success, negative errno code on fail

int disk_access_ioctl(const char *pdrv, uint8_t cmd, void *buff)
Get/Configure disk parameters.
Function to get disk parameters and make any special device requests.

Parameters
  • pdrv – [in] Disk name
  • cmd – [in] DISK_IOCTL_* code describing the request
  • buff – [in] Command data buffer

Returns
0 on success, negative errno code on fail

Disk Driver Configuration Options

Related driver configuration options:
  • CONFIG_DISK_DRIVERS

Disk Driver Interface

group disk_driver_interface
  Disk Driver Interface.

Defines

DISK_IOCTL_GET_SECTOR_COUNT
  Possible Cmd Codes for disk_ioctl()
  Get the number of sectors in the disk

DISK_IOCTL_GET_SECTOR_SIZE
  Get the size of a disk SECTOR in bytes.
DISK_IOCTL_RESERVED
    reserved.
    It used to be DISK_IOCTL_GET_DISK_SIZE

DISK_IOCTL_GET_ERASE_BLOCK_SZ
    How many sectors constitute a FLASH Erase block.

DISK_IOCTL_CTRL_SYNC
    Commit any cached read/writes to disk.

DISK_STATUS_OK
    Possible return bitmasks for disk_status()
    Disk status okay

DISK_STATUS_UNINIT
    Disk status uninitialized.

DISK_STATUS_NOMEDIA
    Disk status no media.

DISK_STATUS_WR_PROTECT
    Disk status write protected.

Functions

int disk_access_register(struct disk_info *disk)
    Register disk.

    Parameters
    • disk – [in] Pointer to the disk info structure

    Returns
    0 on success, negative errno code on fail

int disk_access_unregister(struct disk_info *disk)
    Unregister disk.

    Parameters
    • disk – [in] Pointer to the disk info structure

    Returns
    0 on success, negative errno code on fail

struct disk_info
    #include <disk.h> Disk info.

Public Members

sys_dnode_t node
    Internally used list node.
struct disk_operations

#include <disk.h> Disk operations.

4.25.3 Flash map

The <zephyr/storage/flash_map.h> API allows accessing information about device flash partitions via flash_area structures.

Each flash_area describes a flash partition. The API provides access to a “flash map”, which contains predefined flash areas accessible via globally unique ID numbers. The map is created from “fixed-partition” compatible entries in DTS file. Users may also create flash_area objects at runtime for application-specific purposes.

This documentation uses “flash area” when referencing single “fixed-partition” entities.

The flash_area contains a pointer to a device, which can be used to access the flash device an area is placed on directly with the flash API. Each flash area is characterized by a device it is placed on, offset from the beginning of the device and size on the device. An additional identifier parameter is used by the flash_area_open() function to find flash area in flash map.

The flash_map.h API provides functions for operating on a flash_area. The main examples are flash_area_read() and flash_area_write(). These functions are basically wrappers around the flash API with additional offset and size checks, to limit flash operations to a predefined area.

Most <zephyr/storage/flash_map.h> API functions require a flash_area object pointer characterizing the flash area they will be working on. There are two possible methods to obtain such a pointer:

- obtain it using flash_area_open;

- defining a flash_area type object, which requires providing a valid device object pointer with offset and size of the area within the flash device.

flash_area_open() uses numeric identifiers to search flash map for flash_area objects and returns, if found, a pointer to an object representing area with given ID. The ID number for a flash area can be obtained from a fixed-partition DTS node label using FIXED_PARTITION_ID(); these labels are obtained from the devicetree as described below.

Relationship with Devicetree

The flash_map.h API uses data generated from the Devicetree API, in particular its Fixed flash partitions. Zephyr additionally has some partitioning conventions used for Device Firmware Upgrade via the MCUboot bootloader, as well as defining partitions usable by file systems or other nonvolatile storage.

Here is an example devicetree fragment which uses fixed flash partitions for both MCUboot and a storage partition. Some details were left out for clarity.
Partition offset shall be expressed in relation to the flash memory beginning address, to which the partition belongs to.

The boot_partition, slot0_partition, slot1_partition, and scratch_partition node labels are defined for MCUboot, though not all MCUboot configurations require all of them to be defined. See the MCUboot documentation for more details.

The storage_partition node is defined for use by a file system or other nonvolatile storage API.

Numeric flash area ID is obtained by passing DTS node label to \texttt{FIXED_PARTITION_ID()}; for example to obtain ID number for slot0_partition, user would invoke \texttt{FIXED_PARTITION_ID(slot0_partition)}.

All \texttt{FIXED_PARTITION_{}} macros take DTS node labels as partition identifiers.

Users do not have to obtain a \texttt{flash_area} object pointer using \texttt{flash_map_open()} to get information on flash area size, offset or device, if such area is defined in DTS file. Knowing the DTS node label of an area, users may use \texttt{FIXED_PARTITION_OFFSET()}, \texttt{FIXED_PARTITION_SIZE()} or \texttt{FIXED_PARTITION_DEVICE()} respectively to obtain such information directly from DTS node definition. For example to obtain offset of storage_partition it is enough to invoke \texttt{FIXED_PARTITION_OFFSET(storage_partition)}.

Below example shows how to obtain a \texttt{flash_area} object pointer using \texttt{flash_area_open()} and DTS node label:

```c
const struct flash_area *my_area;
int err = flash_area_open(FIXED_PARTITION_ID(slot0_partition), &my_area);
if (err != 0) {
```

(continues on next page)
handle_the_error(err);
} else {
    flash_area_read(my_area, ...);
}

**API Reference**

**Related code samples**

**LittleFS filesystem**
Use file system API over LittleFS.

**nRF SoC flash**
Use the flash API to interact with the SoC flash.

---

**group flash_area_api**
Abstraction over flash partitions/areas and their drivers.

**Defines**

**SOC_FLASH_0_ID**
Provided for compatibility with MCUboot.

**SPI_FLASH_0_ID**
Provided for compatibility with MCUboot.

**FIXED_PARTITION_EXISTS(label)**
Returns non-0 value if fixed-partition of given DTS node label exists.

**Parameters**

- **label** – DTS node label

**Returns**

non-0 if fixed-partition node exists and is enabled; 0 if node does not exist, is not enabled or is not fixed-partition.

**FIXED_PARTITION_ID(label)**
Get flash area ID from fixed-partition DTS node label.

**Parameters**

- **label** – DTS node label of a partition

**Returns**

flash area ID

**FIXED_PARTITION_OFFSET(label)**
Get fixed-partition offset from DTS node label.

**Parameters**

- **label** – DTS node label of a partition

**Returns**

fixed-partition offset, as defined for the partition in DTS.
**FIXED_PARTITION_SIZE**(label)
Get fixed-partition size for DTS node label.

**Parameters**
- `label` – DTS node label

**Returns**
fixed-partition offset, as defined for the partition in DTS.

**FLASH_AREA_DEVICE**(label)
Get device pointer for device the area/partition resides on.

**Parameters**
- `label` – DTS node label of a partition

**Returns**
const struct device type pointer

**FIXED_PARTITION_DEVICE**(label)
Get device pointer for device the area/partition resides on.

**Parameters**
- `label` – DTS node label of a partition

**Returns**
Pointer to a device.

**Typedefs**

typedef void (*`flash_area_cb_t`(const struct flash_area *fa, void *user_data))
Flash map iteration callback.

**Param fa**
flash area

**Param user_data**
User supplied data

**Functions**

`int flash_area_open` (uint8_t id, const struct flash_area **fa)
Retrieve partitions flash area from the flash_map.
Function Retrieves `flash_area` from flash_map for given partition.

**Parameters**
- `fa` – [out] Pointer which has to reference `flash_area`. If ID is unknown, it will be NULL on output.

**Returns**
0 on success, -EACCES if the flash_map is not available, -ENOENT if ID is unknown, -ENODEV if there is no driver attached to the area.

`void flash_area_close`(const struct flash_area *fa)
Close `flash_area`.
Reserved for future usage and external projects compatibility reason. Currently is NOP.
Parameters

- **fa** — [in] Flash area to be closed.

```c
int flash_area_read(const struct flash_area *fa, off_t off, void *dst, size_t len)
```

Read flash area data.

Read data from flash area. Area readout boundaries are asserted before read request. API has the same limitation regard read-block alignment and size as wrapped flash driver.

**Parameters**

- **fa** — [in] Flash area
- **off** — [in] Offset relative from beginning of flash area to read
- **dst** — [out] Buffer to store read data
- **len** — [in] Number of bytes to read

**Returns**

0 on success, negative errno code on fail.

```c
int flash_area_write(const struct flash_area *fa, off_t off, const void *src, size_t len)
```

Write data to flash area.

Write data to flash area. Area write boundaries are asserted before write request. API has the same limitation regard write-block alignment and size as wrapped flash driver.

**Parameters**

- **fa** — [in] Flash area
- **off** — [in] Offset relative from beginning of flash area to write
- **src** — [in] Buffer with data to be written
- **len** — [in] Number of bytes to write

**Returns**

0 on success, negative errno code on fail.

```c
int flash_area_erase(const struct flash_area *fa, off_t off, size_t len)
```

Erase flash area.

Erase given flash area range. Area boundaries are asserted before erase request. API has the same limitation regard erase-block alignment and size as wrapped flash driver.

**Parameters**

- **fa** — [in] Flash area
- **off** — [in] Offset relative from beginning of flash area.
- **len** — [in] Number of bytes to be erase

**Returns**

0 on success, negative errno code on fail.

```c
uint32_t flash_area_align(const struct flash_area *fa)
```

Get write block size of the flash area.

Currently write block size might be treated as read block size, although most of drivers supports unaligned readout.

**Parameters**

- **fa** — [in] Flash area

**Returns**

Alignment restriction for flash writes in [B].
int flash_area_get_sectors(int fa_id, uint32_t *count, struct flash_sector *sectors)
Retrieve info about sectors within the area.

Parameters
• fa_id – [in] Given flash area ID
• sectors – [out] buffer for sectors data
• count – [inout] On input Capacity of sectors, on output number of sectors Retrieved.

Returns
0 on success, negative errno code on fail. Especially returns -ENOMEM if There are too many flash pages on the flash_area to fit in the array.

void flash_area_foreach(flash_area_cb_t user_cb, void *user_data)
Iterate over flash map.

Parameters
• user_cb – User callback
• user_data – User supplied data

int flash_area_has_driver(const struct flash_area *fa)
Check whether given flash area has supporting flash driver in the system.

Parameters
• fa – [in] Flash area.

Returns
1 On success. -ENODEV if no driver match.

const struct device *flash_area_get_device(const struct flash_area *fa)
Get driver for given flash area.

Parameters
• fa – [in] Flash area.

Returns
device driver.

uint8_t flash_area_erased_val(const struct flash_area *fa)
Get the value expected to be read when accessing any erased flash byte.
This API is compatible with the MCUBoot’s porting layer.

Parameters
• fa – Flash area.

Returns
Byte value of erase memory.

struct flash_area
#include <flash_map.h> Flash partition.
This structure represents a fixed-size partition on a flash device. Each partition contains one or more flash sectors.

Public Members
uint8_t fa_id
   ID number.

off_t fa_off
   Start offset from the beginning of the flash device.

size_t fa_size
   Total size.

const struct device *fa_dev
   Backing flash device.

struct flash_sector
   #include <flash_map.h> Structure for transfer flash sector boundaries.
   This template is used for presentation of flash memory structure. It consumes much
   less RAM than flash_area

Public Members

off_t fs_off
   Sector offset from the beginning of the flash device.

size_t fs_size
   Sector size in bytes.

4.25.4 Flash Circular Buffer (FCB)

Flash circular buffer provides an abstraction through which you can treat flash like a FIFO. You
append entries to the end, and read data from the beginning.

Note: As of Zephyr release 2.1 the NVS storage API is recommended over FCB for use as a back-end for the settings API.

Description

Entries in the flash contain the length of the entry, the data within the entry, and checksum over
the entry contents.

Storage of entries in flash is done in a FIFO fashion. When you request space for the next entry,
space is located at the end of the used area. When you start reading, the first entry served is the
oldest entry in flash.

Entries can be appended to the end of the area until storage space is exhausted. You have control
over what happens next; either erase oldest block of data, thereby freeing up some space, or stop
writing new data until existing data has been collected. FCB treats underlying storage as an array
of flash sectors; when it erases old data, it does this a sector at a time.

Entries in the flash are checksummed. That is how FCB detects whether writing entry to flash
completed ok. It will skip over entries which don’t have a valid checksum.
Usage

To add an entry to circular buffer:

- Call \texttt{fcb\_append()} to get the location where data can be written. If this fails due to lack of space, you can call \texttt{fcb\_rotate()} to erase the oldest sector which will make the space. And then call \texttt{fcb\_append()} again.
- Use \texttt{flash\_area\_write()} to write entry contents.
- Call \texttt{fcb\_append\_finish()} when done. This completes the writing of the entry by calculating the checksum.

To read contents of the circular buffer:

- Call \texttt{fcb\_walk()} with a pointer to your callback function.
- Within callback function copy in data from the entry using \texttt{flash\_area\_read()}. You can tell when all data from within a sector has been read by monitoring the returned entry’s area pointer. Then you can call \texttt{fcb\_rotate()}, if you’re done with that data.

Alternatively:

- Call \texttt{fcb\_getnext()} with 0 in entry offset to get the pointer to the oldest entry.
- Use \texttt{flash\_area\_read()} to read entry contents.
- Call \texttt{fcb\_getnext()} with pointer to current entry to get the next one. And so on.

API Reference

The FCB subsystem APIs are provided by \texttt{fcb.h}:

**Data structures**

\texttt{group fcb\_data\_structures}

**Defines**

\begin{verbatim}
FCB\_MAX\_LEN
    Max length of element.
FCB\_ENTRY\_FA\_DATA\_OFF(entry)
    Helper macro for calculating the data offset related to the fcb \texttt{flash\_area} start offset.

    Parameters
    - entry – fcb entry structure

FCB\_FLAGS\_CRC\_DISABLED
    Flag to disable CRC for the fcb\_entries in flash.

struct fcb\_entry
    #include <fcb.h> FCB entry info structure.

    This data structure describes the element location in the flash.

    You would use it to figure out what parameters to pass to \texttt{flash\_area\_read()} to read element contents. Or to \texttt{flash\_area\_write()} when adding a new element. Entry location is pointer to area (within fcb->f_sectors), and offset within that area.
\end{verbatim}
Public Members

struct flash_sector *fe_sector

    Pointer to info about sector where data are placed.

uint32_t fe_elem_off

    Offset from the start of the sector to beginning of element.

uint32_t fe_data_off

    Offset from the start of the sector to the start of element.

uint16_t fe_data_len

    Size of data area in fcb entry.

Public Members

struct fcb_entry_ctx

    #include <fcb.h> Structure for transferring complete information about FCB entry location within flash memory.

Public Members

struct fcb_entry loc

    FCB entry info.

const struct flash_area *fap

    Flash area where the entry is placed.

Public Members

struct fcb

    #include <fcb.h> FCB instance structure.

    The following data structure describes the FCB itself. First part should be filled in by the user before calling fcb_init. The second part is used by FCB for its internal bookkeeping.

Public Members

uint32_t f_magic

    Magic value, should not be 0xFFFFFFFF.

    It is xored with inversion of f_erase_value and placed in the beginning of FCB flash sector. FCB uses this when determining whether sector contains valid data or not. Giving it value of 0xFFFFFFFF means leaving bytes of the filed in “erased” state.

uint8_t f_version

    Current version number of the data.

uint8_t f_sector_cnt

    Number of elements in sector array.
uint8_t f_scratch_cnt
   Number of sectors to keep empty.
   This can be used if you need to have scratch space for garbage collecting when FCB
   fills up.

struct flash_sector *f_sectors
   Array of sectors, must be contiguous.

struct k_mutex f_mtx
   Locking for accessing the FCB data, internal state.

struct flash_sector *f_oldest
   Pointer to flash sector containing the oldest data, internal state.

struct fcb_entry f_active
   internal state

uint16_t f_active_id
   Flash location where the newest data is, internal state.

uint8_t f_align
   writes to flash have to aligned to this, internal state

const struct flash_area *fap
   Flash area used by the fcb instance, internal state.
   This can be transfer to FCB user

uint8_t f_erase_value
   The value flash takes when it is erased.
   This is read from flash parameters and initialized upon call to fcb_init.

API functions

group fcb_api
   Flash Circular Buffer APIs.

Typedefs

typedef int (*fcb_walk_cb)(struct fcb_entry_ctx *loc_ctx, void *arg)
   FCB Walk callback function type.
   Type of function which is expected to be called while walking over fcb entries thanks
   to a fcb_walk call.
   Entry data can be read using flash_area_read(), using loc_ctx fields as arguments. If cb
   wants to stop the walk, it should return non-zero value.

   Param loc_ctx
      [in] entry location information (full context)
Param arg
[inout] callback context, transferred from *fcb_walk.*

Return
0 continue walking, non-zero stop walking.

Functions

int fcb_init(int f_area_id, struct fcb *fcb)
Initialize FCB instance.

Parameters
• f_area_id – [in] ID of flash area where fcb storage resides.
• fcb – [inout] FCB instance structure.

Returns
0 on success, non-zero on failure.

int fcb_append(struct fcb *fcb, uint16_t len, struct fcb_entry *loc)
Appends an entry to circular buffer.
When writing the contents for the entry, use loc->fe_sector and loc->fe_data_off with
*flash_area_write() to *fcb flash_area. When you’re finished, call *fcb_append_finish() with
loc as argument.

Parameters
• fcb – [in] FCB instance structure.
• len – [in] Length of data which are expected to be written as the entry
payload.
• loc – [out] entry location information

Returns
0 on success, non-zero on failure.

int fcb_append_finish(struct fcb *fcb, struct fcb_entry *append_loc)
Finishes entry append operation.

Parameters
• fcb – [in] FCB instance structure.
• append_loc – [in] entry location information

Returns
0 on success, non-zero on failure.

int fcb_walk(struct fcb *fcb, struct flash_sector *sector, *fcb_walk_cb cb, void *cb_arg)
Walk over all entries in the FCB sector.

Parameters
• sector – [in] Fcb sector to be walked. If null, traverse entire storage.
• fcb – [in] FCB instance structure.
• cb – [in] pointer to the function which gets called for every entry. If cb
wants to stop the walk, it should return non-zero value.
• cb_arg – [inout] callback context, transferred to the callback implementa-
tion.
Returns
0 on success, negative on failure (or transferred form callback return-value, positive transferred form callback return-value)

```c
int fcb_getnext(struct fcb *fcb, struct fcb_entry *loc)
```

Get next fcb entry location.

Function to obtain fcb entry location in relation to entry pointed by loc. If loc->fe_sector is set and loc->fe_elem_off is not 0 function fetches next fcb entry location. If loc->fe_sector is NULL function fetches the oldest entry location within FCB storage. loc->fe_sector is set and loc->fe_elem_off is 0 function fetches the first entry location in the fcb sector.

Parameters
- loc – [inout] entry location information

Returns
0 on success, non-zero on failure.

```c
int fcb_rotate(struct fcb *fcb)
```

Rotate fcb sectors.

Function erases the data from oldest sector. Upon that the next sector becomes the oldest. Active sector is also switched if needed.

Parameters

```c
int fcb_append_to_scratch(struct fcb *fcb)
```

Start using the scratch block.

Take one of the scratch blocks into use. So a scratch sector becomes active sector to which entries can be appended.

Parameters

Returns
0 on success, non-zero on failure.

```c
int fcb_free_sector_cnt(struct fcb *fcb)
```

Get free sector count.

Parameters

Returns
Number of free sectors.

```c
int fcb_is_empty(struct fcb *fcb)
```

Check whether FCB has any data.

Parameters

Returns
Positive value if fcb is empty, otherwise 0.
int fcb_offset_last_n(struct fcb *fcb, uint8_t entries, struct fcb_entry *last_n_entry)
Finds the fcb entry that gives back up to n entries at the end.

Parameters
- entries – [in] number of fcb entries the user wants to get
- last_n_entry – [out] last_n_entry the fcb_entry to be returned

Returns
0 on there are any fcbs available; -ENOENT otherwise

int fcb_clear(struct fcb *fcb)
Clear fcb instance storage.

Parameters

Returns
0 on success; non-zero on failure

4.25.5 Stream Flash

The Stream Flash module takes contiguous fragments of a stream of data (e.g. from radio packets), aggregates them into a user-provided buffer, then when the buffer fills (or stream ends) writes it to a raw flash partition. It supports providing the read-back buffer to the client to use in validating the persisted stream content.

One typical use of a stream write operation is when receiving a new firmware image to be used in a DFU operation.

There are several reasons why one might want to use buffered writes instead of writing the data directly as it is made available. Some devices have hardware limitations which does not allow flash writes to be performed in parallel with other operations, such as radio RX and TX. Also, fewer write operations result in faster response times seen from the application.

Persistent stream write progress

Some stream write operations, such as DFU operations, may run for a long time. When performing such long running operations it can be useful to be able to save the stream write progress to persistent storage so that the operation can resume at the same point after an unexpected interruption.

The Stream Flash module offers an API for loading, saving and clearing stream write progress to persistent storage using the Settings module. The API can be enabled using CONFIG_STREAM_FLASH_PROGRESS.

API Reference

group stream_flash
Abstraction over stream writes to flash.
Typedefs

typedef int (*stream_flash_callback_t)(uint8_t *buf, size_t len, size_t offset)

Signature for callback invoked after flash write completes.

Functions of this type are invoked with a buffer containing data read back from the flash after a flash write has completed. This enables verifying that the data has been correctly stored (for instance by using a SHA function). The write buffer ‘buf’ provided in stream_flash_init is used as a read buffer for this purpose.

**Param buf**
- Pointer to the data read.

**Param len**
- The length of the data read.

**Param offset**
- The offset the data was read from.

Functions

```c
int stream_flash_init(struct stream_flash_ctx *ctx, const struct device *fdev, uint8_t *buf,
size_t buf_len, size_t offset, size_t size,
stream_flash_callback_t cb)
```

Initialize context needed for stream writes to flash.

**Parameters**
- **ctx** – context to be initialized
- **fdev** – Flash device to operate on
- **buf** – Write buffer
- **buf_len** – Length of write buffer. Can not be larger than the page size. Must be multiple of the flash device write-block-size.
- **offset** – Offset within flash device to start writing to
- **size** – Number of bytes available for performing buffered write. If this is ‘0’, the size will be set to the total size of the flash device minus the offset.
- **cb** – Callback to be invoked on completed flash write operations.

**Returns**
- non-negative on success, negative errno code on fail

```c
size_t stream_flash_bytes_written(struct stream_flash_ctx *ctx)
```

Read number of bytes written to the flash.

**Note:** api-tags: pre-kernel-ok isr-ok

**Parameters**
- **ctx** – context

**Returns**
- Number of payload bytes written to flash.
Zephyr Project Documentation, Release 3.6.0-rc3

int stream_flash_buffered_write(struct stream_flash_ctx *ctx, const uint8_t *data, size_t len, bool flush)

Process input buffers to be written to flash device in single blocks.
Will store remainder between calls.
A final call to this function with flush set to true will write out the remaining block buffer to flash.

Parameters
• ctx – context
• data – data to write
• len – Number of bytes to write
• flush – when true this forces any buffered data to be written to flash
A flush write should be the last write operation in a sequence of write operations for given context (although this is not mandatory if the total data size is a multiple of the buffer size).

Returns
non-negative on success, negative errno code on fail

int stream_flash_erase_page(struct stream_flash_ctx *ctx, off_t off)

Erase the flash page to which a given offset belongs.
This function erases a flash page to which an offset belongs if this page is not the page previously erased by the provided ctx (ctx->last_erased_page_start_offset).

Parameters
• ctx – context
• off – offset from the base address of the flash device

Returns
non-negative on success, negative errno code on fail

int stream_flash_progress_load(struct stream_flash_ctx *ctx, const char *settings_key)

Load persistent stream write progress stored with key settings_key.
This function should be called directly after stream_flash_init to load previous stream write progress before writing any data. If the loaded progress has fewer bytes written than ctx then it will be ignored.

Parameters
• ctx – context
• settings_key – key to use with the settings module for loading the stream write progress

Returns
non-negative on success, negative errno code on fail

int stream_flash_progress_save(struct stream_flash_ctx *ctx, const char *settings_key)

Save persistent stream write progress using key settings_key.

Parameters
• ctx – context
• settings_key – key to use with the settings module for storing the stream write progress

Returns
non-negative on success, negative errno code on fail

4.25. Storage

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int stream_flash_progress_clear(struct stream_flash_ctx *ctx, const char *settings_key)

Clear persistent stream write progress stored with key settings_key.

**Parameters**
- ctx – context
- settings_key – key previously used for storing the stream write progress

**Returns**
non-negative on success, negative errno code on fail

```c
struct stream_flash_ctx
```

*include <stream_flash.h>*

Structure for stream flash context.

Users should treat these structures as opaque values and only interact with them through the below API.

### 4.26 Sensing Subsystem

- **Overview**
- **Configurability**
- **Main Features**
- **Major Flows**
- **Sensor Types And Instance**
- **Sensor Instance Handler**
- **Sensor Sample Value**
- **Device Tree Configuration**
- **API Reference**

#### 4.26.1 Overview

Sensing Subsystem is a high level sensor framework inside the OS user space service layer. It is a framework focused on sensor fusion, client arbitration, sampling, timing, scheduling and sensor based power management.

Key concepts in Sensing Subsystem include physical sensor and virtual sensor objects, and a scheduling framework over sensor object relationships. Physical sensors do not depend on any other sensor objects for input, and will directly interact with existing zephyr sensor device drivers. Virtual sensors rely on other sensor objects (physical or virtual) as report inputs.

The sensing subsystem relies on Zephyr sensor device APIs (existing version or update in future) to leverage Zephyr's large library of sensor device drivers (100+).

Use of the sensing subsystem is optional. Applications that only need to access simple sensors devices can use the Zephyr Sensors API directly.

Since the sensing subsystem is separated from device driver layer or kernel space and could support various customizations and sensor algorithms in user space with virtual sensor concepts. The existing sensor device driver can focus on low layer device side works, can keep simple as much as possible, just provide device HW abstraction and operations etc. This is very good for system stability.
The sensing subsystem is decoupled with any sensor expose/transfer protocols, the target is to support various up-layer frameworks and Applications with different sensor expose/transfer protocols, such as CHRE, HID sensors Applications, MQTT sensor Applications according different products requirements. Or even support multiple Applications with different up-layer sensor protocols at the same time with it's multiple clients support design.

Sensing subsystem can help build a unified Zephyr sensing architecture for cross host OSes support and as well as IoT sensor solutions.

The diagram below illustrates how the Sensing Subsystem integrates with up-layer frameworks.

### 4.26.2 Configurability

- Reusable and configurable standalone subsystem.
- Based on Zephyr existing low-level Sensor API (reuse 100+ existing sensor device drivers)
- Provide Zephyr high-level Sensing Subsystem API for Applications.
- Separate option CHRE Sensor PAL Implementation module to support CHRE.
- Decoupled with any host link protocols, it's Zephyr Application's role to handle different protocols (MQTT, HID or Private, all configurable)

### 4.26.3 Main Features

- **Scope**
  - Focus on framework for sensor fusion, multiple clients, arbitration, data sampling, timing management and scheduling.
- **Sensor Abstraction**
  - Physical sensor: interacts with Zephyr sensor device drivers, focus on data collecting.
  - Virtual sensor: relies on other sensor(s), physical or virtual, focus on data fusion.
- **Data Driven Model**
  - Polling mode: periodical sampling rate
– Interrupt mode: data ready, threshold interrupt etc.

• Scheduling
  – single thread main loop for all sensor objects sampling and process.
  • Buffer Mode for Batching
  • Configurable Via Device Tree

Below diagram shows the API position and scope:

Sensing Subsystem API is for Applications. Sensing Sensor API is for development sensors.

4.26.4 Major Flows

• Sensor Configuration Flow
4.26.5 Sensor Types And Instance

The Sensing Subsystem supports multiple instances of the same sensor type, there're two methods for Applications to identify and open an unique sensor instance:

- Enumerate all sensor instances

  `sensing_get_sensors()` returns all current board configuration supported sensor instances' information in a `sensing_sensor_info` pointer array.

Then Applications can use `sensing_open_sensor()` to open specific sensor instance for future accessing, configuration and receive sensor data etc.
This method is suitable for supporting some up-layer frameworks like CHRE, HID which need to dynamically enumerate the underlying platform's sensor instances.

- Open the sensor instance by devicetree node directly

Applications can use `sensing_open_sensor_by_dt()` to open a sensor instance directly with sensor devicetree node identifier.

For example:

```c
sensing_open_sensor_by_dt(DEVICE_DT_GET(DT_NODELABEL(base_accel)), cb_list, handle);
sensing_open_sensor_by_dt(DEVICE_DT_GET(DT_CHOSEN(zephyr_sensing_base_accel)), cb_list, handle);
```

This method is useful and easy use for some simple Application which just want to access specific sensor(s).

Sensor type follows the HID standard sensor types definition.

See `include/zephyr/sensing/sensing_sensor_types.h`

### 4.26.6 Sensor Instance Handler

Clients using a `sensing_sensor_handle_t` type handler to handle a opened sensor instance, and all subsequent operations on this sensor instance need use this handler, such as set configurations, read sensor sample data, etc.

For a sensor instance, could have two kinds of clients: Application clients and Sensor clients. Application clients can use `sensing_open_sensor()` to open a sensor instance and get it's handler.

For Sensor clients, there is no open API for opening a reporter, because the client-report relationship is built at the sensor's registration stage with devicetree.

The Sensing Subsystem will auto open and create handlers for client sensor to it's reporter sensors. Sensor clients can get it's reporters' handlers via `sensing_sensor_get_reporters()`.
Note: Sensors inside the Sensing Subsystem, the reporting relationship between them are all auto generated by Sensing Subsystem according devicetree definitions, handlers between client sensor and reporter sensors are auto created. Application(s) need to call `sensing_open_sensor()` to explicitly open the sensor instance.

4.26.7 Sensor Sample Value

- Data Structure
  Each sensor sample value defines as a common header + readings[] data structure, like `sensing_sensor_value_3d_q31`, `sensing_sensor_value_q31`, and `sensing_sensor_value_uint32`.
  The header definition `sensing_sensor_value_header()`.

- Time Stamp
  Time stamp unit in sensing subsystem is micro seconds.
  The header defines a `base_timestamp`, and each element in the `readings[]` array defines `timestamp_delta`.
  The `timestamp_delta` is in relation to the previous `readings` (or the `base_timestamp`).
  For example:
  - timestamp of `readings[0]` is `header.base_timestamp + readings[0].timestamp_delta`.
  - timestamp of `readings[1]` is `timestamp of readings[0] + readings[1].timestamp_delta`.
  Since timestamp unit is micro seconds, the max `timestamp_delta` (`uint32_t`) is 4295 seconds.
  If a sensor has batched data where two consecutive readings differ by more than 4295 seconds, the sensing subsystem runtime will split them across multiple instances of the readings structure, and send multiple events.
  This concept is referred from CHRE Sensor API.

- Data Format
  Sensing Subsystem uses per sensor type defined data format structure, and support Q Format defined in `include/zephyr/dsp/types.h` for zdsp lib support.
  For example `sensing_sensor_value_3d_q31` can be used by 3D IMU sensors like `SENSING_SENSOR_TYPE_MOTION_ACCELEROMETER_3D`, `SENSING_SENSOR_TYPE_MOTION_UNCALIB_ACCELEROMETER_3D`, and `SENSING_SENSOR_TYPE_MOTION_GYROMETER_3D`.
  `sensing_sensor_value_uint32` can be used by `SENSING_SENSOR_TYPE_LIGHT_AMBIENTLIGHT` sensor;
  and `sensing_sensor_value_q31` can be used by `SENSING_SENSOR_TYPE_MOTION_HINGE_ANGLE` sensor.
  See `include/zephyr/sensing/sensing_datatypes.h`

4.26.8 Device Tree Configuration

Sensing subsystem using device tree to configuration all sensor instances and their properties, reporting relationships.
API Reference

Sensor Types Definition.

Sensor types definition followed HID standard. [https://usb.org/sites/default/files/hutrr39b_0.pdf](https://usb.org/sites/default/files/hutrr39b_0.pdf)

TODO: will add more types

**Defines**

- `SENSING_SENSOR_TYPE_LIGHT_AMBIENTLIGHT` sensor category light
- `SENSING_SENSOR_TYPE_MOTION_ACCELEROMETER_3D` sensor category motion
- `SENSING_SENSOR_TYPE_MOTION_GYROMETER_3D`
- `SENSING_SENSOR_TYPE_MOTION_MOTION_DETECTOR`
- `SENSING_SENSOR_TYPE_OTHER_CUSTOM` sensor category other
- `SENSING_SENSOR_TYPE_MOTION_UNCALIB_ACCELEROMETER_3D`
- `SENSING_SENSOR_TYPE_MOTION_HINGE_ANGLE`
- `SENSING_SENSOR_TYPE_ALL`

**Group sensing_datatypes**

Data Types.

```c
struct sensing_sensor_value_header
#include <sensing_datatypes.h> sensor value header
```

Each sensor value data structure should have this header

Here use ‘base_timestamp’ (uint64_t) and ‘timestamp_delta’ (uint32_t) to save memory usage in batching mode.

The ‘base_timestamp’ is for readings[0], the ‘timestamp_delta’ is relation to the previous ‘readings’. So, timestamp of readings[0] is header.base_timestamp + readings[0].timestamp_delta. timestamp of readings[1] is timestamp of readings[0] + readings[1].timestamp_delta.

Since timestamp unit is micro seconds, the max ‘timestamp_delta’ (uint32_t) is 4295 seconds.
If a sensor has batched data where two consecutive readings differ by more than 4295 seconds, the sensor subsystem core will split them across multiple instances of the readings structure, and send multiple events.

This concept is borrowed from CHRE: https://cs.android.com/android/platform/superproject/+/master: system/chre/chre_api/include/chre_api/chre/sensor_types.h

Public Members

uint64_t base_timestamp
   base timestamp of this data readings, unit is micro seconds

uint16_t reading_count
   count of this data readings

struct sensing_sensor_value_3d_q31
   #include <sensing_datatypes.h> Sensor value data structure types based on common data types.
   Suitable for common sensors, such as IMU, Light sensors and orientation sensors.
   Sensor value data structure for 3-axis sensors. struct sensing_sensor_value_3d_q31 can be used by 3D IMU sensors like:
   SENSING_SENSOR_TYPE_MOTION_ACCELEROMETER_3D, SENSING_SENSOR_TYPE_MOTION_UNCALIB_ACCELEROMETER_3D, SENSING_SENSOR_TYPE_MOTION_GYROMETER_3D, q31 version

struct sensing_sensor_value_uint32
   #include <sensing_datatypes.h> Sensor value data structure for single 1-axis value.
   struct sensing_sensor_value_uint32 can be used by SENSING_SENSOR_TYPE_LIGHT_AMBIENTLIGHT sensor uint32_t version

struct sensing_sensor_value_q31
   #include <sensing_datatypes.h> Sensor value data structure for single 1-axis value.
   struct sensing_sensor_value_q31 can be used by SENSING_SENSOR_TYPE_MOTION_HINGE_ANGLE sensor q31 version

Related code samples

Sensing subsystem
   Get high-level sensor data in defined intervals.

   group sensing_api
   Sensing Subsystem API.

   Defines

   SENSING_SENSOR_VERSION(_major, _minor, _hotfix, _build)
SENSING_SENSOR_FLAG_REPORT_ON_EVENT
Sensor flag indicating if this sensor is on event reporting data.
Reporting sensor data when the sensor event occurs, such as a motion detect sensor reporting a motion or motionless detected event.

SENSING_SENSOR_FLAG_REPORT_ON_CHANGE
Sensor flag indicating if this sensor is on change reporting data.
Reporting sensor data when the sensor data changes.
Exclusive with SENSING_SENSOR_FLAG_REPORT_ON_EVENT

SENSING_SENSITIVITY_INDEX_ALL
SENSING_SENSITIVITY_INDEX_ALL indicating sensitivity of each data field should be set.

Typedefs

typedef void *sensing_sensor_handle_t
Define Sensing subsystem sensor handle.

typedef void (*sensing_data_event_t)(sensing_sensor_handle_t handle, const void *buf, void *context)
Sensor data event receive callback.
    Param handle
    The sensor instance handle.
    Param buf
    The data buffer with sensor data.

 Enums

eenum sensing_sensor_state
Sensing subsystem sensor state.
Values:
    enumerator SENSING_SENSOR_STATE_READY = 0
    enumerator SENSING_SENSOR_STATE_OFFLINE = 1

eenum sensing_sensor_attribute
Sensing subsystem sensor config attribute.
Values:
    enumerator SENSING_SENSOR_ATTRIBUTE_INTERVAL = 0
    enumerator SENSING_SENSOR_ATTRIBUTE_SENSITIVITY = 1
enumerator SENSING_SENSOR_ATTRIBUTE_LATENCY = 2

enumerator SENSING_SENSOR_ATTRIBUTE_MAX

**Functions**

```c
int sensing_get_sensors(int *num_sensors, const struct sensing_sensor_info **info)
```

Get all supported sensor instances' information.

This API just returns read only information of sensor instances, pointer info will directly point to internal buffer, no need for caller to allocate buffer, no side effect to sensor instances.

**Parameters**

- `num_sensors` – Get number of sensor instances.
- `info` – For receiving sensor instances' information array pointer.

**Returns**

0 on success or negative error value on failure.

```c
int sensing_open_sensor(const struct sensing_sensor_info *info, struct sensing_callback_list *cb_list, sensing_sensor_handle_t *handle)
```

Open sensor instance by sensing sensor info.

Application clients use it to open a sensor instance and get its handle. Support multiple Application clients for open same sensor instance, in this case, the returned handle will different for different clients. meanwhile, also register sensing callback list

**Parameters**

- `info` – The sensor info got from `sensing_get_sensors`
- `cb_list` – callback list to be registered to sensing, must have a static lifetime.
- `handle` – The opened instance handle, if failed will be set to NULL.

**Returns**

0 on success or negative error value on failure.

```c
int sensing_open_sensor_by_dt(const struct device *dev, struct sensing_callback_list *cb_list, sensing_sensor_handle_t *handle)
```

Open sensor instance by device.

Application clients use it to open a sensor instance and get its handle. Support multiple Application clients for open same sensor instance, in this case, the returned handle will different for different clients. meanwhile, also register sensing callback list.

**Parameters**

- `dev` – pointer device get from device tree.
- `cb_list` – callback list to be registered to sensing, must have a static lifetime.
- `handle` – The opened instance handle, if failed will be set to NULL.

**Returns**

0 on success or negative error value on failure.
int sensing_close_sensor(sensing_sensor_handle_t *handle)

Close sensor instance.

Parameters

• handle – The sensor instance handle need to close.

Returns

0 on success or negative error value on failure.

int sensing_set_config(sensing_sensor_handle_t handle, struct sensing_sensor_config *configs, int count)

Set current config items to Sensing subsystem.

Parameters

• handle – The sensor instance handle.

• configs – The configs to be set according to config attribute.

• count – count of configs.

Returns

0 on success or negative error value on failure, not support etc.

int sensing_get_config(sensing_sensor_handle_t handle, struct sensing_sensor_config *configs, int count)

Get current config items from Sensing subsystem.

Parameters

• handle – The sensor instance handle.

• configs – The configs to be get according to config attribute.

• count – count of configs.

Returns

0 on success or negative error value on failure, not support etc.

const struct sensing_sensor_info *sensing_get_sensor_info(sensing_sensor_handle_t handle)

Get sensor information from sensor instance handle.

Parameters

• handle – The sensor instance handle.

Returns

a const pointer to sensing_sensor_info on success or NULL on failure.

struct sensing_sensor_version

#include <sensing.h> Sensor Version.

struct sensing_sensor_info

#include <sensing.h> Sensor basic constant information.

Public Members

const char *name

Name of the sensor instance.
const char *friendly_name
    Friendly name of the sensor instance.

const char *vendor
    Vendor name of the sensor instance.

const char *model
    Model name of the sensor instance.

const int32_t type
    Sensor type.

const uint32_t minimal_interval
    Minimal report interval in micro seconds.

struct sensing_callback_list
    #include <sensing.h> Sensing subsystem event callback list.

struct sensing_sensor_config
    #include <sensing.h> Sensing subsystem sensor configure, including interval, sensitivity, latency.

Public Members

int8_t data_field
    SENSING_SENSITIVITY_INDEX_ALL

group sensing_sensor
    Sensing Sensor API.

Defines

SENSING_SENSOR_INFO_NAME(node, idx)
SENSING_SENSOR_INFO_DEFINE(node, idx)
SENSING_CONNECTIONS_NAME(node)
SENSING_SENSOR_SOURCE_NAME(idx, node)
SENSING_SENSOR_SOURCE_EXTERN(idx, node)
SENSING_CONNECTION_INITIALIZER(source_name, cb_list_ptr)
SENSING_CONNECTION_DEFINE(idx, node, cb_list_ptr)
SENSING_CONNECTIONS_DEFINE(node, num, cb_list_ptr)
SENSING_SUBMIT_CFG_NAME(node, idx)
SENSING_SENSOR_IODEV_NAME(node, idx)
**SENSING_SENSOR_IODEV_DEFINE**(node, idx)

**SENSINGSENSOR_NAME**(node, idx)

**SENSING_SENSOR_DEFINE**(node, prop, idx, reg_ptr, cb_list_ptr)

**SENSING_SENSORS_DEFINE**(node, prop, idx, reg_ptr, cb_list_ptr)

**SENSING_SENSORS_DT_DEFINE**(node, prop, idx, reg_ptr, cb_list_ptr, init_fn, pm_device, data_ptr, cfg_ptr, level, prio, api_ptr, ...)

Like **SENSOR_DEVICE_DT_DEFINE()** with sensing specifics.

Defines a sensor which implements the sensor API. May define an element in the sensing sensor iterable section used to enumerate all sensing sensors.

**Parameters**

- **node** – The devicetree node identifier.
- **reg_ptr** – Pointer to the device's *sensing_sensor_register_info*.
- **cb_list_ptr** – Pointer to devices callback list.
- **init_fn** – Name of the init function of the driver.
- **pm_device** – PM device resources reference (NULL if device does not use PM).
- **data_ptr** – Pointer to the device's private data.
- **cfg_ptr** – The address to the structure containing the configuration information for this instance of the driver.
- **level** – The initialization level. See SYS_INIT() for details.
- **prio** – Priority within the selected initialization level. See SYS_INIT() for details.
- **api_ptr** – Provides an initial pointer to the API function struct used by the driver. Can be NULL.

**SENSING_SENSORS_DT_INST_DEFINE**(inst, ...)

Like **SENSING_SENSORS_DT_DEFINE()** for an instance of a DT_DRV_COMPAT compatible.

**Parameters**

- **inst** – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to **SENSING_SENSORS_DT_DEFINE()**.
- **...** – other parameters as expected by **SENSING_SENSORS_DT_DEFINE()**.

** Enums **

**Values:**

enumerator **EVENT_CONFIG_READY**

**Values:**

enumerator **SENSOR_LATER_CFG_BIT**
Functions

int sensing_sensor_get_reporters(const struct device *dev, int type, sensing_sensor_handle_t *reporter_handles, int max_handles)

Get reporter handles of a given sensor instance by sensor type.

Parameters
- **dev** – The sensor instance device structure.
- **type** – The given type, SENSING_SENSOR_TYPE_ALL to get reporters with all types.
- **max_handles** – The max count of the reporter_handles array input. Can get real count number via sensing_sensor_get_reporters_count
- **reporter_handles** – Input handles array for receiving found reporter sensor instances

Returns
number of reporters found, 0 returned if not found.

int sensing_sensor_get_reporters_count(const struct device *dev, int type)

Get reporters count of a given sensor instance by sensor type.

Parameters
- **dev** – The sensor instance device structure.
- **type** – The sensor type for checking, SENSING_SENSOR_TYPE_ALL

Returns
Count of reporters by type, 0 returned if no reporters by type.

int sensing_sensor_get_state(const struct device *dev, enum sensing_sensor_state *state)

Get this sensor's state.

Parameters
- **dev** – The sensor instance device structure.
- **state** – Returned sensor state value

Returns
0 on success or negative error value on failure.

struct sensing_sensor_register_info
#include <sensing_sensor.h> Sensor registration information.

Public Members

uint16_t flags
Sensor flags.

uint16_t sample_size
Sample size in bytes for a single sample of the registered sensor.
 sensing runtime need this information for internal buffer allocation.
uint8_t sensitivity_count
    The number of sensor sensitivities.

struct sensing_sensor_version version
    Sensor version.

    Version can be used to identify different versions of sensor implementation.

struct sensing_connection
    #include <sensing_sensor.h> Connection between a source and sink of sensor data.

struct sensing_sensor
    #include <sensing_sensor.h> Internal sensor instance data structure.

    Each sensor instance will have its unique data structure for storing all its related information.

    Sensor management will enumerate all these instance data structures, build report relationship model base on them, etc.

struct sensing_submit_config
    #include <sensing_sensor.h>

# 4.27 Task Watchdog

## 4.27.1 Overview

Many microcontrollers feature a hardware watchdog timer peripheral. Its purpose is to trigger an action (usually a system reset) in case of severe software malfunctions. Once initialized, the watchdog timer has to be restarted (“fed”) in regular intervals to prevent it from timing out. If the software got stuck and does not manage to feed the watchdog anymore, the corrective action is triggered to bring the system back to normal operation.

In real-time operating systems with multiple tasks running in parallel, a single watchdog instance may not be sufficient anymore, as it can be used for only one task. This software watchdog based on kernel timers provides a method to supervise multiple threads or tasks (called watchdog channels).

An existing hardware watchdog can be used as an optional fallback if the task watchdog itself or the scheduler has a malfunction.

The task watchdog uses a kernel timer as its backend. If configured properly, the timer ISR is never actually called during normal operation, as the timer is continuously updated in the feed calls.

It's currently not possible to have multiple instances of task watchdogs. Instead, the task watchdog API can be accessed globally to add or delete new channels without passing around a context or device pointer in the firmware.

The maximum number of channels is predefined via Kconfig and should be adjusted to match exactly the number of channels required by the application.

## 4.27.2 Configuration Options

Related configuration options can be found under subsys/task_wdt/Kconfig.
• \texttt{CONFIG\_TASK\_WDT}
• \texttt{CONFIG\_TASK\_WDT\_CHANNELS}
• \texttt{CONFIG\_TASK\_WDT\_HW\_FALLBACK}
• \texttt{CONFIG\_TASK\_WDT\_MIN\_TIMEOUT}
• \texttt{CONFIG\_TASK\_WDT\_HW\_FALLBACK\_DELAY}

\subsection{API Reference}

\subsubsection{Related code samples}

\textbf{Task watchdog}

Monitor a thread using a task watchdog.

\begin{verbatim}
\textit{group task_wdt_api}

Task Watchdog APIs.

\textbf{Typedefs}

typedef void (*\texttt{task_wdt_callback_t})(int channel_id, void *user_data)

Task watchdog callback.

\textbf{Functions}

\texttt{int task_wdt_init}\,(const \textit{struct device} *hw_wdt)

Initialize task watchdog.

This function sets up necessary kernel timers and the hardware watchdog (if desired as fallback). It has to be called before \texttt{task_wdt_add()} and \texttt{task_wdt_feed()}.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{hw_wdt} – Pointer to the hardware watchdog device used as fallback. Pass NULL if no hardware watchdog fallback is desired.
\end{itemize}

\textbf{Return values}

\begin{itemize}
  \item \texttt{0} – If successful.
  \item \texttt{-ENOTSUP} – If assigning a hardware watchdog is not supported.
  \item \texttt{-Errno} – Negative errno if the fallback \texttt{hw_wdt} is used and the install timeout API fails. See \texttt{wdt_install_timeout()} API for possible return values.
\end{itemize}

\texttt{int task_wdt_add}\,(uint32_t reload_period, \texttt{task_wdt_callback_t} callback, void *user_data)

Install new timeout.

Adds a new timeout to the list of task watchdog channels.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{reload_period} – Period in milliseconds used to reset the timeout
  \item \texttt{callback} – Function to be called when watchdog timer expired. Pass NULL to use system reset handler.
\end{itemize}

\section{4.27. Task Watchdog}
• **user_data** – User data to associate with the watchdog channel.

**Return values**

• **channel_id** – If successful, a non-negative value indicating the index of the channel to which the timeout was assigned. This ID is supposed to be used as the parameter in calls to `task_wdt_feed()`.

• `-EINVAL` – If the reload_period is invalid.

• `-ENOMEM` – If no more timeouts can be installed.

```c
int task_wdt_delete(int channel_id)
Delete task watchdog channel.

Deletes the specified channel from the list of task watchdog channels. The channel is now available again for other tasks via `task_wdt_add()` function.

**Parameters**

• **channel_id** – Index of the channel as returned by `task_wdt_add()`.

**Return values**

• **0** – If successful.

• `-EINVAL` – If there is no installed timeout for supplied channel.

```c
int task_wdt_feed(int channel_id)
Feed specified watchdog channel.

This function loops through all installed task watchdogs and updates the internal kernel timer used as for the software watchdog with the next due timeout.

**Parameters**

• **channel_id** – Index of the fed channel as returned by `task_wdt_add()`.

**Return values**

• **0** – If successful.

• `-EINVAL` – If there is no installed timeout for supplied channel.

## 4.28 Trusted Firmware-M

### 4.28.1 Trusted Firmware-M Overview

**Trusted Firmware-M (TF-M)** is a reference implementation of the Platform Security Architecture (PSA) IoT Security Framework. It defines and implements an architecture and a set of software components that aim to address some of the main security concerns in IoT products.

Zephyr RTOS has been PSA Certified since Zephyr 2.0.0 with TF-M 1.0, and is currently integrated with TF-M 2.0.0.

**What Does TF-M Offer?**

Through a set of secure services and by design, TF-M provides:

• Isolation of secure and non-secure resources

• Embedded-appropriate crypto

• Management of device secrets (keys, etc.)

• Firmware verification (and encryption)
• Protected off-chip data storage and retrieval
• Proof of device identity (device attestation)
• Audit logging

Build System Integration

When using TF-M with a supported platform, TF-M will be automatically built and link in the background as part of the standard Zephyr build process. This build process makes a number of assumptions about how TF-M is being used, and has certain implications about what the Zephyr application image can and cannot do:

• The secure processing environment (secure boot and TF-M) starts first
• Resource allocation for Zephyr relies on choices made in the secure image.

Architecture Overview

A TF-M application will, generally, have the following three parts, from most to least trusted, left-to-right, with code execution happening in the same order (secure boot > secure image > ns image).

While the secure bootloader is optional, it is enabled by default, and secure boot is an important part of providing a secure solution:

Communication between the (Zephyr) Non-Secure Processing Environment (NSPE) and the (TF-M) Secure Processing Environment image happens based on a set of PSA APIs, and normally makes use of an IPC mechanism that is included as part of the TF-M build, and implemented in Zephyr (see modules/trusted-firmware-m/interface).

Root of Trust (RoT) Architecture

TF-M is based upon a Root of Trust (RoT) architecture. This allows for hierarchies of trust from most, to less, to least trusted, providing a sound foundation upon which to build or access trusted services and resources.

The benefit of this approach is that less trusted components are prevented from accessing or compromising more critical parts of the system, and error conditions in less trusted environments won’t corrupt more trusted, isolated resources.

The following RoT hierarchy is defined for TF-M, from most to least trusted:

• PSA Root of Trust (PRoT), which consists of:
  – PSA Immutable Root of Trust: secure boot
  – PSA Updateable Root of Trust: most trusted secure services

• Application Root of Trust (ARoT): isolated secure services
The **PSA Immutable Root of Trust** is the most trusted piece of code in the system, to which subsequent Roots of Trust are anchored. In TF-M, this is the secure boot image, which verifies that the secure and non-secure images are valid, have not been tampered with, and come from a reliable source. The secure bootloader also verifies new images during the firmware update process, thanks to the public signing key(s) built into it. As the name implies, this image is immutable.

The **PSA Updateable Root of Trust** implements the most trusted secure services and components in TF-M, such as the Secure Partition Manager (SPM), and shared secure services like PSA Crypto, Internal Trusted Storage (ITS), etc. Services in the PSA Updateable Root of Trust have access to other resources in the same Root of Trust.

The **Application Root of Trust** is a reduced-privilege area in the secure processing environment which, depending on the isolation level chosen when building TF-M, has limited access to the PRoT, or even other ARoT services at the highest isolation levels. Some standard services exist in the ARoT, such as Protected Storage (PS), and generally custom secure services that you implement should be placed in the ARoT, unless a compelling reason is present to place them in the PRoT.

These divisions are distinct from the **untrusted code**, which runs in the non-secure environment, and has the least privilege in the system. This is the Zephyr application image in this case.

**Isolation Levels** At present, there are three distinct isolation levels defined in TF-M, with increasingly rigid boundaries between regions. The isolation level used will depend on your security requirements, and the system resources available to you.

- **Isolation Level 1** is the lowest isolation level, and the only major boundary is between the secure and non-secure processing environment, usually by means of Arm TrustZone on Armv8-M processors. There is no distinction here between the PSA Updateable Root of Trust (PRoT) and the Application Root of Trust (ARoT). They execute at the same privilege level. This isolation level will lead to the smallest combined application images.

- **Isolation Level 2** builds upon level one by introducing a distinction between the PSA Updateable Root of Trust and the Application Root of Trust, where ARoT services have limited access to PRoT services, and can only communicate with them through public APIs exposed by the PRoT services. ARoT services, however, are not strictly isolated from one another.

- **Isolation Level 3** is the highest isolation level, and builds upon level 2 by isolating ARoT services from each other, so that each ARoT is essentially silo’ed from other services. This provides the highest level of isolation, but also comes at the cost of additional overhead and code duplication between services.

The current isolation level can be checked via `CONFIG_TFM_ISOLATION_LEVEL`.

**Secure Boot** The default secure bootloader in TF-M is based on MCUBoot, and is referred to as BL2 in TF-M (for the second-stage bootloader, potentially after a HW-based bootloader on the secure MCU, etc.).

All images in TF-M are hashed and signed, with the hash and signature verified by MCUBoot during the firmware update process.

Some key features of MCUBoot as used in TF-M are:

- Public signing key(s) are baked into the bootloader
- S and NS images can be signed using different keys
- Firmware images can optionally be encrypted
- Client software is responsible for writing a new image to the secondary slot
- By default, uses static flash layout of two identically-sized memory regions
- Optional security counter for rollback protection

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When dealing with (optionally) encrypted images:

- Only the payload is encrypted (header, TLVs are plain text)
- Hashing and signing are applied over the un-encrypted data
- Uses AES-CTR-128 or AES-CTR-256 for encryption
- Encryption key randomized every encryption cycle (via `imgtool`)
- The AES-CTR key is included in the image and can be encrypted using:
  - RSA-OAEP
  - AES-KW (128 or 256 bits depending on the AES-CTR key length)
  - ECIES-P256
  - ECIES-X25519

Key config properties to control secure boot in Zephyr are:

- `CONFIG_TFM_BL2` toggles the bootloader (default = y).
- `CONFIG_TFM_KEY_FILE_S` overrides the secure signing key.
- `CONFIG_TFM_KEY_FILE_NS` overrides the non-secure signing key.

**Secure Processing Environment**  Once the secure bootloader has finished executing, a TF-M based secure image will begin execution in the secure processing environment. This is where our device will be initially configured, and any secure services will be initialised.

Note that the starting state of our device is controlled by the secure firmware, meaning that when the non-secure Zephyr application starts, peripherals may not be in the HW-default reset state. In case of doubts, be sure to consult the board support packages in TF-M, available in the platform/ext/target/ folder of the TF-M module (which is in modules/tee/tf-m/trusted-firmware-m/ within a default Zephyr west workspace.)

**Secure Services**  As of TF-M 1.8.0, the following secure services are generally available (although vendor support may vary):

- Crypto
- Firmware Update (FWU)
- Initial Attestation
- Platform
- Secure Storage, which has two parts:
  - Internal Trusted Storage (ITS)
  - Protected Storage (PS)

A template also exists for creating your own custom services.

For full details on these services, and their exposed APIs, please consult the TF-M Documentation.

**Key Management and Derivation**  Key and secret management is a critical part of any secure device. You need to ensure that key material is available to regions that require it, but not to anything else, and that it is stored securely in a way that makes it difficult to tamper with or maliciously access.

The Internal Trusted Storage service in TF-M is used by the PSA Crypto service (which itself makes use of mbedtls) to store keys, and ensure that private keys are only ever accessible to the secure processing environment. Crypto operations that make use of key material, such as when
signing payloads or when decrypting sensitive data, all take place via key handles. At no point should the key material ever be exposed to the NS environment.

One exception is that private keys can be provisioned into the secure processing environment as a one-way operation, such as during a factory provisioning process, but even this should be avoided where possible, and a request should be made to the SPE (via the PSA Crypto service) to generate a new private key itself, and the public key for that can be requested during provisioning and logged in the factory. This ensures the private key material is never exposed, or even known during the provisioning phase.

TF-M also makes extensive use of the Hardware Unique Key (HUK), which every TF-M device must provide. This device-unique key is used by the Protected Storage service, for example, to encrypt information stored in external memory. For example, this ensures that the contents of flash memory can't be decrypted if they are removed and placed on a new device, since each device has its own unique HUK used while encrypting the memory contents the first time.

HUKs provide an additional advantage for developers, in that they can be used to derive new keys, and the derived keys don't need to be stored since they can be regenerated from the HUK at startup, using an additional salt/seed value (depending on the key derivation algorithm used). This removes the storage issue and a frequent attack vector. The HUK itself is usually highly protected in secure devices, and inaccessible directly by users.

TFM_CRYPTO_ALG_HUK_DERIVATION identifies the default key derivation algorithm used if a software implementation is used. The current default algorithm is HKDF (RFC 5869) with a SHA-256 hash. Other hardware implementations may be available on some platforms.

Non-Secure Processing Environment Zephyr is used for the NSPE, using a board that is supported by TF-M where the CONFIG_BUILD_WITH_TFM flag has been enabled.

Generally, you simply need to select the _ns variant of a valid target (for example mps2_an521_ns), which will configure your Zephyr application to run in the NSPE, correctly build and link it with the TF-M secure images, sign the secure and non-secure images, and merge the three binaries into a single tfm_merged.hex file. The west flash command will flash tfm_merged.hex by default in this configuration.

At present, Zephyr can not be configured to be used as the secure processing environment.

4.28.2 TF-M Requirements

The following are some of the boards that can be used with TF-M:

<table>
<thead>
<tr>
<th>Board</th>
<th>NSPE board name</th>
</tr>
</thead>
<tbody>
<tr>
<td>mps2_an521_board</td>
<td>mps2_an521_ns (qemu supported)</td>
</tr>
<tr>
<td>mps3_an547_board</td>
<td>mps3_an547_ns (qemu supported)</td>
</tr>
<tr>
<td>bl5340_dvk</td>
<td>bl5340_dvk_cpuapp_ns</td>
</tr>
<tr>
<td>lpexprss055s69</td>
<td>lpexprss055s69_ns</td>
</tr>
<tr>
<td>nrf9160dk_nrf9160</td>
<td>nrf9160dk_nrf9160_ns</td>
</tr>
<tr>
<td>nrf5340dk_nrf5340</td>
<td>nrf5340dk_nrf5340_cpuapp_ns</td>
</tr>
<tr>
<td>b_u585i_iot02a_board</td>
<td>b_u585i_iot02a_ns</td>
</tr>
<tr>
<td>nucleo_l552ze_q_board</td>
<td>nucleo_l552ze_q_ns</td>
</tr>
<tr>
<td>stm32l562e_dk_board</td>
<td>stm32l562e_dk_ns</td>
</tr>
<tr>
<td>v2m_musca_b1_board</td>
<td>v2m_musca_b1_ns</td>
</tr>
<tr>
<td>v2m_musca_s1_board</td>
<td>v2m_musca_s1_ns</td>
</tr>
</tbody>
</table>

You can run west boards -n _ns$ to search for non-secure variants of different board targets. To make sure TF-M is supported for a board in its output, check that CONFIG_TRUSTED_EXECUTION_NONSECURE is set to y in that board’s default configuration.
Software Requirements

The following Python modules are required when building TF-M binaries:

- cryptography
- pyasn1
- pyyaml
- cbor>=1.0.0
- imgtool>=1.9.0
- jinja2
- click

You can install them via:

```
$ pip3 install --user cryptography pyasn1 pyyaml cbor>=1.0.0 imgtool>=1.9.0
   ... jinja2 click
```

They are used by TF-M's signing utility to prepare firmware images for validation by the bootloader.

Part of the process of generating binaries for QEMU and merging signed secure and non-secure binaries on certain platforms also requires the use of the `srec_cat` utility.

This can be installed on Linux via:

```
$ sudo apt-get install srec
```

And on OS X via:

```
$ brew install srec
```

For Windows-based systems, please make sure you have a copy of the utility available on your system path. See, for example: SRecord for Windows

4.28.3 TF-M Build System

When building a valid `_ns` board target, TF-M will be built in the background, and linked with the Zephyr non-secure application. No knowledge of TF-M's build system is required in most cases, and the following will build a TF-M and Zephyr image pair, and run it in qemu with no additional steps required:

```
$ west build -p auto -b mps2_an521_ns samples/tfm_integration/psa_protected_
   ...storage/ -t run
```

The outputs and certain key steps in this build process are described here, however, since you will need to understand and interact with the outputs, and deal with signing the secure and non-secure images before deploying them.

Images Created by the TF-M Build

The TF-M build system creates the following executable files:

- `tfm_s` - TF-M secure firmware
- `tfm_ns` - TF-M non-secure app (only used by regression tests).
- `bl2` - TF-M MCUboot, if enabled
For each of these, it creates .bin, .hex, .elf, and .axf files.

The TF-M build system also creates signed variants of tfm_s and tfm_ns, and a file which combines them:

- tfm_s_signed
- tfm_ns_signed
- tfm_s_ns_signed

For each of these, only .bin files are created.

The TF-M non-secure app is discarded in favor of Zephyr non-secure app except when running the TF-M regression test suite.

The Zephyr build system usually signs both tfm_s and the Zephyr non-secure app itself. See below for details.

The ‘tfm’ target contains properties for all these paths. For example, the following will resolve to <path>/tfm_s.hex:

```
$<TARGET_PROPERTY:tfm,TFM_S_HEX_FILE>
```

See the top level CMakeLists.txt file in the tfm module for an overview of all the properties.

### Signing Images

When CONFIG_TFM_BL2 is set to y, TF-M uses a secure bootloader (BL2) and firmware images must be signed with a private key. The firmware image is validated by the bootloader during updates using the corresponding public key, which is stored inside the secure bootloader firmware image.

By default, `<tfm-dir>/bl2/ext/mcuboot/root-rsa-3072.pem` is used to sign secure images, and `<tfm-dir>/bl2/ext/mcuboot/root-rsa-3072_1.pem` is used to sign non-secure images. These default .pem keys can (and **should**) be overridden using the CONFIG_TFM_KEY_FILE_S and CONFIG_TFM_KEY_FILE_NS config flags.

To satisfy **PSA Certified Level 1** requirements, **You MUST replace the default .pem file with a new key pair!**

To generate a new public/private key pair, run the following commands:

```
$ imgtool keygen -k root-rsa-3072_s.pem -t rsa-3072
$ imgtool keygen -k root-rsa-3072_ns.pem -t rsa-3072
```

You can then place the new .pem files in an alternate location, such as your Zephyr application folder, and reference them in the `prj.conf` file via the CONFIG_TFM_KEY_FILE_S and CONFIG_TFM_KEY_FILE_NS config flags.

**Warning:** Be sure to keep your private key file in a safe, reliable location! If you lose this key file, you will be unable to sign any future firmware images, and it will no longer be possible to update your devices in the field!

After the built-in signing script has run, it creates a `tfm_merged.hex` file that contains all three binaries: bl2, tfm_s, and the zephyr app. This hex file can then be flashed to your development board or run in QEMU.

**Custom CMake arguments** When building a Zephyr application with TF-M it might be necessary to control the CMake arguments passed to the TF-M build.
Zephyr TF-M build offers several Kconfig options for controlling the build, but doesn’t cover every CMake argument supported by the TF-M build system.

The TFM_CMAKE_OPTIONS property on the zephyr_property_target can be used to pass custom CMake arguments to the TF-M build system.

To pass the CMake argument `-DFOO=bar` to the TF-M build system, place the following CMake snippet in your CMakeLists.txt file.

```
set_property(TARGET zephyr_property_target
  APPEND PROPERTY TFM_CMAKE_OPTIONS
  -DFOO=bar)
```

**Note:** The TFM_CMAKE_OPTIONS is a list so it is possible to append multiple options. Also CMake generator expressions are supported, such as `$<1:-DFOO=bar>`

Since TFM_CMAKE_OPTIONS is a list argument it will be expanded before it is passed to the TF-M build system. Options that have list arguments must therefore be properly escaped to avoid being expanded as a list.

```
set_property(TARGET zephyr_property_target
  APPEND PROPERTY TFM_CMAKE_OPTIONS
  -DFOO="bar\\;baz")
```

**Footprint and Memory Usage**

The build system offers targets to view and analyse RAM and ROM usage in generated images. The tools run on the final images and give information about size of symbols and code being used in both RAM and ROM. For more information on these tools look here: [Footprint and Memory Usage](#)

Use the `tfm_ram_report` to get the RAM report for TF-M secure firmware (tfm_s).

Using west:

```
west build -b mps2_an521_ns samples/hello_world
west build -t tfm_ram_report
```

Using CMake and ninja:

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=mps2_an521_ns samples/hello_world

# Now run the build tool on the generated build system:
ninja -Cbuild tfm_ram_report
```

Use the `tfm_rom_report` to get the ROM report for TF-M secure firmware (tfm_s).

Using west:

```
west build -b mps2_an521_ns samples/hello_world
west build -t tfm_rom_report
```

Using CMake and ninja:

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=mps2_an521_ns samples/hello_world
```

(continues on next page)
Now run the build tool on the generated build system:
```
ninja -Cbuild tfm_rom_report
```

Use the `bl2_ram_report` to get the RAM report for TF-M MCUboot, if enabled.

Using west:
```
west build -b mps2_an521_ns samples/hello_world
west build -t bl2_ram_report
```

Using CMake and ninja:
```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=mps2_an521_ns samples/hello_world
# Now run the build tool on the generated build system:
ninja -Cbuild bl2_ram_report
```

Use the `bl2_rom_report` to get the ROM report for TF-M MCUboot, if enabled.

Using west:
```
west build -b mps2_an521_ns samples/hello_world
west build -t bl2_rom_report
```

Using CMake and ninja:
```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=mps2_an521_ns samples/hello_world
# Now run the build tool on the generated build system:
ninja -Cbuild bl2_rom_report
```

4.28.4 Trusted Firmware-M Integration

The Trusted Firmware-M (TF-M) section contains information about the integration between TF-M and Zephyr RTOS. Use this information to help understand how to integrate TF-M with Zephyr for Cortex-M platforms and make use of its secure run-time services in Zephyr applications.

**Board Definitions**

TF-M will be built for the secure processing environment along with Zephyr if the `CONFIG_BUILD_WITH_TFM` flag is set to `y`.

Generally, this value should never be set at the application level, however, and all config flags required for TF-M should be set in a board variant with the `_ns` suffix.

This board variant must define an appropriate flash, SRAM and peripheral configuration that takes into account the initialisation process in the secure processing environment. `CONFIG_TFM_BOARD` must also be set via `modules/trusted-firmware-m/Kconfig.tfm` to the board name that TF-M expects for this target, so that it knows which target to build for the secure processing environment.

**Example:** `mps2_an521_ns` The `mps2_an521` target is a dual-core Arm Cortex-M33 evaluation board that, when using the default board variant, would generate a secure Zephyr binary.
The optional `mps2_an521_ns` target, however, sets these additional kconfig flags that indicate that Zephyr should be built as a non-secure image, linked with TF-M as an external project, and optionally the secure bootloader:

- `CONFIG_TRUSTED_EXECUTION_NONSECURE y`
- `CONFIG_ARM_TRUSTZONE_M y`

Comparing the `mps2_an521.dts` and `mps2_an521_ns.dts` files, we can see that the _ns_ version defines offsets in flash and SRAM memory, which leave the required space for TF-M and the secure bootloader:

```c
reserved-memory {
    #address-cells = <1>;
    #size-cells = <1>;
    ranges;

    /* The memory regions defined below must match what the TF-M
     * project has defined for that board - a single image boot is
     * assumed. Please see the memory layout in:
     * https://git.trustedfirmware.org/TF-M/trusted-firmware-m.git/tree/platform/
     * _ext/target/mps2/an521/partition/flash_layout.h
     */

    code: memory@100000 {
        reg = <0x00100000 DT_SIZE_K(512)>;
    };

    ram: memory@28100000 {
        reg = <0x28100000 DT_SIZE_M(1)>;
    };
};
```

This reserves 1 MB of code memory and 1 MB of RAM for secure boot and TF-M, such that our non-secure Zephyr application code will start at 0x10000, with RAM at 0x28100000. 512 KB code memory is available for the NS zephyr image, along with 1 MB of RAM.

This matches the flash memory layout we see in `flash_layout.h` in TF-M:

```
* 0x0000_0000 BL2 - MCUBoot (0.5 MB)
* 0x0008_0000 Secure image primary slot (0.5 MB)
* 0x0010_0000 Non-secure image primary slot (0.5 MB)
* 0x0018_0000 Secure image secondary slot (0.5 MB)
* 0x0020_0000 Non-secure image secondary slot (0.5 MB)
* 0x0028_0000 Scratch area (0.5 MB)
* 0x0030_0000 Protected Storage Area (20 KB)
* 0x0030_5000 Internal Trusted Storage Area (16 KB)
* 0x0030_9000 NV counters area (4 KB)
* 0x0030_A000 Unused (984 KB)
```

`mps2/an521` will be passed in to TF-M as the board target, specified via `CONFIG_TFM_BOARD`.

### 4.28.5 Test Suites

TF-M includes two sets of test suites:

- `tf-m-tests` - Standard TF-M specific regression tests
- `psa-arch-tests` - Test suites for specific PSA APIs (secure storage, etc.)

These test suites can be run from Zephyr via an appropriate sample application in the samples/tfm_integration folder.
TF-M Regression Tests

The regression test suite can be run via the tfm_regression_test sample. This sample tests various services and communication mechanisms across the NS/S boundary via the PSA APIs. They provide a useful sanity check for proper integration between the NS RTOS (Zephyr in this case) and the secure application (TF-M).

PSA Arch Tests

The PSA Arch Test suite, available via tfm_psa_test, contains a number of test suites that can be used to validate that PSA API specifications are being followed by the secure application, TF-M being an implementation of the Platform Security Architecture (PSA).

Only one of these suites can be run at a time, with the available test suites described via CONFIG_TFM_PSA_TEST_* KConfig flags:

**Purpose**

The output of these test suites is required to obtain PSA Certification for your specific board, RTOS (Zephyr here), and PSA implementation (TF-M in this case). They also provide a useful test case to validate any PRs that make meaningful changes to TF-M, such as enabling a new TF-M board target, or making changes to the core TF-M module(s). They should generally be run as a coherence check before publishing a new PR for new board support, etc.

### 4.29 Virtualization

#### 4.29.1 Inter-VM Shared Memory

- **Overview**
- **Support**
- **ivshmem-v2**
- **API Reference**

**Overview**

As Zephyr is enabled to run as a guest OS on Qemu and ACRN it might be necessary to make VMs aware of each other, or aware of the host. This is made possible by exposing a shared memory among parties via a feature called ivshmem, which stands for inter-VM Shared Memory.

The two types are supported: a plain shared memory (ivshmem-plain) or a shared memory with the ability for a VM to generate an interruption on another, and thus to be interrupted as well itself (ivshmem-doorbell).

Please refer to the official Qemu ivshmem documentation for more information.
Support

Zephyr supports both versions: plain and doorbell. Ivshmem driver can be built by enabling CONFIG_IVSHMEM. By default, this will expose the plain version. CONFIG_IVSHMEM_DOORBELL needs to be enabled to get the doorbell version.

Because the doorbell version uses MSI-X vectors to support notification vectors, the CONFIG_IVSHMEM_MSI_X_VECTORS has to be tweaked to the number of vectors that will be needed.

Note that a tiny shell module can be exposed to test the ivshmem feature by enabling CONFIG_IVSHMEM_SHELL.

ivshmem-v2

Zephyr also supports ivshmem-v2:


This is primarily used for IPC in the Jailhouse hypervisor (e.g. eth-ivshmem). It is also possible to use ivshmem-v2 without Jailhouse by building the Siemens fork of QEMU, and modifying the QEMU launch flags:

https://github.com/siemens/qemu/tree/wip/ivshmem2

API Reference

Related code samples

IVSHMEM doorbell
Use Inter-VM Shared Memory to exchange messages between two processes running on different operating systems.

Inter-VM Shared Memory (ivshmem) Ethernet
Communicate with another "cell" in the Jailhouse hypervisor using IVSHMEM Ethernet.

\[ group \text{ ivshmem} \]
Inter-VM Shared Memory (ivshmem) reference API.

Defines

IVSHMEM_V2_PROTO_UNDEFINED

IVSHMEM_V2_PROTO_NET

Typedefs

typedef size_t (*ivshmem_get_mem_f)(const struct device *dev, uintptr_t *memmap)

typedef uint32_t (*ivshmem_get_id_f)(const struct device *dev)
typedef uint16_t (*ivshmem_get_vectors_f)(const struct device *dev)

typedef int (*ivshmem_int_peer_f)(const struct device *dev, uint32_t peer_id, uint16_t vector)

typedef int (*ivshmem_register_handler_f)(const struct device *dev, struct k_poll_signal *signal, uint16_t vector)

Functions

size_t ivshmem_get_mem(const struct device *dev, uintptr_t *memmap)
Get the inter-VM shared memory.

Note: This API is not supported for ivshmem-v2, as the R/W and R/O areas may not be mapped contiguously. For ivshmem-v2, use the ivshmem_get_rw_mem_section, ivshmem_get_output_mem_section and ivshmem_get_state APIs to access the shared memory.

Parameters
• dev – Pointer to the device structure for the driver instance
• memmap – A pointer to fill in with the memory address

Returns
the size of the memory mapped, or 0

uint32_t ivshmem_get_id(const struct device *dev)
Get our VM ID.

Parameters
• dev – Pointer to the device structure for the driver instance

Returns
our VM ID or 0 if we are not running on doorbell version

uint16_t ivshmem_get_vectors(const struct device *dev)
Get the number of interrupt vectors we can use.

Parameters
• dev – Pointer to the device structure for the driver instance

Returns
the number of available interrupt vectors

int ivshmem_int_peer(const struct device *dev, uint32_t peer_id, uint16_t vector)
Interrupt another VM.

Parameters
• dev – Pointer to the device structure for the driver instance
• peer_id – The VM ID to interrupt
• vector – The interrupt vector to use

Returns
0 on success, a negative errno otherwise
int ivshmem_register_handler(const struct device *dev, struct k_poll_signal *signal, uint16_t vector)

Register a vector notification (interrupt) handler.

Note: The returned status, if positive, to a raised signal is the vector that generated the signal. This lets the possibility to the user to have one signal for all vectors, or one per-vector.

Parameters
- dev – Pointer to the device structure for the driver instance
- signal – A pointer to a valid and ready to be signaled struct k_poll_signal. Or NULL to unregister any handler registered for the given vector.
- vector – The interrupt vector to get notification from

Returns
0 on success, a negative errno otherwise

struct ivshmem_driver_api
#include <ivshmem.h>

4.30 Retention System

The retention system provides an API which allows applications to read and write data from and to memory areas or devices that retain the data while the device is powered. This allows for sharing information between different applications or within a single application without losing state information when a device reboots. The stored data should not persist in the event of a power failure (or during some low-power modes on some devices) nor should it be stored to a non-volatile storage like Flash, Electrically Erasable Programmable Read-Only Memory (EEPROM), or battery-backed RAM.

The retention system builds on top of the retained data driver, and adds additional software-level features to it for ensuring the validity of data. Optionally, a magic header can be used to check if the front of the retained data memory section contains this specific value, and an optional checksum (1, 2, or 4-bytes in size) of the stored data can be appended to the end of the data. Additionally, the retention system API allows partitioning of the retained data sections into multiple distinct areas. For example, a 64-byte retained data area could be split up into 4 bytes for a boot mode, 16 bytes for a timestamp, 44 bytes for a last log message. All of these sections can be accessed or updated independently. The prefix and checksum can be set per-instance using devicetree.

4.30.1 Devicetree setup

To use the retention system, a retained data driver must be setup for the board you are using, there is a zephyr driver which can be used which will use some RAM as non-init for this purpose. The retention system is then initialised as a child node of this device 1 or more times - note that the memory region will need to be decremented to account for this reserved portion of RAM. See the following example (examples in this guide are based on the nrf52840dk_nrf52840 board and memory layout):

```c
/ {
    sram@0203FC00 {
        compatible = "zephyr,memory-region", "mmio-sram";
        reg = <0x2003FC00 DT_SIZE_K(1)>;
    }
}
```

(continues on next page)
zephyr,memory-region = "RetainedMem";
status = "okay";

retainedmem {
    compatible = "zephyr,retained-ram";
    status = "okay";
    #address-cells = <1>;
    #size-cells = <1>;

    /* This creates a 256-byte partition */
    retention0: retention@0 {
        compatible = "zephyr,retention";
        status = "okay";

        /* The total size of this area is 256
        * bytes which includes the prefix and
        * checksum, this means that the usable
        * data storage area is 256 - 3 = 253
        * bytes
        */
        reg = <0x0 0x100>;

        /* This is the prefix which must appear
        * at the front of the data
        */
        prefix = [08 04];

        /* This uses a 1-byte checksum */
        checksum = <1>;
    }

    /* This creates a 768-byte partition */
    retention1: retention@100 {
        compatible = "zephyr,retention";
        status = "okay";

        /* Start position must be after the end
        * of the previous partition. The total
        * size of this area is 768 bytes which
        * includes the prefix and checksum,
        * this means that the usable data
        * storage area is 768 - 6 = 762 bytes
        */
        reg = <0x100 0x300>;

        /* This is the prefix which must appear
        * at the front of the data
        */
        prefix = [00 11 55 88 fa bc];

        /* If omitted, there will be no
        * checksum
        */

    }
}

/* Reduce SRAM0 usage by 1KB to account for non-init area */
&sram0 {
    reg = <0x20000000 DT_SIZE_K(255)>;
}
The retention areas can then be accessed using the data retention API (once enabled with CONFIG_RETENTION, which requires that CONFIG RETAINED_MEM be enabled) by getting the device by using:

```c
#include <zephyr/device.h>
#include <zephyr/retention/retention.h>
const struct device *retention1 = DEVICE_DT_GET(DT_NODELABEL(retention1));
const struct device *retention2 = DEVICE_DT_GET(DT_NODELABEL(retention2));
```

When the write function is called, the magic header and checksum (if enabled) will be set on the area, and it will be marked as valid from that point onwards.

### 4.30.2 Mutex protection

Mutex protection of retention areas is enabled by default when applications are compiled with multithreading support. This means that different threads can safely call the retention functions without clashing with other concurrent thread function usage, but means that retention functions cannot be used from ISRs. It is possible to disable mutex protection globally on all retention areas by enabling CONFIG_RETENTION_MUTEX_FORCE_DISABLE - users are then responsible for ensuring that the function calls do not conflict with each other. Note that to use this, retention driver mutex support must also be disabled by enabling CONFIG RETAINED_MEM_MUTEX_FORCE_DISABLE.

### 4.30.3 Boot mode

An addition to the retention subsystem is a boot mode interface, this can be used to dynamically change the state of an application or run a different application with a minimal set of functions when a device is rebooted (an example is to have a buttonless way of entering mcuboot's serial recovery feature from the main application).

To use the boot mode feature, a data retention entry must exist in the device tree, which is dedicated for use as the boot mode selection (the user area data size only needs to be a single byte), and this area be assigned to the chosen node of zephyr.boot-mode. See the following example:

```c
/ {
    sram@2003FFFF {
        compatible = "zephyr,retained-ram";
        status = "okay";
    }
    retainedmem {
        compatible = "zephyr,retained-ram";
        status = "okay";
        #address-cells = <1>;
        #size-cells = <1>;
        retention0: retention@0 {
            compatible = "zephyr,retention";
            status = "okay";
            reg = <0x0 0x1>;
        }
    }
};
```
chosen {
    zephyr,boot-mode = &retention0;
};

/* Reduce SRAM0 usage by 1 byte to account for non-init area */
&sram0 {
    reg = <0x20000000 0x3FFFF>;
};

The boot mode interface can be enabled with CONFIG_RETENTION_BOOT_MODE and then accessed by using the boot mode functions. If using mcuboot with serial recovery, it can be built with CONFIG_MCUBOOT_SERIAL and CONFIG_BOOT_SERIAL_BOOT_MODE enabled which will allow rebooting directly into the serial recovery mode by using:

```
#include <zephyr/retention/bootmode.h>
#include <zephyr/sys/reboot.h>

bootmode_set(BOOT_MODE_TYPE_BOOTLOADER);
sys_reboot(0);
```

### 4.30.4 Retention system modules

Modules can expand the functionality of the retention system by using it as a transport (e.g. between a bootloader and application).

**Bootloader Information**

The bootloader information (abbreviated to blinfo) subsystem is an extension of the Retention System which allows for reading shared data from a bootloader and allowing applications to query it. It has an optional feature of organising the information retrieved from the bootloader and storing it in the Settings with the blinfo/ prefix.

**Devicetree setup** To use the bootloader information subsystem, a retention area needs to be created which has a retained data section as its parent, generally non-init RAM is used for this purpose. See the following example (examples in this guide are based on the nrf52840dk_nrf52840 board and memory layout):

```
/ {
    sram@003F000 {
        compatible = "zephyr,memory-region", "mmio-sram";
        reg = <0x2003F000 DT_SIZE_K(1)>;
        zephyr,memory-region = "RetainedMem";
        status = "okay";
    }
    retainedmem {
        compatible = "zephyr,retained-ram";
        status = "okay";
        #address-cells = <1>;
        #size-cells = <1>;
        boot_info0: boot_info@0 {
            compatible = "zephyr,retention";
            status = "okay";
        }
    }
}
```
/* Reduce SRAM0 usage by 1KB to account for non-init area */

Note that this configuration needs to be applied on both the bootloader (MCUboot) and application to be usable. It can be combined with other retention system APIs such as the Boot mode.

MCUboot setup Once the above devicetree configuration is applied, MCUboot needs to be configured to store the shared data in this area, the following Kconfigs need to be set for this:

- CONFIG_RETAINED_MEM - Enables retained memory driver
- CONFIG_RETENTION - Enables retention system
- CONFIG_BOOT_SHARE_DATA - Enables shared data
- CONFIG_BOOT_SHARE_DATA_BOOTINFO - Enables boot information shared data type
- CONFIG_BOOT_SHARE_BACKEND_RETENTION - Stores shared data using retention/blinfo subsystem

Application setup The application must enable the following base Kconfig options for the bootloader information subsystem to function:

- CONFIG_RETAINED_MEM
- CONFIG_RETENTION
- CONFIG_RETENTION_BOOTLOADER_INFO
- CONFIG_RETENTION_BOOTLOADER_INFO_TYPE_MCUBOOT

The following include is needed to use the bootloader information subsystem:

```
#include <zephyr/retention/blinfo.h>
```

By default, only the lookup function is provided: `blinfo_lookup()`, the application can call this to query the information from the bootloader. This function is enabled by default with `CONFIG_RETENTION_BOOTLOADER_INFO_OUTPUT_FUNCTION`, however, applications can optionally choose to use the settings storage feature instead. In this mode, the bootloader information can be queried by using settings keys, the following Kconfig options need to be enabled for this mode:

- CONFIG_SETTINGS
- CONFIG_SETTINGS_RUNTIME
- CONFIG_RETENTION_BOOTLOADER_INFO_OUTPUT_SETTINGS

This allows the information to be queried via the `settings_runtime_get()` function with the following keys:

- blinfo/mode The mode that MCUboot is configured for (enum mcuboot_mode value)
• `blinfo/signature_type` The signature type MCUboot is configured for (enum `mcuboot_signatu
 • `blinfo/recovery` The recovery type enabled in MCUboot (enum `mcuboot_recovery_mode
 • `blinfo/running_slot` The running slot, useful for direct-XIP mode to know which slot to
 • `blinfo/bootloader_version` Version of the bootloader (struct `image_version` object)
 • `blinfo/max_application_size` Maximum size of an application (in bytes) that can be

In addition to the previous include, the following includes are required for this mode:

```c
#include <bootutil/boot_status.h>
#include <bootutil/image.h>
#include <mcuboot_version.h>
#include <zephyr/settings/settings.h>
```

### API Reference

**Bootloader information API**

**group bootloader_info_interface**

Bootloader info interface.

**Functions**

```c
int blinfo_lookup(uint16_t key, char *val, int val_len_max)
```

Returns bootinfo information.

**Parameters**

- **key** – The information to return (for MCUboot: minor TLV).
- **val** – Where the return information will be placed.
- **val_len_max** – The maximum size of the provided buffer.

**Return values**

- **0** – If successful.
- `-EOVERFLOW` – If the data is too large to fit the supplied buffer.
- `-EIO` – If the requested key was not found.
- `-errno` – Error code.

### 4.30.5 API Reference

**Retention system API**

**group retention_api**

Retention API.
Typedefs

typedef ssize_t (*_retention_size_api)(const struct device *dev)

typedef int (*_retention_is_valid_api)(const struct device *dev)

typedef int (*_retention_read_api)(const struct device *dev, off_t offset, uint8_t *buffer, size_t size)

typedef int (*_retention_write_api)(const struct device *dev, off_t offset, const uint8_t *buffer, size_t size)

typedef int (*_retention_clear_api)(const struct device *dev)

Functions

ssize_t retention_size(const struct device *dev)
Returns the size of the retention area.

Parameters
  • dev – Retention device to use.

Return values
  Positive – value indicating size in bytes on success, else negative errno code.

int retention_is_valid(const struct device *dev)
Checks if the underlying data in the retention area is valid or not.

Parameters
  • dev – Retention device to use.

Return values
  • 1 – If successful and data is valid.
  • 0 – If data is not valid.
  • -ENOTSUP – If there is no header/checksum configured for the retention area.
  • -errno – Error code code.

int retention_read(const struct device *dev, off_t offset, uint8_t *buffer, size_t size)
Reads data from the retention area.

Parameters
  • dev – Retention device to use.
  • offset – Offset to read data from.
  • buffer – Buffer to store read data in.
  • size – Size of data to read.

Return values
  • 0 – If successful.
  • -errno – Error code code.
int retention_write(const struct device *dev, off_t offset, const uint8_t *buffer, size_t size)
Writes data to the retention area (underlying data does not need to be cleared prior to writing), once function returns with a success code, the data will be classed as valid if queried using retention_is_valid().

Parameters
- dev – Retention device to use.
- offset – Offset to write data to.
- buffer – Data to write.
- size – Size of data to be written.

Return values
0 – on success else negative errno code.

int retention_clear(const struct device *dev)
Clears all data in the retention area (sets it to 0)

Parameters
- dev – Retention device to use.

Return values
0 – on success else negative errno code.

struct retention_api
#include <retention.h>

Boot mode interface

group boot_mode_interface
Boot mode interface.

 Enums

enum BOOT_MODE_TYPES
Values:

enumerator BOOT_MODE_TYPE_NORMAL = 0x00
Default (normal) boot, to user application.

e enumerator BOOT_MODE_TYPE_BOOTLOADER
Bootloader boot mode (e.g. serial recovery for MCUboot)

Functions

int bootmode_check(uint8_t boot_mode)
Checks if the boot mode of the device is set to a specific value.

Parameters
- boot_mode – Expected boot mode to check.
Return values
  • 1 – If successful and boot mode matches.
  • 0 – If boot mode does not match.
  • -errno – Error code code.

int bootmode_set(uint8_t boot_mode)
  Sets boot mode of device.

Parameters
  • boot_mode – Boot mode value to set.

Return values
  • 0 – If successful.
  • -errno – Error code code.

int bootmode_clear(void)
  Clear boot mode value (sets to 0) - which corresponds to BOOT_MODE_TYPE_NORMAL.

Return values
  • 0 – If successful.
  • -errno – Error code code.

4.31 Real Time I/O (RTIO)

• Problem
• Inspiration, introducing io_uring
• Submission Queue
• Completion Queue
• Executor
• IO Device
• Cancellation
• Memory pools
• When to Use
• API Reference
  – MPSC Lock-free Queue API
  – SPSC Lock-free Queue API
RTIO provides a framework for doing asynchronous operation chains with event driven I/O. This section covers the RTIO API, queues, executor, iodev, and common usage patterns with peripheral devices.

RTIO takes a lot of inspiration from Linux's io_uring in its operations and API as that API matches up well with hardware transfer queues and descriptions such as DMA transfer lists.

### 4.31.1 Problem

An application wishing to do complex DMA or interrupt driven operations today in Zephyr requires direct knowledge of the hardware and how it works. There is no understanding in the DMA API of other Zephyr devices and how they relate.

This means doing complex audio, video, or sensor streaming requires direct hardware knowledge or leaky abstractions over DMA controllers. Neither is ideal.

To enable asynchronous operations, especially with DMA, a description of what to do rather than direct operations through C and callbacks is needed. Enabling DMA features such as channels with priority, and sequences of transfers requires more than a simple list of descriptions.

Using DMA and/or interrupt driven I/O shouldn't dictate whether or not the call is blocking or not.

### 4.31.2 Inspiration, introducing io_uring

It’s better not to reinvent the wheel (or ring in this case) and io_uring as an API from the Linux kernel provides a winning model. In io_uring there are two lock-free ring buffers acting as queues shared between the kernel and a userland application. One queue for submission entries which may be chained and flushed to create concurrent sequential requests. A second queue for completion queue events. Only a single syscalls is actually required to execute many operations, the io_uring_submit call. This call may block the caller when a number of operations to wait on is given.

This model maps well to DMA and interrupt driven transfers. A request to do a sequence of operations in an asynchronous way directly relates to the way hardware typically works with...
interrupt driven state machines potentially involving multiple peripheral IPs like bus and DMA controllers.

### 4.31.3 Submission Queue

The submission queue (sq), is the description of the operations to perform in concurrent chains. For example imagine a typical SPI transfer where you wish to write a register address to then read from. So the sequence of operations might be...

1. Chip Select  
2. Clock Enable  
3. Write register address into SPI transmit register  
4. Read from the SPI receive register into a buffer  
5. Disable clock  
6. Disable Chip Select

If anything in this chain of operations fails give up. Some of those operations can be embodied in a device abstraction that understands a read or write implicitly means setup the clock and chip select. The transactional nature of the request also needs to be embodied in some manner. Of the operations above perhaps the read could be done using DMA as its large enough make sense. That requires an understanding of how to setup the device's particular DMA to do so.

The above sequence of operations is embodied in RTIO as chain of submission queue entries (sqe). Chaining is done by setting a bitflag in an sqe to signify the next sqe must wait on the current one.

Because the chip select and clocking is common to a particular SPI controller and device on the bus it is embodied in what RTIO calls an iodev.

Multiple operations against the same iodev are done in the order provided as soon as possible. If two operation chains have varying points using the same device its possible one chain will have to wait for another to complete.

### 4.31.4 Completion Queue

In order to know when a sqe has completed there is a completion queue (cq) with completion queue events (cqe). A sqe once completed results in a cqe being pushed into the cq. The ordering of cqe may not be the same order of sqe. A chain of sqe will however ensure ordering and failure cascading.

Other potential schemes are possible but a completion queue is a well trod idea with io_uring and other similar operating system APIs.

### 4.31.5 Executor

The RTIO executor is a low overhead concurrent I/O task scheduler. It ensures certain request flags provide the expected behavior. It takes a list of submissions working through them in order. Various flags allow for changing the behavior of how submissions are worked through. Flags to form in order chains of submissions, transactional sets of submissions, or create multi-shot (continuously producing) requests are all possible!
4.31.6 IO Device

Turning submission queue entries (sqe) into completion queue events (cqe) is the job of objects implementing the iodev (IO device) API. This API accepts requests in the form of the iodev submit API call. It is the iodev's job to work through its internal queue of submissions and convert them into completions. In effect every iodev can be viewed as an independent, event driven actor like object, that accepts a never ending queue of I/O like requests. How the iodev does this work is up to the author of the iodev, perhaps the entire queue of operations can be converted to a set of DMA transfer descriptors, meaning the hardware does almost all of the real work.

4.31.7 Cancellation

Canceling an already queued operation is possible but not guaranteed. If the SQE has not yet started, it's likely that a call to `rtio_sqe_cancel()` will remove the SQE and never run it. If, however, the SQE already started running, the cancel request will be ignored.

4.31.8 Memory pools

In some cases requests to read may not know how much data will be produced. Alternatively, a reader might be handling data from multiple iodevs where the frequency of the data is unpredictable. In these cases it may be wasteful to bind memory to in flight read requests. Instead with memory pools the memory to read into is left to the iodev to allocate from a memory pool associated with the RTIO context that the read was associated with. To create such an RTIO context the `RTIO_DEFINE_WITH_MEMPOOL` can be used. It allows creating an RTIO context with a dedicated pool of “memory blocks” which can be consumed by the iodev. Below is a snippet setting up the RTIO context with a memory pool. The memory pool has 128 blocks, each block has the size of 16 bytes, and the data is 4 byte aligned.

```c
#include <zephyr/rtio/rtio.h>

#define SQ_SIZE   4
#define CQ_SIZE   4
#define MEM_BLK_COUNT 128
#define MEM_BLK_SIZE 16
#define MEM_BLK_ALIGN 4

RTIO_DEFINE_WITH_MEMPOOL(rtio_context,
                          SQ_SIZE, CQ_SIZE,
                          MEM_BLK_COUNT, MEM_BLK_SIZE,
                          MEM_BLK_ALIGN);
```

When a read is needed, the caller simply needs to replace the call `rtio_sqe_prep_read()` (which takes a pointer to a buffer and a length) with a call to `rtio_sqe_prep_read_with_pool()`. The iodev requires only a small change which works with both pre-allocated data buffers as well as the mempool. When the read is ready, instead of getting the buffers directly from the `rtio_iodev_sqe`, the iodev should get the buffer and count by calling `rtio_sqe_rx_buf()` like so:

```c
uint8_t *buf;
uint32_t buf_len;
int rc = rtio_sqe_rx_buf(iodev_sqe, MIN_BUF_LEN, DESIRED_BUF_LEN, &buf, &buf_len);
if (rc != 0) {
    LOG_ERR("Failed to get buffer of at least %u bytes", MIN_BUF_LEN);
    return;
}
```

Finally, the consumer will be able to access the allocated buffer via `rtio_cqe_get_mempool_buffer()`. 

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```c
uint8_t *buf;
uint32_t buf_len;
int rc = rtio_cqe_get_mempool_buffer(&rtio_context, &cqe, &buf, &buf_len);

if (rc != 0) {
    LOG_ERR("Failed to get mempool buffer");
    return rc;
}

// Release the cqe events (note that the buffer is not released yet */
rtio_cqe_release_all(&rtio_context);

// Do something with the memory */

// Release the mempool buffer */
rtio_release_buffer(&rtio_context, buf);
```

### 4.31.9 When to Use

RTIO is useful in cases where concurrent or batch like I/O flows are useful. From the driver/hardware perspective the API enables batching of I/O requests, potentially in an optimal way. Many requests to the same SPI peripheral for example might be translated to hardware command queues or DMA transfer descriptors entirely. Meaning the hardware can potentially do more than ever.

There is a small cost to each RTIO context and iodev. This cost could be weighed against using a thread for each concurrent I/O operation or custom queues and threads per peripheral. RTIO is much lower cost than that.

### 4.31.10 API Reference

**group rtio**

RTIO.

**Defines**

- **RTIO_IODEV_I2C_STOP**
  Equivalent to the I2C_MSG_STOP flag.

- **RTIO_IODEV_I2C_RESTART**
  Equivalent to the I2C_MSG_RESTART flag.

- **RTIO_IODEV_I2C_10_BITS**
  Equivalent to the I2C_MSG_ADDR_10_BITS.

- **RTIO_OP_NOP**
  An operation that does nothing and will complete immediately.

- **RTIO_OP_RX**
  An operation that receives (reads)
RTIO_OP_TX
An operation that transmits (writes)

RTIO_OP_TINY_TX
An operation that transmits tiny writes by copying the data to write.

RTIO_OP_CALLBACK
An operation that calls a given function (callback)

RTIO_OP_TXRX
An operation that transceives (reads and writes simultaneously)

RTIO_IODEV_DEFINE(name, iodev_api, iodev_data)
Statically define and initialize an RTIO IODev.

Parameters

- name – Name of the iodev
- iodev_api – Pointer to struct rtio_iodev_api
- iodev_data – Data pointer

RTIO_BMEM
Allocate to bss if available.
If CONFIG_USERSPACE is selected, allocate to the rtio_partition bss. Maps to: K_APP_BMEM(rtio_partition) static
If CONFIG_USERSPACE is disabled, allocate as plain static: static

RTIO_DMEM
Allocate as initialized memory if available.
If CONFIG_USERSPACE is selected, allocate to the rtio_partition init. Maps to: K_APP_DMEM(rtio_partition) static
If CONFIG_USERSPACE is disabled, allocate as plain static: static

RTIO_DEFINE(name, sq_sz, cq_sz)
Statically define and initialize an RTIO context.

Parameters

- name – Name of the RTIO
- sq_sz – Size of the submission queue entry pool
- cq_sz – Size of the completion queue entry pool

RTIO_DEFINE_WITH_MEMPOOL(name, sq_sz, cq_sz, num_blks, blk_size, balign)
Statically define and initialize an RTIO context.

Parameters

- name – Name of the RTIO
- sq_sz – Size of the submission queue, must be power of 2
- cq_sz – Size of the completion queue, must be power of 2
- num_blks – Number of blocks in the memory pool
- blk_size – The number of bytes in each block
• **balign** – The block alignment

**Typedefs**

typedef void (*rtio_callback_t)(struct rtio *r, const struct rtio_sqe *sqe, void *arg0)

Callback signature for RTIO_OP_CALLBACK.

**Param r**
RTIO context being used with the callback

**Param sqe**
Submission for the callback op

**Param arg0**
Argument option as part of the sqe

**Functions**

static inline size_t rtio_mempool_block_size(const struct rtio *r)

Get the mempool block size of the RTIO context.

**Parameters**

• **r** – [in] The RTIO context

**Returns**

The size of each block in the context's mempool

**Returns**

0 if the context doesn't have a mempool

static inline void rtio_sqe_prep_nop(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, void *userdata)

Prepare a nop (no op) submission.

static inline void rtio_sqe_prep_read(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, int8_t prio, uint8_t *buf, uint32_t len, void *userdata)

Prepare a read op submission.

static inline void rtio_sqe_prep_read_with_pool(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, int8_t prio, void *userdata)

Prepare a read op submission with context's mempool.

**See also:**

*rtio_sqe_prep_read()*

static inline void rtio_sqe_prep_write_read_multishot(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, int8_t prio, uint8_t *buf, void *userdata)

Prepare a write op submission.
static inline void rtio_sqe_prep_tiny_write(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, int8_t prio, const uint8_t *tiny_write_data, uint8_t tiny_write_len, void *userdata)

Prepare a tiny write op submission.
Unlike the normal write operation where the source buffer must outlive the call the tiny write data in this case is copied to the sqe. It must be tiny to fit within the specified size of a rtio_sqe.
This is useful in many scenarios with RTL logic where a write of the register to subsequently read must be done.

static inline void rtio_sqe_prep_callback(struct rtio_sqe *sqe, rtio_callback_t callback, void *arg0, void *userdata)

Prepare a callback op submission.
A somewhat special operation in that it may only be done in kernel mode.
Used where general purpose logic is required in a queue of io operations to do transforms or logic.

static inline void rtio_sqe_prep_transceive(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, int8_t prio, uint8_t *tx_buf, uint8_t *rx_buf, uint32_t buf_len, void *userdata)

Prepare a transceive op submission.

static inline struct rtio_iodev_sqe *rtio_sqe_pool_alloc(struct rtio_sqe_pool *pool)

static inline void rtio_sqe_pool_free(struct rtio_sqe_pool *pool, struct rtio_iodev_sqe *iodev_sqe)

static inline struct rtio_cqe *rtio_cqe_pool_alloc(struct rtio_cqe_pool *pool)

static inline void rtio_cqe_pool_free(struct rtio_cqe_pool *pool, struct rtio_cqe *cqe)

static inline int rtio_block_pool_alloc(struct rtio *r, size_t min_sz, size_t max_sz, uint8_t **buf, uint32_t *buf_len)

static inline void rtio_block_pool_free(struct rtio *r, void *buf, uint32_t buf_len)

static inline uint32_t rtio_sqe_acquirable(struct rtio *r)
Count of acquirable submission queue events.

Parameters
• r – RTIO context

Returns
Count of acquirable submission queue events

static inline struct rtio_iodev_sqe *rtio_txn_next(const struct rtio_iodev_sqe *iodev_sqe)
Get the next sqe in the transaction.

Parameters
• iodev_sqe – Submission queue entry

Return values
• NULL – if current sqe is last in transaction
• struct – rtio_sqe * if available
static inline struct rtio_iodev_sqe *rtio_chain_next(const struct rtio_iodev_sqe *iodev_sqe)

Get the next sqe in the chain.

**Parameters**
- iodev_sqe – Submission queue entry

**Return values**
- NULL – if current sqe is last in chain
- struct – rtio_sqe * if available

static inline struct rtio_iodev_sqe *rtio_iodev_sqe_next(const struct rtio_iodev_sqe *iodev_sqe)

Get the next sqe in the chain or transaction.

**Parameters**
- iodev_sqe – Submission queue entry

**Return values**
- NULL – if current sqe is last in chain
- struct – rtio_iodev_sqe * if available

static inline struct rtio_sqe *rtio_sqe_acquire(struct rtio *r)

Acquire a single submission queue event if available.

**Parameters**
- r – RTIO context

**Return values**
- sqe – A valid submission queue event acquired from the submission queue
- NULL – No submission queue event available

static inline void rtio_sqe_drop_all(struct rtio *r)

Drop all previously acquired sqe.

**Parameters**
- r – RTIO context

static inline struct rtio_cqe *rtio_cqe_acquire(struct rtio *r)

Acquire a complete queue event if available.

static inline void rtio_cqe_produce(struct rtio *r, struct rtio_cqe *cqe)

Produce a complete queue event if available.

static inline struct rtio_cqe *rtio_cqe_consume(struct rtio *r)

Consume a single completion queue event if available.

If a completion queue event is returned rtio_cq_release(r) must be called at some point to release the cqe spot for the cqe producer.

**Parameters**
- r – RTIO context

**Return values**
- cqe – A valid completion queue event consumed from the completion queue
- NULL – No completion queue event available
static inline struct rtio_cqe* rtio_cqe_consume_block(struct rtio*r)

Wait for and consume a single completion queue event.

If a completion queue event is returned rtio_cq_release(r) must be called at some point to release the cqe spot for the cqe producer.

Parameters

• r – RTIO context

Return values

cqe – A valid completion queue event consumed from the completion queue

static inline void rtio_cqe_release(struct rtio*r, struct rtio_cqe*cqe)

Release consumed completion queue event.

Parameters

• r – RTIO context

• cqe – Completion queue entry

static inline uint32_t rtio_cqe_compute_flags(struct rtio_iodev_sqe*iodev_sqe)

Compute the CQE flags from the rtio_iodev_sqe entry.

Parameters

• iodev_sqe – The SQE entry in question.

Returns

The value that should be set for the CQE’s flags field.

int rtio_cqe_get_mempool_buffer(const struct rtio*r, struct rtio_cqe*cqe, uint8_t **buff, uint32_t *buff_len)

Retrieve the mempool buffer that was allocated for the CQE.

If the RTIO context contains a memory pool, and the SQE was created by calling rtio_sqe_read_with_pool(), this function can be used to retrieve the memory associated with the read. Once processing is done, it should be released by calling rtio_release_buffer().

Parameters

• r – [in] RTIO context

• cqe – [in] The CQE handling the event.

• buff – [in] Pointer to the mempool buffer

• buff_len – [out] Length of the allocated buffer

Returns

0 on success

Returns

-EINVAL if the buffer wasn’t allocated for this cqe

Returns

-ENOTSUP if memory blocks are disabled

void rtio_executor_submit(struct rtio*r)

void rtio_executor_ok(struct rtio_iodev_sqe*iodev_sqe, int result)

void rtio_executor_err(struct rtio_iodev_sqe*iodev_sqe, int result)
static inline void rtio_iodev_sqe_ok(struct rtio_iodev_sqe *iodev_sqe, int result)
Inform the executor of a submission completion with success.
This may start the next asynchronous request if one is available.

Parameters
• iodev_sqe – IODev Submission that has succeeded
• result – Result of the request

static inline void rtio_iodev_sqe_err(struct rtio_iodev_sqe *iodev_sqe, int result)
Inform the executor of a submissions completion with error.
This SHALL fail the remaining submissions in the chain.

Parameters
• iodev_sqe – Submission that has failed
• result – Result of the request

static inline void rtio_iodev_cancel_all(struct rtio_iodev *iodev)
Cancel all requests that are pending for the iodev.

Parameters
• iodev – IODev to cancel all requests for

static inline void rtio_cqe_submit(struct rtio *r, int result, void *userdata, uint32_t flags)
Submit a completion queue event with a given result and userdata.
Called by the executor to produce a completion queue event, no inherent locking is
performed and this is not safe to do from multiple callers.

Parameters
• r – RTIO context
• result – Integer result code (could be -errno)
• userdata – Userdata to pass along to completion
• flags – Flags to use for the CEQ see RTIO_CQE_FLAG_ *

static inline int rtio_sqe_rx_buf(const struct rtio_iodev_sqe *iodev_sqe, uint32_t min_buf_len, uint32_t max_buf_len, uint8_t **buf, uint32_t *buf_len)
Get the buffer associate with the RX submission.

Parameters
• iodev_sqe – [in] The submission to probe
• min_buf_len – [in] The minimum number of bytes needed for the operation
• max_buf_len – [in] The maximum number of bytes needed for the operation
• buf – [out] Where to store the pointer to the buffer
• buf_len – [out] Where to store the size of the buffer

Returns
0 if buf and buf_len were successfully filled

Returns
-ENOMEM Not enough memory for min_buf_len
void rtio_release_buffer(struct rtio *r, void *buff, uint32_t buff_len)
Release memory that was allocated by the RTIO's memory pool.

If the RTIO context was created by a call to RTIO_DEFINE_WITH_MEMPOOL(), then
the cqe data might contain a buffer that's owned by the RTIO context. In those cases
(if the read request was configured via rtio_sqe_read_with_pool()) the buffer must be
returned back to the pool.

Call this function when processing is complete. This function will validate that the
memory actually belongs to the RTIO context and will ignore invalid arguments.

Parameters
• r – RTIO context
• buff – Pointer to the buffer to be released.
• buff_len – Number of bytes to free (will be rounded up to nearest mem-
ory block).

static inline void rtio_access_grant(struct rtio *r, struct k_thread *t)
Grant access to an RTIO context to a user thread.

int rtio_sqe_cancel(struct rtio_sqe *sqe)
Attempt to cancel an SQE.

If possible (not currently executing), cancel an SQE and generate a failure with -
ECANCELED result.

Parameters
• sqe – [in] The SQE to cancel

Returns
0 if the SQE was flagged for cancellation

Returns
<0 on error

int rtio_sqe_copy_in_get_handles(struct rtio *r, const struct rtio_sqe *sqes, struct rtio_sqe **handle, size_t sqe_count)
Copy an array of SQEs into the queue and get resulting handles back.

Copies one or more SQEs into the RTIO context and optionally returns their generated
SQE handles. Handles can be used to cancel events via the rtio_sqe_cancel() call.

Parameters
• r – [in] RTIO context
• sqes – [in] Pointer to an array of SQEs
• handle – [out] Optional pointer to rtio_sqe pointer to store the handle of
the first generated SQE. Use NULL to ignore.
• sqe_count – [in] Count of sqes in array

Return values
• 0 – success
• -ENOMEM – not enough room in the queue

static inline int rtio_sqe_copy_in(struct rtio *r, const struct rtio_sqe *sqes, size_t sqe_count)
Copy an array of SQEs into the queue.

Useful if a batch of submissions is stored in ROM or RTIO is used from user mode where
a copy must be made.
Partial copying is not done as chained SQEs need to be submitted as a whole set.

**Parameters**
- `r` – RTIO context
- `sqes` – Pointer to an array of SQEs
- `sqe_count` – Count of sqes in array

**Return values**
- `0` – success
- `-ENOMEM` – not enough room in the queue

```c
int rtio_cqe_copy_out(struct rtio *r, struct rtio_cqe *cqes, size_t cqe_count, k_timeout_t timeout)
```

Copy an array of CQEs from the queue.

Copies from the RTIO context and its queue completion queue events, waiting for the given time period to gather the number of completions requested.

**Parameters**
- `r` – RTIO context
- `cqes` – Pointer to an array of SQEs
- `cqe_count` – Count of sqes in array
- `timeout` – Timeout to wait for each completion event. Total wait time is potentially `timeout*cqe_count` at maximum.

**Return values**
- `copy_count` – Count of copied CQEs (0 to `cqe_count`)

```c
int rtio_submit(struct rtio *r, uint32_t wait_count)
```

Submit I/O requests to the underlying executor.

Submits the queue of submission queue events to the executor. The executor will do the work of managing tasks representing each submission chain, freeing submission queue events when done, and producing completion queue events as submissions are completed.

**Parameters**
- `r` – RTIO context
- `wait_count` – Number of submissions to wait for completion of.

**Return values**
- `0` – On success

**Variables**

```c
#include <rtio.h>
```

```
struct k_mem_partition rtio_partition
```

The memory partition associated with all RTIO context information.

```
struct rtio_sqe
```

```c
#include <rtio.h> A submission queue event.
```
Public Members

uint8_t op
   Op code.

uint8_t prio
   Op priority.

uint16_t flags
   Op Flags.

uint16_t iodev_flags
   Op iodev flags.

const struct rtio_iodev *iodev
   Device to operation on.

void *userdata
   User provided data which is returned upon operation completion.
   Could be a pointer or integer.
   If unique identification of completions is desired this should be unique as well.

uint32_t buf_len
   Length of buffer.

uint8_t *buf
   Buffer to use.

uint8_t tiny_buf_len
   Length of tiny buffer.

uint8_t tiny_buf[7]
   Tiny buffer.

void *arg0
   Last argument given to callback.

struct rtio_cqe
   #include <rtio.h> A completion queue event.

Public Members

int32_t result
   Result from operation.

void *userdata
   Associated userdata with operation.
uint32_t flags
    Flags associated with the operation.

struct rtio_sqe_pool
    #include <rtio.h>

struct rtio_cqe_pool
    #include <rtio.h>

struct rtio
    #include <rtio.h> An RTIO context containing what can be viewed as a pair of queues. A queue for submissions (available and in queue to be produced) as well as a queue of completions (available and ready to be consumed).
    The rtio executor along with any objects implementing the rtio_iodev interface are the consumers of submissions and producers of completions.
    No work is started until rtio_submit() is called.

struct rtio_iodev_sqe
    #include <rtio.h> Compute the mempool block index for a given pointer.

IO device submission queue entry
May be cast safely to and from a rtio_sqe as they occupy the same memory provided by the pool

Param r
    [in] RTIO context

Param ptr
    [in] Memory pointer in the mempool

Return
    Index of the mempool block associated with the pointer. Or UINT16_MAX if invalid.

struct rtio_iodev_api
    #include <rtio.h> API that an RTIO IO device should implement.

Public Members

void (*submit)(struct rtio_iodev_sqe *iodev_sqe)
    Submit to the iodev an entry to work on.
    This call should be short in duration and most likely either enqueue or kick off an entry with the hardware.
    Param iodev_sqe
        Submission queue entry

struct rtio_iodev
    #include <rtio.h> An IO device with a function table for submitting requests.
MPSC Lock-free Queue API

*group* *rtio_mpsc*

RTIO Multiple Producer Single Consumer (MPSC) Queue API.

**Defines**

mpsc_ptr_get(ptr)

mpsc_ptr_set(ptr, val)

mpsc_ptr_set_get(ptr, val)

RTIO_MPSC_INIT(symbol)

Static initializer for a mpsc queue.

Since the queue is

**Parameters**

• symbol – name of the queue

**Typedefs**

typedef atomic_ptr_t mpsc_ptr_t

**Functions**

static inline void rtio_mpsc_init(struct rtio_mpsc *q)

Initialize queue.

**Parameters**

• q – Queue to initialize or reset

ALWAYS_INLINE static void rtio_mpsc_push(struct rtio_mpsc *q, struct rtio_mpsc_node *n)

Push a node.

**Parameters**

• q – Queue to push the node to
• n – Node to push into the queue

static inline struct rtio_mpsc_node *rtio_mpsc_pop(struct rtio_mpsc *q)

Pop a node off of the list.

**Return values**

• NULL – When no node is available
• node – When node is available

struct rtio_mpsc_node

#include <rtio_mpsc.h> Queue member.

struct rtio_mpsc

#include <rtio_mpsc.h> MPSC Queue.
SPSC Lock-free Queue API

**group rtio_spsc**

RTIO Single Producer Single Consumer (SPSC) Queue API.

**Defines**

`RTIO_SPSC_INITIALIZER(sz, buf)`

Statically initialize an rtio_spsc.

**Parameters**

- `sz` – Size of the spsc, must be power of 2 (ex: 2, 4, 8)
- `buf` – Buffer pointer

`RTIO_SPSC_DECLARE(name, type)`

Declare an anonymous struct type for an rtio_spsc.

**Parameters**

- `name` – Name of the spsc symbol to be provided
- `type` – Type stored in the spsc

`RTIO_SPSC_DEFINE(name, type, sz)`

Define an rtio_spsc with a fixed size.

**Parameters**

- `name` – Name of the spsc symbol to be provided
- `type` – Type stored in the spsc
- `sz` – Size of the spsc, must be power of 2 (ex: 2, 4, 8)

`rtio_spsc_size(spsc)`

Size of the SPSC queue.

**Parameters**

- `spsc` – SPSC reference

`rtio_spsc_reset(spsc)`

Initialize/reset a spsc such that its empty.

Note that this is not safe to do while being used in a producer/consumer situation with multiple calling contexts (isrs/threads).

**Parameters**

- `spsc` – SPSC to initialize/reset

`rtio_spsc_acquire(spsc)`

Acquire an element to produce from the SPSC.

**Parameters**

- `spsc` – SPSC to acquire an element from for producing

**Returns**

A pointer to the acquired element or null if the spsc is full
rtio_spsc_produce(spsc)
Produce one previously acquired element to the SPSC.
This makes one element available to the consumer immediately

Parameters
• spsc – SPSC to produce the previously acquired element or do nothing

rtio_spsc_produce_all(spsc)
Produce all previously acquired elements to the SPSC.
This makes all previous acquired elements available to the consumer immediately

Parameters
• spsc – SPSC to produce all previously acquired elements or do nothing

rtio_spsc_drop_all(spsc)
Drop all previously acquired elements.
This makes all previous acquired elements available to be acquired again

Parameters
• spsc – SPSC to drop all previously acquired elements or do nothing

rtio_spsc_consume(spsc)
Consume an element from the spsc.

Parameters
• spsc – Spsc to consume from

Returns
Pointer to element or null if no consumable elements left

rtio_spsc_release(spsc)
Release a consumed element.

Parameters
• spsc – SPSC to release consumed element or do nothing

rtio_spsc_release_all(spsc)
Release all consumed elements.

Parameters
• spsc – SPSC to release consumed elements or do nothing

rtio_spsc_acquirable(spsc)
Count of acquirable in spsc.

Parameters
• spsc – SPSC to get item count for

rtio_spsc_consumable(spsc)
Count of consumables in spsc.

Parameters
• spsc – SPSC to get item count for

rtio_spsc_peek(spsc)
Peek at the first available item in queue.

Parameters
• spsc – Spsc to peek into
**Returns**
Pointer to element or null if no consumable elements left

```
rtio_spsc_next(spsc, item)
```
Peek at the next item in the queue from a given one.

**Parameters**
- `spsc` – SPSC to peek at
- `item` – Pointer to an item in the queue

**Returns**
Pointer to element or null if none left

```
rtio_spsc_prev(spsc, item)
```
Get the previous item in the queue from a given one.

**Parameters**
- `spsc` – SPSC to peek at
- `item` – Pointer to an item in the queue

**Returns**
Pointer to element or null if none left

```
struct rtio_spsc
```
Common SPSC attributes.

**Warning:** Not to be manipulated without the macros!

## 4.32 Zephyr bus (zbus)

The **Zephyr bus - zbus** is a lightweight and flexible software bus enabling a simple way for threads to talk to one another in a many-to-many way.

- **Concepts**
  - Virtual Distributed Event Dispatcher
  - Limitations
- **Usage**
  - Publishing to a channel
  - Reading from a channel
  - Notifying a channel
  - Declaring channels and observers
  - Iterating over channels and observers
  - Advanced channel control
- **Samples**
- **Suggested Uses**
- **Configuration Options**
- **API Reference**
4.32.1 Concepts

Threads can send messages to one or more observers using zbus. It makes the many-to-many communication possible. The bus implements message-passing and publish/subscribe communication paradigms that enable threads to communicate synchronously or asynchronously through shared memory.

The communication through zbus is channel-based. Threads (or callbacks) use channels to exchange messages. Additionally, besides other actions, threads can publish and observe channels. When a thread publishes a message on a channel, the bus will make the message available to all the published channel’s observers. Based on the observer’s type, it can access the message directly, receive a copy of it, or even receive only a reference of the published channel.

The figure below shows an example of a typical application using zbus in which the application logic (hardware independent) talks to other threads via software bus. Note that the threads are decoupled from each other because they only use zbus channels and do not need to know each other to talk.

![Fig. 18: A typical zbus application architecture.](image)

The bus comprises:

- Set of channels that consists of the control metadata information, and the message itself;
- Virtual Distributed Event Dispatcher (VDED), the bus logic responsible for sending notifications/messages to the observers. The VDED logic runs inside the publishing action in the same thread context, giving the bus an idea of a distributed execution. When a thread publishes to a channel, it also propagates the notifications to the observers;
- Threads (subscribers and message subscribers) and callbacks (listeners) publishing, reading, and receiving notifications from the bus.

The bus makes the publish, read, claim, finish, notify, and subscribe actions available over channels. Publishing, reading, claiming, and finishing are available in all RTOS thread contexts, including ISRs. The publish and read operations are simple and fast; the procedure is channel locking followed by a memory copy to and from a shared memory region and then a channel unlocking. Another essential aspect of zbus is the observers. There are three types of observers:

- Listeners, a callback that the event dispatcher executes every time an observed channel is published or notified;
- Subscriber, a thread-based observer that relies internally on a message queue where the event dispatcher puts a changed channel’s reference every time an observed channel is published or notified. Note this kind of observer does not receive the message itself. It should read the message from the channel after receiving the notification;
- Message subscribers, a thread-based observer that relies internally on a FIFO where the event dispatcher puts a copy of the message every time an observed channel is published or notified.
Channel observation structures define the relationship between a channel and its observers. For every observation, a pair channel/observer. Developers can statically allocate observation using the `ZBUS_CHAN_DEFINE` or `ZBUS_CHAN_ADD_OBS`. There are also runtime observers, enabling developers to create runtime observations. It is possible to disable an observer entirely or observations individually. The event dispatcher will ignore disabled observers and observations.

The above figure illustrates some states, from (a) to (d), for channels from C1 to C5, Subscriber 1, and the observations. The last two are in orange to indicate they are dynamically allocated (runtime observation). (a) shows that the observer and all observations are enabled. (b) shows the observer is disabled, so the event dispatcher will ignore it. (c) shows the observer enabled. However, there is one static observation disabled. The event dispatcher will only stop sending notifications from channel C3. In (d), the event dispatcher will stop sending notifications from channels C3 and C5 to Subscriber 1.

Suppose a usual sensor-based solution is in the figure below for illustration purposes. When triggered, the timer publishes to the Trigger channel. As the sensor thread subscribed to the Trigger channel, it receives the sensor data. Notice the VDED executes the Blink because it also listens to the Trigger channel. When the sensor data is ready, the sensor thread publishes it to the Sensor data channel. The core thread receives the message as a Sensor data channel message subscriber, processes the sensor data, and stores it in an internal sample buffer. It repeats until the sample buffer is full; when it happens, the core thread aggregates the sample buffer information, prepares a package, and publishes that to the Payload channel. The Lora thread receives that because it is a Payload channel message subscriber and sends the payload to the cloud. When it completes the transmission, the Lora thread publishes to the Transmission done channel. The VDED executes the Blink again since it listens to the Transmission done channel.

This way of implementing the solution makes the application more flexible, enabling us to change things independently. For example, we want to change the trigger from a timer to a button press. We can do that, and the change does not affect other parts of the system. Likewise, we would like to change the communication interface from LoRa to Bluetooth; we only need to change the LoRa thread. No other change is required in order to make that work. Thus, the developer would do that for every block of the image. Based on that, there is a sign zbus promotes decoupling in the system architecture.

Another important aspect of using zbus is the reuse of system modules. If a code portion with well-defined behaviors (we call that module) only uses zbus channels and not hardware interfaces, it can easily be reused in other solutions. The new solution must implement the interfaces (set of channels) the module needs to work. That indicates zbus could improve the module reuse.
Fig. 21: ZBus observation mask.

Fig. 22: ZBus sensor-based application.
The last important note is the zbus solution reach. We can count on many ways of using zbus to enable the developer to be as free as possible to create what they need. For example, messages can be dynamic or static allocated; notifications can be synchronous or asynchronous; the developer can control the channel in so many different ways claiming the channel, developers can add their metadata information to a channel by using the user-data field, the discretionary use of a validator enables the systems to be accurate over message format, and so on. Those characteristics increase the solutions that can be done with zbus and make it a good fit as an open-source community tool.

**Virtual Distributed Event Dispatcher**

The VDED execution always happens in the publisher’s context. It can be a thread or an ISR. Be careful with publications inside ISR because the scheduler won’t preempt the VDED. Use that wisely. The basic description of the execution is as follows:

- The channel lock is acquired;
- The channel receives the new message via direct copy (by a raw `memcpy()`);
- The event dispatcher logic executes the listeners, sends a copy of the message to the message subscribers, and pushes the channel’s reference to the subscribers’ notification message queue in the same sequence they appear on the channel observers’ list. The listeners can perform non-copy quick access to the constant message reference directly (via the `zbus_chan_const_msg()` function) since the channel is still locked;
- At last, the publishing function unlocks the channel.

To illustrate the VDED execution, consider the example illustrated below. We have four threads in ascending priority `S1, MS2, MS1, and T1` (the highest priority); two listeners, `L1` and `L2`; and channel `A`. Supposing `L1, L2, MS1, MS2, and S1` observer channel `A`.

![ZBus VDED execution example scenario.](image)

The following code implements channel `A`. Note the `struct a_msg` is illustrative only.

```c
ZBUS_CHAN_DEFINE(a_chan, /* Name */
    struct a_msg, /* Message type */
    NULL, /* Validator */
    NULL, /* User Data */
    ZBUS_OBSERVERS(L1, L2, MS1, MS2, S1), /* observers */
    ZBUS_MSG_INIT(0) /* Initial value {0} */
);
```

In the figure below, the letters indicate some action related to the VDED execution. The X-axis represents the time, and the Y-axis represents the priority of threads. Channel `A`'s message, represented by a voice balloon, is only one memory portion (shared memory). It appears several times only as an illustration of the message at that point in time.
Fig. 24: ZBus VDED execution detail for priority T1 > MS1 > MS2 > S1.

The figure above illustrates the actions performed during the VDED execution when T1 publishes to channel A. Thus, the table below describes the activities (represented by a letter) of the VDED execution. The scenario considers the following priorities: T1 > MS1 > MS2 > S1. T1 has the highest priority.

<table>
<thead>
<tr>
<th>Actions</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>a</td>
<td>T1 starts and, at some point, publishes to channel A.</td>
</tr>
<tr>
<td>b</td>
<td>The publishing (VDED) process starts. The VDED locks the channel A.</td>
</tr>
<tr>
<td>c</td>
<td>The VDED copies the T1 message to the channel A message.</td>
</tr>
<tr>
<td>d, e</td>
<td>The VDED executes L1 and L2 in the respective sequence. Inside the listeners, usually, there is a call to the <code>zbus_chan_const_msg()</code> function, which provides a direct constant reference to channel A's message. It is quick, and no copy is needed here.</td>
</tr>
<tr>
<td>f, g</td>
<td>The VDED copies the message and sends that to MS1 and MS2 sequentially. Notice the threads get ready to execute right after receiving the notification. However, they go to a pending state because they have less priority than T1.</td>
</tr>
<tr>
<td>h</td>
<td>The VDED pushes the notification message to the queue of S1. Notice the thread gets ready to execute right after receiving the notification. However, it goes to a pending state because it cannot access the channel since it is still locked.</td>
</tr>
<tr>
<td>i</td>
<td>VDED finishes the publishing by unlocking channel A. The MS1 leaves the pending state and starts executing.</td>
</tr>
<tr>
<td>j</td>
<td>MS1 finishes execution. The MS2 leaves the pending state and starts executing.</td>
</tr>
<tr>
<td>k</td>
<td>MS2 finishes execution. The S1 leaves the pending state and starts executing.</td>
</tr>
<tr>
<td>l, m, n</td>
<td>The S1 leaves the pending state since channel A is not locked. It gets in the CPU again and starts executing. As it did receive a notification from channel A, it performed a channel read (as simple as lock, memory copy, unlock), continues its execution and goes out of the CPU.</td>
</tr>
<tr>
<td>o</td>
<td>S1 finishes its workload.</td>
</tr>
</tbody>
</table>

The figure below illustrates the actions performed during the VDED execution when T1 publishes...
to channel A. The scenario considers the following priorities: T1 < MS1 < MS2 < S1.

Fig. 25: ZBus VDED execution detail for priority T1 < MS1 < MS2 < S1.

Thus, the table below describes the activities (represented by a letter) of the VDED execution.

<table>
<thead>
<tr>
<th>Actions</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>a</td>
<td>T1 starts and, at some point, publishes to channel A.</td>
</tr>
<tr>
<td>b</td>
<td>The publishing (VDED) process starts. The VDED locks the channel A.</td>
</tr>
<tr>
<td>c</td>
<td>The VDED copies the T1 message to the channel A message.</td>
</tr>
<tr>
<td>d, e</td>
<td>The VDED executes L1 and L2 in the respective sequence. Inside the listeners, usually, there is a call to the <code>zbus_chan_const_msg()</code> function, which provides a direct constant reference to channel A's message. It is quick, and no copy is needed here.</td>
</tr>
<tr>
<td>f</td>
<td>The VDED copies the message and sends that to MS1. MS1 preempts T1 and starts working. After that, the T1 regain MCU.</td>
</tr>
<tr>
<td>g</td>
<td>The VDED copies the message and sends that to MS2. MS2 preempts T1 and starts working. After that, the T1 regain MCU.</td>
</tr>
<tr>
<td>h</td>
<td>The VDED pushes the notification message to the queue of S1.</td>
</tr>
<tr>
<td>i</td>
<td>VDED finishes the publishing by unlocking channel A.</td>
</tr>
<tr>
<td>j, k, l</td>
<td>The S1 leaves the pending state since channel A is not locked. It gets in the CPU again and starts executing. As it did receive a notification from channel A, it performs a channel read (as simple as lock, memory copy, unlock), continues its execution, and goes out the CPU.</td>
</tr>
</tbody>
</table>

**HLP priority boost** ZBus implements the Highest Locker Protocol that relies on the observers’ thread priority to determine a temporary publisher priority. The protocol considers the channel's Highest Observer Priority (HOP); even if the observer is not waiting for a message on the channel, it is considered in the calculation. The VDED will elevate the publisher’s priority based on the HOP to ensure small latency and as few preemptions as possible.
**Note:** The priority boost is enabled by default. To deactivate it, you must set the `CONFIG_ZBUS_PRIORITY_BOOST` configuration.

**Warning:** ZBus priority boost does not consider runtime observers on the HOP calculations.

The figure below illustrates the actions performed during the VDED execution when T1 publishes to channel A. The scenario considers the priority boost feature and the following priorities: T1 < MS1 < MS2 < S1.

Fig. 26: ZBus VDED execution detail with priority boost enabled and for priority T1 < MS1 < MS2 < S1.

To properly use the priority boost, attaching the observer to a thread is necessary. When the subscriber is attached to a thread, it assumes its priority, and the priority boost algorithm will consider the observer's priority. The following code illustrates the thread-attaching function.

```c
ZBUS_SUBSCRIBER_DEFINE(s1, 4);
void s1_thread(void *ptr1, void *ptr2, void *ptr3)
{
    ARG_UNUSED(ptr1);
    ARG_UNUSED(ptr2);
    ARG_UNUSED(ptr3);

    const struct zbus_channel *chan;

    zbus_obs_attach_to_thread(&s1);

    while (1) {
        zbus_sub_wait(&s1, &chan, K_FOREVER);
        /* Subscriber implementation */
    }
}
```

(continues on next page)
K_THREAD_DEFINE(s1_id, CONFIG_MAIN_STACK_SIZE, s1_thread, NULL, NULL, NULL, 2, 0, 0);

On the above code, the `zbus_obs_attach_to_thread()` will set the s1 observer with priority two as the thread has that priority. It is possible to reverse that by detach the observer using `zbus_obs_detach_from_thread()`. Only enabled observers and observations will be considered on the channel HOP calculation. Masking a specific observation of a channel will affect the channel HOP.

In summary, the benefits of the feature are:

- The HLP is more effective for zbus than the mutexes priority inheritance;
- No bounded priority inversion will happen among the publisher and the observers;
- No other threads (that are not involved in the communication) with priority between T1 and S1 can preempt T1, avoiding unbounded priority inversion;
- Message subscribers will wait for the VDED to finish the message delivery process. So the VDED execution will be faster and more consistent;
- The HLP priority is dynamic and can change in execution;
- ZBus operations can be used inside ISRs;
- The priority boosting feature can be turned off, and plain semaphores can be used as the channel lock mechanism;
- The Highest Locker Protocol's major disadvantage, the Inheritance-related Priority Inversion, is acceptable in the zbus scenario since it will ensure a small bus latency.

**Limitations**

Based on the fact that developers can use zbus to solve many different problems, some challenges arise. ZBus will not solve every problem, so it is necessary to analyze the situation to be sure zbus is applicable. For instance, based on the zbus benchmark, it would not be well suited to a high-speed stream of bytes between threads. The `Pipe` kernel object solves this kind of need.

**Delivery guarantees**  ZBus always delivers the messages to the listeners and message subscribers. However, there are no message delivery guarantees for subscribers because zbus only sends the notification, but the message reading depends on the subscriber’s implementation. It is possible to increase the delivery rate by following design tips:

- Keep the listeners quick-as-possible (deal with them as ISRs). If some processing is needed, consider submitting a work to a work-queue;
- Try to give producers a high priority to avoid losses;
- Leave spare CPU for observers to consume data produced;
- Consider using message queues or pipes for intensive byte transfers.

**Warning:** ZBus uses `include/zephyr/net/buf.h` (network buffers) to exchange data with message subscribers. So, chose carefully the configurations `CONFIG_ZBUS_MSG_SUBSCRIBER_NET_BUF_POOL_SIZE` and `CONFIG_HEAP_MEM_POOL_SIZE`. They are crucial to a proper VDED execution (delivery guarantee) considering message subscribers.
**Warning:** Subscribers will receive only the reference of the changing channel. A data loss may be perceived if the channel is published twice before the subscriber reads it. The second publication overwrites the value from the first. Thus, the subscriber will receive two notifications, but only the last data is there.

**Message delivery sequence** The message delivery will follow the precedence:

1. Observers defined in a channel using the `ZBUS_CHAN_DEFINE` (following the definition sequence);
2. Observers defined using the `ZBUS_CHAN_ADD_OBS` based on the sequence priority (parameter of the macro);
3. The latest is the runtime observers in the addition sequence using the `zbus_chan_add_obs()`.

**Note:** The VDED will ignore all disabled observers or observations.

### 4.32.2 Usage

ZBus operation depends on channels and observers. Therefore, it is necessary to determine its message and observers list during the channel definition. A message is a regular C struct; the observer can be a subscriber (asynchronous), a message subscriber (asynchronous), or a listener (synchronous).

The following code defines and initializes a regular channel and its dependencies. This channel exchanges accelerometer data, for example.

```c
struct acc_msg {
    int x;
    int y;
    int z;
};
ZBUS_CHAN_DEFINE(acc_chan, /* Name */
    struct acc_msg, /* Message type */
    NULL, /* Validator */
    NULL, /* User Data */
    ZBUS_OBSERVERS(my_listener, my_subscriber, my_msg_subscriber), /* observers */
    ZBUS_MSG_INIT(.x = 0, .y = 0, .z = 0) /* Initial value */
);

void listener_callback_example(const struct zbus_channel *chan) {
    const struct acc_msg *acc;
    if (&acc_chan == chan) {
        acc = zbus_chan_const_msg(chan); // Direct message access
        LOG_DBG("From listener -> Acc x=%d, y=%d, z=%d", acc->x, acc->y, acc->z);
    }
}
ZBUS_LISTENER_DEFINE(my_listener, listener_callback_example);
ZBUS_LISTENER_DEFINE(my_listener2, listener_callback_example);
```

(continues on next page)
It is possible to add static observers to a channel using the `ZBUS_CHAN_ADD_OBS`. We call that a post-definition static observer. The command enables us to indicate an initialization priority that affects the observers’ initialization order. The sequence priority param only affects the post-definition static observers. There is no possibility to overwrite the message delivery sequence of the static observers.

**Note:** It is unnecessary to claim/lock a channel before accessing the message inside the listener since the event dispatcher calls listeners with the notifying channel already locked. Subscribers, however, must claim/lock that or use regular read operations to access the message after being notified.

Channels can have a **validator function** that enables a channel to accept only valid messages. Publish attempts invalidated by hard channels will return immediately with an error code. This allows original creators of a channel to exert some authority over other developers/publishers who may want to piggy-back on their channels. The following code defines and initializes a hard channel and its dependencies. Only valid messages can be published to a hard channel. It is possible because a validator function was passed to the channel’s definition. In this example, only messages with `move` equal to 0, -1, and 1 are valid. Publish function will discard all other values to `move`.
struct control_msg {
  int move;
};

bool control_validator(const void* msg, size_t msg_size) {
  const struct control_msg* cm = msg;
  bool is_valid = (cm->move == -1) || (cm->move == 0) || (cm->move == 1);
  return is_valid;
}

static int message_count = 0;

ZBUS_CHAN_DEFINE(control_chan, /* Name */
  struct control_msg, /* Message type */
  control_validator, /* Validator */
  &message_count, /* User data */
  ZBUS_OBSERVERS_EMPTY, /* observers */
  ZBUS_MSG_INIT(.move = 0) /* Initial value */
);

The following sections describe in detail how to use zbus features.

## Publishing to a channel

Messages are published to a channel in zbus by calling `zbus_chan_pub()`. For example, the following code builds on the examples above and publishes to channel `acc_chan`. The code is trying to publish the message `acc1` to channel `acc_chan`, and it will wait up to one second for the message to be published. Otherwise, the operation fails. As can be inferred from the code sample, it's OK to use stack allocated messages since VDED copies the data internally.

```c
struct acc_msg acc1 = {.x = 1, .y = 1, .z = 1};
zbus_chan_pub(&acc_chan, &acc1, K_SECONDS(1));
```

**Warning:** Only use this function inside an ISR with a `K_NO_WAIT` timeout.

## Reading from a channel

Messages are read from a channel in zbus by calling `zbus_chan_read()`. So, for example, the following code tries to read the channel `acc_chan`, which will wait up to 500 milliseconds to read the message. Otherwise, the operation fails.

```c
struct acc_msg acc = {0};
zbus_chan_read(&acc_chan, &acc, K_MSEC(500));
```

**Warning:** Only use this function inside an ISR with a `K_NO_WAIT` timeout.

**Warning:** Choose the timeout of `zbus_chan_read()` after receiving a notification from `zbus_sub_wait()` carefully because the channel will always be unavailable during the VDED execution. Using `K_NO_WAIT` for reading is highly likely to return a timeout error if there are more than one subscriber. For example, consider the VDED illustration again and notice how
Notifying a channel

It is possible to force zbus to notify a channel's observers by calling `zbus_chan_notify()`. For example, the following code builds on the examples above and forces a notification for the channel `acc_chan`. Note this can send events with no message, which does not require any data exchange. See the code example under *Claim and finish a channel* where this may become useful.

```c
zbus_chan_notify(&acc_chan, K_NO_WAIT);
```

**Warning:** Only use this function inside an ISR with a `K_NO_WAIT` timeout.

Declaring channels and observers

For accessing channels or observers from files other than its defining files, it is necessary to declare them by calling `ZBUS_CHAN_DECLARE` and `ZBUS_OBS_DECLARE`. In other words, zbus channel definitions and declarations with the same channel names in different files would point to the same (global) channel. Thus, developers should be careful about existing channels, and naming new channels or linking will fail. It is possible to declare more than one channel or observer on the same call. The following code builds on the examples above and displays the defined channels and observers.

```c
ZBUS_OBS_DECLARE(my_listener, my_subscriber);
ZBUS_CHAN_DECLARE(acc_chan, version_chan);
```

Iterating over channels and observers

ZBus subsystem also implements *Iterable Sections* for channels and observers, for which there are supporting APIs like `zbus_iterate_over_channels()`, `zbus_iterate_over_channels_with_user_data()`, `zbus_iterate_over_observers()` and `zbus_iterate_over_observers_with_user_data()`. This feature enables developers to call a procedure over all declared channels, where the procedure parameter is a `zbus_channel`. The execution sequence is in the alphabetical name order of the channels (see *Iterable Sections* documentation for details). ZBus also implements this feature for `zbus_observer`.

```c
static bool print_channel_data_iterator(const struct zbus_channel *chan, void *user_data)
{
    int *count = user_data;
    
    LOG_INF("%d - Channel %s:", *count, zbus_chan_name(chan));
    LOG_INF(" Message size: %d", zbus_chan_msg_size(chan));
    LOG_INF(" Observers:");
    ++(*count);
    
    struct zbus_channel_observation *observation;
    
    for(int16_t i = *chan->observers_start_idx, limit = *chan->observers_end_idx; i < limit; ++i) {
(continues on next page)```
STRUCT_SECTION_GET(zbus_channel_observation, i, &observation);

LOG_INF("    - %s", observation->obs->name);

struct zbus_observer_node *obs_nd, *tmp;
SYS_SLIST_FOR_EACH_CONTAINER_SAFE(chan->observers, obs_nd, tmp, node) {
    LOG_INF("    - %s", obs_nd->obs->name);
}
return true;

static bool print_observer_data_iterator(const struct zbus_observer *obs, void *user_data)
{
    int *count = user_data;

    LOG_INF("%d - %s %s", *count, obs->queue ? "Subscriber" : "Listener", zbus_obs_
        ->name(obs));
    ++(*count);
    return true;
}

int main(void)
{
    int count = 0;

    LOG_INF("Channel list:");
    zbus_iterate_over_channels_with_user_data(print_channel_data_iterator, &count);
    count = 0;
    LOG_INF("Observers list:");
    zbus_iterate_over_observers_with_user_data(print_observer_data_iterator, &count);
    return 0;
}

The code will log the following output:

D: Channel list:
D: 0 - Channel acc_chan:
D:   Message size: 12
D:   Observers:
D:     - my_listener
D:     - my_subscriber
D: 1 - Channel version_chan:
D:   Message size: 4
D:   Observers:
D:   Observers list:
D: 0 - Listener my_listener
D: 1 - Subscriber my_subscriber
Advanced channel control

ZBus was designed to be as flexible and extensible as possible. Thus, there are some features designed to provide some control and extensibility to the bus.

Listeners message access For performance purposes, listeners can access the receiving channel message directly since they already have the channel locked for it. To access the channel's message, the listener should use the `zbus_chan_const_msg()` because the channel passed as an argument to the listener function is a constant pointer to the channel. The const pointer return type tells developers not to modify the message.

```c
void listener_callback_example(const struct zbus_channel *chan)
{
    const struct acc_msg *acc;
    if (&acc_chan == chan) {
        acc = zbus_chan_const_msg(chan); // Use this
        // instead of zbus_chan_read(chan, &acc, K_MSEC(200))
        // or zbus_chan_msg(chan)
        LOG_DBG("From listener -> Acc x=%d, y=%d, z=%d", acc->x, acc->y, acc->z);
    }
}
```

User Data It is possible to pass custom data into the channel's `user_data` for various purposes, such as writing channel metadata. That can be achieved by passing a pointer to the channel definition macro's `user_data` field, which will then be accessible by others. Note that `user_data` is individual for each channel. Also, note that `user_data` access is not thread-safe. For thread-safe access to `user_data`, see the next section.

Claim and finish a channel To take more control over channels, two functions were added `zbus_chan_claim()` and `zbus_chan_finish()`. With these functions, it is possible to access the channel's metadata safely. When a channel is claimed, no actions are available to that channel. After finishing the channel, all the actions are available again.

**Warning:** Never change the fields of the channel struct directly. It may cause zbus behavior inconsistencies and scheduling issues.

**Warning:** Only use this function inside an ISR with a `K_NO_WAIT` timeout.

The following code builds on the examples above and claims the `acc_chan` to set the `user_data` to the channel. Suppose we would like to count how many times the channels exchange messages. We defined the `user_data` to have the 32 bits integer. This code could be added to the listener code described above.

```c
if (!zbus_chan_claim(&acc_chan, K_MSEC(200))) {
    int *message_counting = (int *) zbus_chan_user_data(&acc_chan);
    *message_counting += 1;
    zbus_chan_finish(&acc_chan);
}
```

The following code has the exact behavior of the code in *Publishing to a channel*. 
if (!zbus_chan_claim(&acc_chan, K_MSEC(200))) {
    struct acc_msg *acc1 = (struct acc_msg *) zbus_chan_msg(&acc_chan);
    acc1->x = 1;
    acc1->y = 1;
    acc1->z = 1;
    zbus_chan_finish(&acc_chan);
    zbus_chan_notify(&acc_chan, K_SECONDS(1));
}

The following code has the exact behavior of the code in *Reading from a channel*.

if (!zbus_chan_claim(&acc_chan, K_MSEC(200))) {
    const struct acc_msg *acc1 = (const struct acc_msg *) zbus_chan_const_msg(&acc_chan);
    // access the acc_msg fields directly.
    zbus_chan_finish(&acc_chan);
}

**Runtime observer registration**  It is possible to add observers to channels in runtime. This feature uses the heap to allocate the nodes dynamically. The heap size limits the number of dynamic observers zbus can create. Therefore, set the `CONFIG_ZBUS_RUNTIME_OBSERVERS` to enable the feature. It is possible to adjust the heap size by changing the configuration `CONFIG_HEAP_MEM_POOL_SIZE`. The following example illustrates the runtime registration usage.

```c
ZBUS_LISTENER_DEFINE(my_listener, callback);
// ...
void thread_entry(void) {
    // ...
    /* Adding the observer to channel chan1 */
    zbus_chan_add_obs(&chan1, &my_listener, K_NO_WAIT);
    /* Removing the observer from channel chan1 */
    zbus_chan_rm_obs(&chan1, &my_listener, K_NO_WAIT);
}
```

### 4.32.3 Samples

For a complete overview of zbus usage, take a look at the samples. There are the following samples available:

- zbus-hello-world illustrates the code used above in action;
- zbus-work-queue shows how to define and use different kinds of observers. Note there is an example of using a work queue instead of executing the listener as an execution option;
- zbus-msg-subscriber illustrates how to use message subscribers;
- zbus-dyn-channel demonstrates how to use dynamically allocated exchanging data in zbus;
- zbus-uart-bridge shows an example of sending the operation of the channel to a host via serial;
- zbus-remote-mock illustrates how to implement an external mock (on the host) to send and receive messages to and from the bus;
- zbus-priority-boost illustrates zbus priority boost feature with a priority inversion scenario;
- zbus-runtime-obs-registration illustrates a way of using the runtime observer registration feature;
- zbus-confirmed-channel implements a way of implement confirmed channel only with subscribers;
- zbus-benchmark implements a benchmark with different combinations of inputs.
4.32.4 Suggested Uses

Use zbus to transfer data (messages) between threads in one-to-one, one-to-many, and many-to-many synchronously or asynchronously. Choosing the proper observer type is crucial. Use subscribers for scenarios that can tolerate message losses and duplications; when they cannot, use message subscribers (if you need a thread) or listeners (if you need to be lean and fast). In addition to the listener, another asynchronous message processing mechanism (like message queues) may be necessary to retain the pending message until it gets processed.

Note: ZBus can be used to transfer streams from the producer to the consumer. However, this can increase zbus' communication latency. So maybe consider a Pipe a good alternative for this communication topology.

4.32.5 Configuration Options

For enabling zbus, it is necessary to enable the CONFIG_ZBUS option.

Related configuration options:

- CONFIG_ZBUS_PRIORITY_BOOST zbus Highest Locker Protocol implementation;
- CONFIG_ZBUS_CHANNELS_SYS_INIT_PRIORITY determine the SYS_INIT priority used by zbus to organize the channels observations by channel;
- CONFIG_ZBUS_CHANNEL_NAME enables the name of channels to be available inside the channels metadata. The log uses this information to show the channels' names;
- CONFIG_ZBUS_OBSERVER_NAME enables the name of observers to be available inside the channels metadata;
- CONFIG_ZBUS_MSG_SUBSCRIBER enables the message subscriber observer type;
- CONFIG_ZBUS_MSG_SUBSCRIBER_BUF_ALLOC_DYNAMIC uses the heap to allocate message buffers;
- CONFIG_ZBUS_MSG_SUBSCRIBER_BUF_ALLOC_STATIC uses the stack to allocate message buffers;
- CONFIG_ZBUS_MSG_SUBSCRIBER_NET_BUF_POOL_SIZE the available number of message buffers to be used simultaneously;
- CONFIG_ZBUS_MSG_SUBSCRIBER_NET_BUF_STATIC_DATA_SIZE the biggest message of zbus channels to be transported into a message buffer;
- CONFIG_ZBUS_RUNTIME_OBSERVERS enables the runtime observer registration.

4.32.6 API Reference

Related code samples

Benchmarking

Measure the time for sending 256KB from a producer to N consumers.

Confirmed channel

Use confirmed zbus channels to ensure all subscribers consume a message.

Dynamic channel

Use zbus channels with dynamically allocated messages.
Message subscriber
   Use zbus message subscribers to listen to messages published to channels.

Remote mock sample
   Publish to a zbus instance using UART as a bridge.

Runtime observer registration
   Use zbus' runtime observer registration to filter data generated by a producer.

UART bridge
   Redirect channel events to the host over UART.

Work queue
   Use a work queue to process zbus messages in various ways.

zbus Hello World
   Make three threads talk to each other using zbus.

zbus Priority Boost
   Illustrates zbus priority boost feature with a priority inversion scenario.

---

**group zbus apis**

Zbus API.

**Defines**

**ZBUS_CHAN_ADD_OBS_WITH_MASK(_chan, _obs, _masked, _prio)**
   Add a static channel observeration.
   This macro initializes a channel observation by receiving the channel and the observer.
   **Parameters**
   - _chan – Channel instance.
   - _obs – Observer instance.
   - _masked – Observation state.
   - _prio – Observer notification sequence priority.

**ZBUS_CHAN_ADD_OBS(_chan, _obs, _prio)**
   Add a static channel observeration.
   This macro initializes a channel observation by receiving the channel and the observer.
   **Parameters**
   - _chan – Channel instance.
   - _obs – Observer instance.
   - _prio – Observer notification sequence priority.

**ZBUS_OBS_DECLARE(...)**
   This macro list the observers to be used in a file.
   Internally, it declares the observers with the extern statement. Note it is only necessary when the observers are declared outside the file.

**ZBUS_CHAN_DECLARE(...)**
   This macro list the channels to be used in a file.
   Internally, it declares the channels with the extern statement. Note it is only necessary when the channels are declared outside the file.
ZBUS_OBSERVERS_EMPTY
This macro indicates the channel has no observers.

ZBUS_OBSERVERS(...)
This macro indicates the channel has listed observers.
Note the sequence of observer notification will follow the same as listed.

ZBUS_CHAN_DEFINE(_name, _type, _validator, _user_data, _observers, _init_val)
Zbus channel definition.
This macro defines a channel.

See also:

struct zbus_channel

Parameters

• _name – The channel's name.
• _type – The Message type. It must be a struct or union.
• _validator – The validator function.
• _user_data – A pointer to the user data.
• _observers – The observers list. The sequence indicates the priority of
  the observer. The first the highest priority.
• _init_val – The message initialization.

ZBUS_MSG_INIT(_val, ...)
Initialize a message.
This macro initializes a message by passing the values to initialize the message struct
or union.

Parameters

• _val – [in] Variadic with the initial values. ZBUS_INIT(0) means {0}, as
  ZBUS_INIT(a=10, .b=30) means {.a=10, .b=30}.

ZBUS_SUBSCRIBER_DEFINE_WITH_ENABLE(_name, _queue_size, _enable)
Define and initialize a subscriber.
This macro defines an observer of subscriber type. It defines a message queue where
the subscriber will receive the notification asynchronously, and initialize the struct
zbus_observer defining the subscriber.

Parameters

• _name – [in] The subscriber's name.
• _enable – [in] The subscriber initial enable state.

ZBUS_SUBSCRIBER_DEFINE(_name, _queue_size)
Define and initialize a subscriber.
This macro defines an observer of subscriber type. It defines a message queue where
the subscriber will receive the notification asynchronously, and initialize the struct
zbus_observer defining the subscriber. The subscribers are defined in the enabled
state with this macro.
Parameters


\texttt{ZBUS\_LISTENER\_DEFINE\_WITH\_ENABLE(\_name, \_cb, \_enable)}

Define and initialize a listener.

This macro defines an observer of listener type. This macro establishes the callback where the listener will be notified synchronously, and initialize the struct \texttt{zbus\_observer} defining the listener.

Parameters


\texttt{ZBUS\_LISTENER\_DEFINE(\_name, \_cb)}

Define and initialize a listener.

This macro defines an observer of listener type. This macro establishes the callback where the listener will be notified synchronously and initialize the struct \texttt{zbus\_observer} defining the listener. The listeners are defined in the enabled state with this macro.

Parameters


\texttt{ZBUS\_MSG\_SUBSCRIBER\_DEFINE\_WITH\_ENABLE(\_name, \_enable)}

Define and initialize a message subscriber.

This macro defines an observer of \texttt{ZBUS\_OBSERVER\_SUBSCRIBER\_TYPE} type. It defines a FIFO where the subscriber will receive the message asynchronously and initialize the \texttt{zbus\_observer} defining the subscriber.

Parameters


\texttt{ZBUS\_MSG\_SUBSCRIBER\_DEFINE(\_name)}

Define and initialize an enabled message subscriber.

This macro defines an observer of message subscriber type. It defines a FIFO where the subscriber will receive the message asynchronously and initialize the \texttt{zbus\_observer} defining the subscriber. The message subscribers are defined in the enabled state with this macro.

Parameters


Enums

\texttt{enum zbus\_observer\_type}

Type used to represent an observer type.

A observer can be a listener or a subscriber.
Values:

enumerator ZBUS_OBSERVER_LISTENER_TYPE

enumerator ZBUS_OBSERVER_SUBSCRIBER_TYPE

enumerator ZBUS_OBSERVER_MSG_SUBSCRIBER_TYPE

Functions

int zbus_chan_pub(const struct zbus_channel *chan, const void *msg, k_timeout_t timeout)

Publish to a channel.

This routine publishes a message to a channel.

Parameters

• chan – The channel's reference.

• msg – Reference to the message where the publish function copies the channel's message data from.

• timeout – Waiting period to publish the channel, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

• 0 – Channel published.

• -ENOMEM – The message is invalid based on the validator function or some of the observers could not receive the notification.

• -EBUSY – The channel is busy.

• -EAGAIN – Waiting period timed out.

• -EFAULT – A parameter is incorrect, the notification could not be sent to one or more observer, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_chan_read(const struct zbus_channel *chan, void *msg, k_timeout_t timeout)

Read a channel.

This routine reads a message from a channel.

Parameters


• msg – [out] Reference to the message where the read function copies the channel's message data to.

• timeout – [in] Waiting period to read the channel, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

• 0 – Channel read.

• -EBUSY – The channel is busy.

• -EAGAIN – Waiting period timed out.
• -EFAULT – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_chan_claim(const struct zbus_channel *chan, k_timeout_t timeout)
Claim a channel.

This routine claims a channel. During the claiming period the channel is blocked for publishing, reading, notifying or claiming again. Finishing is the only available action.

**Warning:** After calling this routine, the channel cannot be used by other thread until the zbus_chan_finish routine is performed.

**Warning:** This routine should only be called once before a zbus_chan_finish.

**Parameters**
- **timeout** – [in] Waiting period to claim the channel, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**
- **0** – Channel claimed.
- **-EBUSY** – The channel is busy.
- **-EAGAIN** – Waiting period timed out.
- **-EFAULT** – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_chan_finish(const struct zbus_channel *chan)
Finish a channel claim.

This routine finishes a channel claim. After calling this routine with success, the channel will be able to be used by other thread.

**Warning:** This routine must only be used after a zbus_chan_claim.

**Parameters**
- **chan** – The channel's reference.

**Return values**
- **0** – Channel finished.
- **-EFAULT** – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_chan_notify(const struct zbus_channel *chan, k_timeout_t timeout)
Force a channel notification.

This routine forces the event dispatcher to notify the channel's observers even if the message has no changes. Note this function could be useful after claiming/finishing actions.
Parameters

- chan – The channel's reference.
- timeout – Waiting period to notify the channel, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

- 0 – Channel notified.
- -EBUSY – The channel's semaphore returned without waiting.
- -EAGAIN – Timeout to take the channel's semaphore.
- -ENOMEM – There is not more buffer on the message buffers pool.
- -EFAULT – A parameter is incorrect, the notification could not be sent to one or more observer, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

static inline const char * zbus_chan_name (const struct zbus_channel *chan)
Get the channel's name.
This routine returns the channel's name reference.

Parameters

- chan – The channel's reference.

Returns

Channel's name reference.

static inline void * zbus_chan_msg (const struct zbus_channel *chan)
Get the reference for a channel message directly.
This routine returns the reference of a channel message.

Warning: This function must only be used directly for already locked channels. This can be done inside a listener for the receiving channel or after claim a channel.

Parameters

- chan – The channel's reference.

Returns

Channel's message reference.

static inline const void * zbus_chan_const_msg (const struct zbus_channel *chan)
Get a constant reference for a channel message directly.
This routine returns a constant reference of a channel message. This should be used inside listeners to access the message directly. In this way zbus prevents the listener of changing the notifying channel's message during the notification process.

Warning: This function must only be used directly for already locked channels. This can be done inside a listener for the receiving channel or after claim a channel.

Parameters

- chan – The channel's constant reference.
Returns
A constant channel's message reference.

```c
static inline uint16_t zbus_chan_msg_size(const struct zbus_channel *chan)
```
Get the channel's message size.
This routine returns the channel's message size.

Parameters
- chan – The channel's reference.

Returns
Channel's message size.

```c
static inline void *zbus_chan_user_data(const struct zbus_channel *chan)
```
Get the channel's user data.
This routine returns the channel's user data.

Parameters
- chan – The channel's reference.

Returns
Channel's user data.

```c
int zbus_chan_add_obs(const struct zbus_channel *chan, const struct zbus_observer *obs,
                       k_timeout_t timeout)
```
Add an observer to a channel.
This routine adds an observer to the channel.

Parameters
- chan – The channel's reference.
- obs – The observer's reference to be added.
- timeout – Waiting period to add an observer, or one of the special values K_NO_WAIT and K_FOREVER.

Return values
- 0 – Observer added to the channel.
- -EALREADY – The observer is already present in the channel's runtime observers list.
- -ENOMEM – Returned without waiting.
- -EAGAIN – Waiting period timed out.
- -EINVAL – Some parameter is invalid.

```c
int zbus_chan_rm_obs(const struct zbus_channel *chan, const struct zbus_observer *obs,
                      k_timeout_t timeout)
```
Remove an observer from a channel.
This routine removes an observer to the channel.

Parameters
- chan – The channel's reference.
- obs – The observer's reference to be removed.
- timeout – Waiting period to remove an observer, or one of the special values K_NO_WAIT and K_FOREVER.

Return values
• 0 – Observer removed to the channel.
• -EINVAL – Invalid data supplied.
• -EBUSY – Returned without waiting.
• -EAGAIN – Waiting period timed out.
• -ENODATA – no observer found in channel’s runtime observer list.
• -ENOMEM – Returned without waiting.

int zbus_obs_set_enable(struct zbus_observer *obs, bool enabled)
Change the observer state.
This routine changes the observer state. A channel when disabled will not receive
notifications from the event dispatcher.

Parameters
• enabled – [in] State to be. When false the observer stops to receive notifi-
cations.

Return values
• 0 – Observer set enable.
• -EFAULT – A parameter is incorrect, or the function context is invalid
(inside an ISR). The function only returns this value when the CON-
FIG_ZBUS_ASSERT_MOCK is enabled.

static inline int zbus_obs_is_enabled(struct zbus_observer *obs, bool *enable)
Get the observer state.
This routine retrieves the observer state.

Parameters
• enable – [out] The boolean output’s reference.

Returns
Observer state.

int zbus_obs_set_chan_notification_mask(const struct zbus_observer *obs, const struct
zbus_channel *chan, bool masked)
Mask notifications from a channel to an observer.
The observer can mask notifications from a specific observing channel by calling this
function.

Parameters
• obs – The observer’s reference to be added.
• chan – The channel’s reference.
• masked – The mask state. When the mask is true, the observer will not
receive notifications from the channel.

Return values
• 0 – Channel notifications masked to the observer.
• -ESRCH – No observation found for the related pair chan/obs.
• -EINVAL – Some parameter is invalid.
int zbus_obs_is_chan_notification_masked(const struct zbus_observer *obs, const struct zbus_channel *chan, bool *masked)

Get the notifications masking state from a channel to an observer.

Parameters

- obs – The observer's reference to be added.
- chan – The channel's reference.
- masked – [out] The mask state. When the mask is true, the observer will not receive notifications from the channel.

Return values

- 0 – Retrieved the masked state.
- -ESRCH – No observation found for the related pair chan/obs.
- -EINVAL – Some parameter is invalid.

static inline const char *zbus_obs_name(const struct zbus_observer *obs)

Get the observer’s name.

This routine returns the observer’s name reference.

Parameters

- obs – The observer’s reference.

Returns

The observer’s name reference.

int zbus_obs_attach_to_thread(const struct zbus_observer *obs)

Set the observer thread priority by attaching it to a thread.

Parameters


Return values

- 0 – Observer detached from the thread.
- -EFAULT – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_obs_detach_from_thread(const struct zbus_observer *obs)

Clear the observer thread priority by detaching it from a thread.

Parameters


Return values

- 0 – Observer detached from the thread.
- -EFAULT – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_sub_wait(const struct zbus_observer *sub, const struct zbus_channel **chan, k_timeout_t timeout)

Wait for a channel notification.

This routine makes the subscriber to wait a notification. The notification comes as a channel reference.

Parameters
• chan – [out] The notification channel’s reference.
• timeout – [in] Waiting period for a notification arrival, or one of the special values K_NO_WAIT and K_FOREVER.

Return values
• 0 – Notification received.
• -ENOMSG – Returned without waiting.
• -EAGAIN – Waiting period timed out.
• -EINVAL – The observer is not a subscriber.
• -EFAULT – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

```c
int zbus_sub_wait_msg(const struct zbus_observer *sub, const struct zbus_channel **chan, void *msg, k_timeout_t timeout)
```

Wait for a channel message.

This routine makes the subscriber wait for the new message in case of channel publication.

Parameters
• chan – [out] The notification channel’s reference.
• msg – [out] A reference to a copy of the published message.
• timeout – [in] Waiting period for a notification arrival, or one of the special values, K_NO_WAIT and K_FOREVER.

Return values
• 0 – Message received.
• -EINVAL – The observer is not a subscriber.
• -ENOMSG – Could not retrieve the net_buf from the subscriber FIFO.
• -EINVAL – Received an invalid channel reference.
• -EFAULT – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

```c
bool zbus_iterate_over_channels(bool (*iterator_func)(const struct zbus_channel *chan))
```

Iterate over channels.

Enables the developer to iterate over the channels giving to this function an iterator_func which is called for each channel. If the iterator_func returns false all the iteration stops.

Parameters
• iterator_func – [in] The function that will be execute on each iteration.

Return values
• true – Iterator executed for all channels.
• false – Iterator could not be executed. Some iterate returned false.
Iterate over channels with user data.
Enables the developer to iterate over the channels giving to this function an iterator_func which is called for each channel. If the iterator_func returns false all the iteration stops.

**Parameters**
- iterator_func – [in] The function that will be execute on each iteration.
- user_data – [in] The user data that can be passed in the function.

**Return values**
- true – Iterator executed for all channels.
- false – Iterator could not be executed. Some iterate returned false.

Iterate over observers.
Enables the developer to iterate over the observers giving to this function an iterator_func which is called for each observer. If the iterator_func returns false all the iteration stops.

**Parameters**
- iterator_func – [in] The function that will be execute on each iteration.

**Return values**
- true – Iterator executed for all channels.
- false – Iterator could not be executed. Some iterate returned false.

Iterate over observers with user data.
Enables the developer to iterate over the observers giving to this function an iterator_func which is called for each observer. If the iterator_func returns false all the iteration stops.

**Parameters**
- iterator_func – [in] The function that will be execute on each iteration.
- user_data – [in] The user data that can be passed in the function.

**Return values**
- true – Iterator executed for all channels.
- false – Iterator could not be executed. Some iterate returned false.

`struct zbus_channel_data`

`#include <zbus.h>` Type used to represent a channel mutable data.
Every channel has a `zbus_channel_data` structure associated.
Public Members

int16_t observers_start_idx
    Static channel observer list start index.
    Considering the ITERABLE SECTIONS allocation order.

int16_t observers_end_idx
    Static channel observer list end index.
    Considering the ITERABLE SECTIONS allocation order.

struct k_sem sem
    Access control semaphore.
    Points to the semaphore used to avoid race conditions for accessing the channel.

sys_slist_t observers
    Channel observer list.
    Represents the channel's observers list, it can be empty or have listeners and subscribers mixed in any sequence. It can be changed in runtime.

struct zbus_channel
    #include <zbus.h> Type used to represent a channel.
    Every channel has a zbus_channel structure associated used to control the channel access and usage.

Public Members

const char *const name
    Channel name.

void *const message
    Message reference.
    Represents the message's reference that points to the actual shared memory region.

const size_t message_size
    Message size.
    Represents the channel's message size.

void *const user_data
    User data available to extend zbus features.
    The channel must be claimed before using this field.

bool (*const validator)(const void *msg, size_t msg_size)
    Message validator.
    Stores the reference to the function to check the message validity before actually performing the publishing. No invalid messages can be published. Every message is valid when this field is empty.
struct zbus_channel_data *const data
    Mutable channel data struct.

struct zbus_observer_data
    #include <zbus.h>

Public Members

bool enabled
    Enabled flag.
    Indicates if observer is receiving notification.

struct zbus_observer
    #include <zbus.h> Type used to represent an observer.
    Every observer has an representation structure containing the relevant information. An observer is a code portion interested in some channel. The observer can be notified synchronously or asynchronously and it is called listener and subscriber respectively. The observer can be enabled or disabled during runtime by change the enabled boolean field of the structure. The listeners have a callback function that is executed by the bus with the index of the changed channel as argument when the notification is sent. The subscribers have a message queue where the bus enqueues the index of the changed channel when a notification is sent.

See also:
    zbus_obs_set_enable function to properly change the observer's enabled field.

Public Members

const char *const name
    Observer name.

enum zbus_observer_type type
    Type indication.

struct zbus_observer_data *const data
    Mutable observer data struct.

struct k_msgq *const queue
    Observer message queue.
    It turns the observer into a subscriber.

void (*const callback)(const struct zbus_channel *chan)
    Observer callback function.
    It turns the observer into a listener.
struct kfifo *const message_fifo
    Observer message FIFO.
    It turns the observer into a message subscriber. It only exists if the CONFIG_ZBUS_MSG_SUBSCRIBER is enabled.

4.33 Miscellaneous

4.33.1 Checksum APIs

CRC

group crc

Enums

enum crc_type
    CRC algorithm enumeration.
    These values should be used with the CRC dispatch function.
    Values:

    enumerator CRC4
        Use crc4.

    enumerator CRC4_TI
        Use crc4_ti.

    enumerator CRC7_BE
        Use crc7_be.

    enumerator CRC8
        Use crc8.

    enumerator CRC8_CCITT
        Use crc8_ccitt.

    enumerator CRC16
        Use crc16.

    enumerator CRC16_ANSI
        Use crc16_ansi.

    enumerator CRC16_CCITT
        Use crc16_ccitt.
enumerator CRC16_ITU_T
Use `crc16_itu_t`.

enumerator CRC32_C
Use `crc32_c`.

enumerator CRC32_IEEE
Use `crc32_ieee`.

Functions

```c
uint16_t crc16(uint16_t poly, uint16_t seed, const uint8_t *src, size_t len)
```

Generic function for computing a CRC-16 without input or output reflection.

Compute CRC-16 by passing in the address of the input, the input length and polynomial used in addition to the initial value. This is $O(n \times 8)$ where $n$ is the length of the buffer provided. No reflection is performed.

**Note:** If you are planning to use a CRC based on poly 0x1012 the functions `crc16_itu_t()` is faster and thus recommended over this one.

**Parameters**
- **poly** – The polynomial to use omitting the leading $x^{16}$ coefficient
- **seed** – Initial value for the CRC computation
- **src** – Input bytes for the computation
- **len** – Length of the input in bytes

**Returns**
The computed CRC16 value (without any XOR applied to it)

```c
uint16_t crc16_reflect(uint16_t poly, uint16_t seed, const uint8_t *src, size_t len)
```

Generic function for computing a CRC-16 with input and output reflection.

Compute CRC-16 by passing in the address of the input, the input length and polynomial used in addition to the initial value. This is $O(n \times 8)$ where $n$ is the length of the buffer provided. Both input and output are reflected.

The following checksums can, among others, be calculated by this function, depending on the value provided for the initial seed and the value the final calculated CRC is XORed with:

- CRC-16/ANSI, CRC-16/MODBUS, CRC-16/USB, CRC-16/IBM, CRC-16/IBM
poly: 0x8005 (0xA001) initial seed: 0xffff, xor output: 0x0000

**Note:** If you are planning to use a CRC based on poly 0x1012 the function `crc16_ccitt()` is faster and thus recommended over this one.

**Parameters**
• **poly** – The polynomial to use omitting the leading \(x^{16}\) coefficient. Important: please reflect the poly. For example, use 0xA001 instead of 0x8005 for CRC-16-MODBUS.

• **seed** – Initial value for the CRC computation

• **src** – Input bytes for the computation

• **len** – Length of the input in bytes

**Returns**
The computed CRC16 value (without any XOR applied to it)

```
uint8_t crc8(const uint8_t *src, size_t len, uint8_t polynomial, uint8_t initial_value, bool reversed)
```

Generic function for computing CRC 8.

Compute CRC 8 by passing in the address of the input, the input length and polynomial used in addition to the initial value.

**Parameters**

• **src** – Input bytes for the computation

• **len** – Length of the input in bytes

• **polynomial** – The polynomial to use omitting the leading \(x^8\) coefficient

• **initial_value** – Initial value for the CRC computation

• **reversed** – Should we use reflected/reversed values or not

**Returns**
The computed CRC8 value

```
uint16_t crc16_ccitt(uint16_t seed, const uint8_t *src, size_t len)
```

Compute the checksum of a buffer with polynomial 0x1021, reflecting input and output.

This function is able to calculate any CRC that uses 0x1021 as it polynomial and requires reflecting both the input and the output. It is a fast variant that runs in \(O(n)\) time, where \(n\) is the length of the input buffer.

The following checksums can, among others, be calculated by this function, depending on the value provided for the initial seed and the value the final calculated CRC is XORed with:

- CRC-16/CCITT, CRC-16/CCITT-TRUE, CRC-16/KERMIT [https://reveng.sourceforge.io/crc-catalogue/16.htm#crc.cat.crc-16-kermit](https://reveng.sourceforge.io/crc-catalogue/16.htm#crc.cat.crc-16-kermit) initial seed: 0x0000, xor output: 0x0000


**Note:** To calculate the CRC across non-contiguous blocks use the return value from block N-1 as the seed for block N.

**Parameters**

• **seed** – Value to seed the CRC with


- **src** – Input bytes for the computation
- **len** – Length of the input in bytes

**Returns**

The computed CRC16 value (without any XOR applied to it)

```c
uint16_t crc16_itu_t(uint16_t seed, const uint8_t *src, size_t len)
```

Compute the checksum of a buffer with polynomial 0x1021, no reflection of input or output.

This function is able to calculate any CRC that uses 0x1021 as it polynomial and requires no reflection on both the input and the output. It is a fast variant that runs in O(n) time, where n is the length of the input buffer.

The following checksums can, among others, be calculated by this function, depending on the value provided for the initial seed and the value the final calculated CRC is XORed with:

- **CRC-16/XMODEM, CRC-16/ACORN, CRC-16/LTE**
  - Initial seed: 0x0000, XOR output: 0x0000

- **CRC16/CCITT-FALSE, CRC-16/IBM-3740, CRC-16/AUTOSAR**
  - Initial seed: 0xffff, XOR output: 0x0000

- **CRC-16/GSM**
  - Initial seed: 0x0000, XOR output: 0xffff


**Note:** To calculate the CRC across non-contiguous blocks use the return value from block N-1 as the seed for block N.

---

**Parameters**

- **seed** – Value to seed the CRC with
- **src** – Input bytes for the computation
- **len** – Length of the input in bytes

**Returns**

The computed CRC16 value (without any XOR applied to it)

```c
static inline uint16_t crc16_ansi(const uint8_t *src, size_t len)
```

Compute the ANSI (or Modbus) variant of CRC-16.

The ANSI variant of CRC-16 uses 0x8005 (0xA001 reflected) as its polynomial with the initial * value set to 0xffff.

**Parameters**

- **src** – Input bytes for the computation
- **len** – Length of the input in bytes

**Returns**

The computed CRC16 value
uint32_t crc32_ieee(const uint8_t *data, size_t len)
Generate IEEE conform CRC32 checksum.

Parameters
• data – Pointer to data on which the CRC should be calculated.
• len – Data length.

Returns
CRC32 value.

uint32_t crc32_ieee_update(uint32_t crc, const uint8_t *data, size_t len)
Update an IEEE conforming CRC32 checksum.

Parameters
• crc – CRC32 checksum that needs to be updated.
• data – Pointer to data on which the CRC should be calculated.
• len – Data length.

Returns
CRC32 value.

uint32_t crc32_c(uint32_t crc, const uint8_t *data, size_t len, bool first_pkt, bool last_pkt)
Calculate CRC32C (Castagnoli) checksum.

Parameters
• crc – CRC32C checksum that needs to be updated.
• data – Pointer to data on which the CRC should be calculated.
• len – Data length.
• first_pkt – Whether this is the first packet in the stream.
• last_pkt – Whether this is the last packet in the stream.

Returns
CRC32 value.

uint8_t crc8_ccitt(uint8_t initial_value, const void *buf, size_t len)
Compute CCITT variant of CRC 8.
Normal CCITT variant of CRC 8 is using 0x07.

Parameters
• initial_value – Initial value for the CRC computation
• buf – Input bytes for the computation
• len – Length of the input in bytes

Returns
The computed CRC8 value

uint8_t crc7_be(uint8_t seed, const uint8_t *src, size_t len)
Compute the CRC-7 checksum of a buffer.
See JESD84-A441. Used by the MMC protocol. Uses 0x09 as the polynomial with no
reflection. The CRC is left justified, so bit 7 of the result is bit 6 of the CRC.

Parameters
• seed – Value to seed the CRC with
• src – Input bytes for the computation
• `len` – Length of the input in bytes

**Returns**
The computed CRC7 value

```c
uint8_t crc4_ti(uint8_t seed, const uint8_t *src, size_t len)
```

Compute the CRC-4 checksum of a buffer.

Used by the TMAG5170 sensor. Uses 0x03 as the polynomial with no reflection. 4 most significant bits of the CRC result will be set to zero.

**Parameters**

- `seed` – Value to seed the CRC with
- `src` – Input bytes for the computation
- `len` – Length of the input in bytes

**Returns**
The computed CRC4 value

```c
uint8_t crc4(const uint8_t *src, size_t len, uint8_t polynomial, uint8_t initial_value, bool reversed)
```

Generic function for computing CRC 4.

Compute CRC 4 by passing in the address of the input, the input length and polynomial used in addition to the initial value. The input buffer must be aligned to a whole byte. It is guaranteed that 4 most significant bits of the result will be set to zero.

**Parameters**

- `src` – Input bytes for the computation
- `len` – Length of the input in bytes
- `polynomial` – The polynomial to use omitting the leading x^4 coefficient
- `initial_value` – Initial value for the CRC computation
- `reversed` – Should we use reflected/reversed values or not

**Returns**
The computed CRC4 value

```c
static inline uint32_t crc_by_type(enum crc_type type, const uint8_t *src, size_t len, uint32_t seed, uint32_t poly, bool reflect, bool first, bool last)
```

Compute a CRC checksum, in a generic way.

This is a dispatch function that calls the individual CRC routine determined by `type`.

For 7, 8, and 16-bit CRCs, the relevant `seed` and `poly` values should be passed in via the least-significant byte(s).

Similarly, for 7, 8, and 16-bit CRCs, the relevant result is stored in the least-significant byte(s) of the returned value.

**Parameters**

- `type` – CRC algorithm to use.
- `src` – Input bytes for the computation
- `len` – Length of the input in bytes
- `seed` – Value to seed the CRC with
- `poly` – The polynomial to use omitting the leading coefficient
- `reflect` – Should we use reflected/reversed values or not
• `first` – Whether this is the first packet in the stream.
• `last` – Whether this is the last packet in the stream.

**Returns**
`uint32_t` the computed CRC value

### 4.33.2 Structured Data APIs

#### JSON

**Related code samples**

**AWS IoT Core MQTT**

Connect to AWS IoT Core and publish messages using MQTT.

---

**group json**

**Defines**

`JSON_OBJ_DESCR_PRIM(struct_, field_name_, type_)`

Helper macro to declare a descriptor for supported primitive values.

Here's an example of use:

```c
struct foo {
    int32_t some_int;
};

struct json_obj_descr foo[] = {
    JSON_OBJ_DESCR_PRIM(struct foo, some_int, JSON_TOK_NUMBER),
};
```

**Parameters**

- `struct_` – Struct packing the values
- `field_name_` – Field name in the struct
- `type_` – Token type for JSON value corresponding to a primitive type. Must be one of: `JSON_TOK_STRING` for strings, `JSON_TOK_NUMBER` for numbers, `JSON_TOK_TRUE` (or `JSON_TOK_FALSE`) for booleans.

`JSON_OBJ_DESCR_OBJECT(struct_, field_name_, sub_descr_)`

Helper macro to declare a descriptor for an object value.

Here's an example of use:

```c
struct nested {
    int32_t foo;
    struct {
        int32_t baz;
    } bar;
};
```

(continues on next page)
struct json_obj_descr nested_bar[] = {
    { ... declare bar.baz descriptor ... },
};
struct json_obj_descr nested[] = {
    { ... declare foo descriptor ... },
    JSON_OBJ_DESCR_OBJECT(struct nested, bar, nested_bar),
};

Parameters

- **struct** – Struct packing the values
- **field_name** – Field name in the struct
- **sub_descr** – Array of *json_obj_descr* describing the subobject

*JSON_OBJ_DESCR_ARRAY*(struct_, field_name_, max_len_, len_field_, elem_type_)

Helper macro to declare a descriptor for an array of primitives.

Here’s an example of use:

```c
struct example {
    int32_t foo[10];
    size_t foo_len;
};
struct json_obj_descr array[] = {
    JSON_OBJ_DESCR_ARRAY(struct example, foo, 10, foo_len,
                          JSON_TOK_NUMBER)
};
```

Parameters

- **struct** – Struct packing the values
- **field_name** – Field name in the struct
- **max_len** – Maximum number of elements in array
- **len_field** – Field name in the struct for the number of elements in the array
- **elem_type** – Element type, must be a primitive type

*JSON_OBJ_DESCR_OBJ_ARRAY*(struct_, field_name_, max_len_, len_field_, elem_descr_,
                           elem_descr_len_)

Helper macro to declare a descriptor for an array of objects.

Here’s an example of use:

```c
struct person_height {
    const char *name;
    int32_t height;
};
struct people_heights {
    struct person_height heights[10];
    size_t heights_len;
};
```
struct json_obj_descr person_height_descr[] = {
    JSON_OBJ_DESCR_PRIM(struct person_height, name, JSON_TOK_STRING),
    JSON_OBJ_DESCR_PRIM(struct person_height, height, JSON_TOK_NUMBER),
};

struct json_obj_descr array[] = {
    JSON_OBJ_DESCR_OBJ_ARRAY(struct people_heights, heights, 10,
                              heights_len, person_height_descr,
                              ARRAY_SIZE(person_height descr)),
};

Parameters

- **struct** – Struct packing the values
- **field_name** – Field name in the struct containing the array
- **max_len** – Maximum number of elements in the array
- **len_field** – Field name in the struct for the number of elements in the array
- **elem_descr** – Element descriptor, pointer to a descriptor array
- **elem_descr_len** – Number of elements in elem_descr

```c
JSON_OBJ_DESCR_ARRAY_ARRAY(struct_, field_name_, max_len_, len_field_, elem_descr_,
                            elem_descr_len_)
```

Helper macro to declare a descriptor for an array of array.

Here's an example of use:

```c
struct person_height {
    const char *name;
    int32_t height;
};

struct person_heights_array {
    struct person_height heights;
}

struct people_heights {
    struct person_height_array heights[10];
    size_t heights_len;
};

struct json_obj_descr person_height descr[] = {
    JSON_OBJ_DESCR_PRIM(struct person_height, name, JSON_TOK_STRING),
    JSON_OBJ_DESCR_PRIM(struct person_height, height, JSON_TOK_NUMBER),
};

struct json_obj_descr person_height_array descr[] = {
    JSON_OBJ_DESCR_OBJECT(struct person_heights_array, heights, person_height descr),
};

struct json_obj descr array_array[] = {
    JSON_OBJ_DESCR_ARRAY_ARRAY(struct people_heights, heights, 10,
                                heights_len, person_height_array descr,
                            JSON_OBJ.Descr')}}}
```

(continues on next page)
Parameters

- `struct_` – Struct packing the values
- `field_name_` – Field name in the struct containing the array
- `max_len_` – Maximum number of elements in the array
- `len_field_` – Field name in the struct for the number of elements in the array
- `elem_descr_` – Element descriptor, pointer to a descriptor array
- `elem_descr_len_` – Number of elements in `elem_descr_`

`JSON_OBJ_DESCR_ARRAY_ARRAY_NAMED(struct_, json_field_name_, struct_field_name_, max_len_, len_field_, elem_descr_, elem_descr_len_)`

Variant of `JSON_OBJ_DESCR_ARRAY_ARRAY` that can be used when the structure and JSON field names differ.

This is useful when the JSON field is not a valid C identifier.

See also:

`JSON_OBJ_DESCR_ARRAY_ARRAY`
• **type_** – Token type for JSON value corresponding to a primitive type.

`JSON_OBJ_DESCR_OBJECT_NAMED(struct_, json_field_name_, struct_field_name_, sub_descr_)`

Variant of `JSON_OBJ_DESCR_OBJECT` that can be used when the structure and JSON field names differ.

This is useful when the JSON field is not a valid C identifier.

**See also:**

`JSON_OBJ_DESCR_OBJECT`

**Parameters**

- **struct_** – Struct packing the values
- **json_field_name_** – String, field name in JSON strings
- **struct_field_name_** – Field name in the struct
- **sub_descr_** – Array of `json_obj_descr` describing the subobject

`JSON_OBJ_DESCR_ARRAY_NAMED(struct_, json_field_name_, struct_field_name_, max_len_, len_field_, elem_type_)`

Variant of `JSON_OBJ_DESCR_ARRAY` that can be used when the structure and JSON field names differ.

This is useful when the JSON field is not a valid C identifier.

**See also:**

`JSON_OBJ_DESCR_ARRAY`

**Parameters**

- **struct_** – Struct packing the values
- **json_field_name_** – String, field name in JSON strings
- **struct_field_name_** – Field name in the struct
- **max_len_** – Maximum number of elements in array
- **len_field_** – Field name in the struct for the number of elements in the array
- **elem_type_** – Element type, must be a primitive type

`JSON_OBJ_DESCR_OBJ_ARRAY_NAMED(struct_, json_field_name_, struct_field_name_, max_len_, len_field_, elem_descr_, elem_descr_len_)`

Variant of `JSON_OBJ_DESCR_OBJ_ARRAY` that can be used when the structure and JSON field names differ.

This is useful when the JSON field is not a valid C identifier.

Here's an example of use:

```c
struct person_height {
    const char *name;
    int32_t height;
};
```

(continues on next page)
struct people_heights {
    struct person_height heights[10];
    size_t heights_len;
};

struct json_obj_descr person_height_descr[] = {
    JSON_OBJ_DESCR_PRIM(struct person_height, name, JSON_TOK_STRING),
    JSON_OBJ_DESCR_PRIM(struct person_height, height, JSON_TOK_NUMBER),
};

struct json_obj_descr array[] = {
    JSON_OBJ_DESCR_OBJ_ARRAY_NAMED(struct people_heights, "people-heights", heights,
                                    10, heights_len,
                                    person_height_descr,
                                    ARRAY_SIZE(person_height_descr)),
};

Parameters

- **struct_** – Struct packing the values
- **json_field_name_** – String, field name of the array in JSON strings
- **struct_field_name_** – Field name in the struct containing the array
- **max_len_** – Maximum number of elements in the array
- **len_field_** – Field name in the struct for the number of elements in the array
- **elem_descr_** – Element descriptor, pointer to a descriptor array
- **elem_descr_len_** – Number of elements in elem_descr_

Typedefs

typedef int (*json_append_bytes_t)(const char *bytes, size_t len, void *data)
Function pointer type to append bytes to a buffer while encoding JSON data.

**Param bytes**
Contents to write to the output

**Param len**
Number of bytes to append to output

**Param data**
User-provided pointer

**Return**
This callback function should return a negative number on error (which will be propagated to the return value of `json_obj_encode()`), or 0 on success.

Enums

enum json_tokens

**Values:**
Functions

```c
int64_t json_obj_parse(char *json, size_t len, const struct json_obj_descr *descr, size_t descr_len, void *val)
```

Parses the JSON-encoded object pointed to by `json`, with size `len`, according to the descriptor pointed to by `descr`.

Values are stored in a struct pointed to by `val`. Set up the descriptor like this:
struct s { int32_t foo; char *bar; } struct json_obj_descr descr[] = {
    JSON_OBJ_DESCR_PRIM(struct s, foo, JSON_TOK_NUMBER),
    JSON_OBJ_DESCR_PRIM(struct s, bar, JSON_TOK_STRING),
};

Since this parser is designed for machine-to-machine communications, some liberties were taken to simplify the design: (1) strings are not unescaped (but only valid escape sequences are accepted); (2) no UTF-8 validation is performed; and (3) only integer numbers are supported (no strtod() in the minimal libc).

Parameters

- json – Pointer to JSON-encoded value to be parsed
- len – Length of JSON-encoded value
- descr – Pointer to the descriptor array
- descr_len – Number of elements in the descriptor array. Must be less than 63 due to implementation detail reasons (if more fields are necessary, use two descriptors)
- val – Pointer to the struct to hold the decoded values

Returns

- 0 if error, bitmap of decoded fields on success (bit 0 is set if first field in the descriptor has been properly decoded, etc).

int json_arr_parse(char *json, size_t len, const struct json_obj_descr *descr, void *val)

Parses the JSON-encoded array pointed to by json, with size len, according to the descriptor pointed to by descr.

Values are stored in a struct pointed to by val. Set up the descriptor like this:

struct s { int32_t foo; char *bar; } struct json_obj_descr descr[] = {
    JSON_OBJ_DESCR_PRIM(struct s, foo, JSON_TOK_NUMBER),
    JSON_OBJ_DESCR_PRIM(struct s, bar, JSON_TOK_STRING),
}; struct a { struct s baz[10]; size_t count; } struct json_obj_descr array[] = {
    JSON_OBJ_DESCR_OBJ_ARRAY(struct a, baz, 10, count, descr, ARRAY_SIZE(descr)),
};

Since this parser is designed for machine-to-machine communications, some liberties were taken to simplify the design: (1) strings are not unescaped (but only valid escape sequences are accepted); (2) no UTF-8 validation is performed; and (3) only integer numbers are supported (no strtod() in the minimal libc).

Parameters

- json – Pointer to JSON-encoded array to be parsed
- len – Length of JSON-encoded array
- descr – Pointer to the descriptor array
- val – Pointer to the struct to hold the decoded values

Returns

- 0 if array has been successfully parsed. A negative value indicates an error (as defined on errno.h).

int json_arr_separate_object_parse_init(struct json_obj *json, char *payload, size_t len)

Initialize single-object array parsing.

JSON-encoded array data is going to be parsed one object at a time. Data is provided by payload with the size of len bytes.

Function validate that Json Array start is detected and initialize json object for Json object parsing separately.

Parameters
• `json` – Provide storage for parser states. To be used when parsing the array.
• `payload` – Pointer to JSON-encoded array to be parsed
• `len` – Length of JSON-encoded array

**Returns**
0 if array start is detected and initialization is successful or negative error code in case of failure.

```c
int json_arr_separate_parse_object(struct json_obj *json, const struct json_obj_descr *descr, size_t descr_len, void *val)
```

Parse a single object from array.

Parses the JSON-encoded object pointed to by `json` object array, with size `len`, according to the descriptor pointed to by `descr`.

**Parameters**
• `json` – Pointer to JSON-object message state
• `descr` – Pointer to the descriptor array
• `descr_len` – Number of elements in the descriptor array. Must be less than 31.
• `val` – Pointer to the struct to hold the decoded values

**Returns**
< 0 if error, 0 for end of message, bitmap of decoded fields on success (bit 0 is set if first field in the descriptor has been properly decoded, etc).

```c
ssize_t json_escape(char *str, size_t *len, size_t buf_size)
```

Escapes the string so it can be used to encode JSON objects.

**Parameters**
• `str` – The string to escape; the escape string is stored the buffer pointed to by this parameter
• `len` – Points to a size_t containing the size before and after the escaping process
• `buf_size` – The size of buffer `str` points to

**Returns**
0 if string has been escaped properly, or -ENOMEM if there was not enough space to escape the buffer

```c
size_t json_calc_escaped_len(const char *str, size_t len)
```

Calculates the JSON-escaped string length.

**Parameters**
• `str` – The string to analyze
• `len` – String size

**Returns**
The length `str` would have if it were escaped

```c
ssize_t json_calc_encoded_len(const struct json_obj_descr *descr, size_t descr_len, const void *val)
```

Calculates the string length to fully encode an object.

**Parameters**
• `descr` – Pointer to the descriptor array
• `descr_len` – Number of elements in the descriptor array
• `val` – Struct holding the values

**Returns**
Number of bytes necessary to encode the values if >0, an error code is returned.

```c
ssize_t json_calc_encoded_arr_len(const struct json_obj_descr *descr, const void *val)
```
Calculates the string length to fully encode an array.

**Parameters**
• `descr` – Pointer to the descriptor array
• `val` – Struct holding the values

**Returns**
Number of bytes necessary to encode the values if >0, an error code is returned.

```c
int json_obj_encode_buf(const struct json_obj_descr *descr, size_t descr_len, const void *val, char *buffer, size_t buf_size)
```
Encodes an object in a contiguous memory location.

**Parameters**
• `descr` – Pointer to the descriptor array
• `descr_len` – Number of elements in the descriptor array
• `val` – Struct holding the values
• `buffer` – Buffer to store the JSON data
• `buf_size` – Size of buffer, in bytes, with space for the terminating NUL character

**Returns**
0 if object has been successfully encoded. A negative value indicates an error (as defined on errno.h).

```c
int json_arr_encode_buf(const struct json_obj_descr *descr, const void *val, char *buffer, size_t buf_size)
```
Encodes an array in a contiguous memory location.

**Parameters**
• `descr` – Pointer to the descriptor array
• `val` – Struct holding the values
• `buffer` – Buffer to store the JSON data
• `buf_size` – Size of buffer, in bytes, with space for the terminating NUL character

**Returns**
0 if object has been successfully encoded. A negative value indicates an error (as defined on errno.h).

```c
int json_obj_encode(const struct json_obj_descr *descr, size_t descr_len, const void *val, json_append_bytes_t append_bytes, void *data)
```
Encodes an object using an arbitrary writer function.

**Parameters**
• `descr` – Pointer to the descriptor array
• `descr_len` – Number of elements in the descriptor array
- **val** – Struct holding the values
- **append_bytes** – Function to append bytes to the output
- **data** – Data pointer to be passed to the append_bytes callback function.

**Returns**

0 if object has been successfully encoded. A negative value indicates an error.

```c
int json_arr_encode(const struct json_obj_descr *descr, const void *val,
                     json_append_bytes_t append_bytes, void *data)
```

Encodes an array using an arbitrary writer function.

**Parameters**

- **descr** – Pointer to the descriptor array
- **val** – Struct holding the values
- **append_bytes** – Function to append bytes to the output
- **data** – Data pointer to be passed to the append_bytes callback function.

**Returns**

0 if object has been successfully encoded. A negative value indicates an error.

```c
struct json_token
#include <json.h>

struct json_lexer
#include <json.h>

struct json_obj
#include <json.h>

struct json_obj_token
#include <json.h>

struct json_obj_descr
#include <json.h>
```

**JWT**

JSON Web Tokens (JWT) are an open, industry standard [RFC 7519](https://tools.ietf.org/html/rfc7519) method for representing claims securely between two parties. Although JWT is fairly flexible, this API is limited to creating the simplistic tokens needed to authenticate with the Google Core IoT infrastructure.

**group jwt**

**Functions**
int jwt_init_builder(struct jwt_builder *builder, char *buffer, size_t buffer_size)
Initialize the JWT builder.

Initialize the given JWT builder for the creation of a fresh token. The buffer size should at least be as long as JWT_BUILDER_MAX_SIZE returns.

Parameters

• builder – The builder to initialize.
• buffer – The buffer to write the token to.
• buffer_size – The size of this buffer. The token will be NULL terminated, which needs to be allowed for in this size.

Return values

• 0 – Success
• –ENOSPC – Buffer is insufficient to initialize

int jwt_add_payload(struct jwt_builder *builder, int32_t exp, int32_t iat, const char *aud)
Add JWT primary payload.

int jwt_sign(struct jwt_builder *builder, const char *der_key, size_t der_key_len)
Sign the JWT token.

static inline size_t jwt_payload_len(struct jwt_builder *builder)

struct jwt_builder

#include <jwt.h> JWT data tracking.

JSON Web Tokens contain several sections, each encoded in base-64. This structure tracks the token as it is being built, including limits on the amount of available space. It should be initialized with jwt_init().

Public Members

char *base
The base of the buffer we are writing to.

char *buf
The place in this buffer where we are currently writing.

size_t len
The length remaining to write.

bool overflowed
Flag that is set if we try to write past the end of the buffer.
If set, the token is not valid.
Chapter 5

Build and Configuration Systems

5.1 Build System (CMake)

CMake is used to build your application together with the Zephyr kernel. A CMake build is done in two stages. The first stage is called configuration. During configuration, the CMakeLists.txt build scripts are executed. After configuration is finished, CMake has an internal model of the Zephyr build, and can generate build scripts that are native to the host platform.

CMake supports generating scripts for several build systems, but only Ninja and Make are tested and supported by Zephyr. After configuration, you begin the build stage by executing the generated build scripts. These build scripts can recompile the application without involving CMake following most code changes. However, after certain changes, the configuration step must be executed again before building. The build scripts can detect some of these situations and reconfigure automatically, but there are cases when this must be done manually.

Zephyr uses CMake's concept of a ‘target’ to organize the build. A target can be an executable, a library, or a generated file. For application developers, the library target is the most important to understand. All source code that goes into a Zephyr build does so by being included in a library target, even application code.

Library targets have source code, that is added through CMakeLists.txt build scripts like this:

```cmake
target_sources(app PRIVATE src/main.c)
```

In the above CMakeLists.txt, an existing library target named app is configured to include the source file src/main.c. The PRIVATE keyword indicates that we are modifying the internals of how the library is being built. Using the keyword PUBLIC would modify how other libraries that link with app are built. In this case, using PUBLIC would cause libraries that link with app to also include the source file src/main.c, behavior that we surely do not want. The PUBLIC keyword could however be useful when modifying the include paths of a target library.

5.1.1 Build and Configuration Phases

The Zephyr build process can be divided into two main phases: a configuration phase (driven by CMake) and a build phase (driven by Make or Ninja).

Configuration Phase

The configuration phase begins when the user invokes CMake to generate a build system, specifying a source application directory and a board target.
Configuration overview...

*.dts/*.dtsi files

C preprocessor

Preprocessed devicetree...

Kconfig files

Bindings (YAML files)

Scripts in scripts/d...

Scripts in scripts/kconf...

devicetree_generated.h...

Final devicetree, zephyr.dts

dtc: optional, for warning...

Outputs

Makefile or Ninja file (...

Final devicetree, zephyr.dts

Viewer does not support full SVG 1.1

autconf.h

.config

devicetree.h...

Makefile or Ninja file (...
CMake begins by processing the `CMakeLists.txt` file in the application directory, which refers to the `CMakeLists.txt` file in the Zephyr top-level directory, which in turn refers to `CMakeLists.txt` files throughout the build tree (directly and indirectly). Its primary output is a set of Makefiles or Ninja files to drive the build process, but the CMake scripts also do some processing of their own, which is explained here.

Note that paths beginning with `build/` below refer to the build directory you create when running CMake.

**Devicetree**

*.dts (devicetree source) and *.dti (devicetree source include) files are collected from the target's architecture, SoC, board, and application directories.

*.dti files are included by *.dts files via the C preprocessor (often abbreviated `cpp`, which should not be confused with C++). The C preprocessor is also used to merge in any devicetree *.overlay files, and to expand macros in *.dts, *.dti, and *.overlay files. The preprocessor output is placed in `build/zephyr/zephyr.dts.pre`.

The preprocessed devicetree sources are parsed by `gen_defines.py` to generate a `build/zephyr/include/generated/devicetree_generated.h` header with preprocessor macros.

Source code should access preprocessor macros generated from devicetree by including the `devicetree.h` header, which includes `devicetree_generated.h`.

`gen_defines.py` also writes the final devicetree to `build/zephyr/zephyr.dts` in the build directory. This file's contents may be useful for debugging.

If the devicetree compiler `dtc` is installed, it is run on `build/zephyr/zephyr.dts` to catch any extra warnings and errors generated by this tool. The output from `dtc` is unused otherwise, and this step is skipped if `dtc` is not installed.

The above is just a brief overview. For more information on devicetree, see [Devicetree Guide](#).

**Kconfig**

Kconfig files define available configuration options for the target architecture, SoC, board, and application, as well as dependencies between options.

Kconfig configurations are stored in configuration files. The initial configuration is generated by merging configuration fragments from the board and application (e.g. `prj.conf`).

The output from Kconfig is an `autoconf.h` header with preprocessor assignments, and a `.config` file that acts both as a saved configuration and as configuration output (used by CMake). The definitions in `autoconf.h` are automatically exposed at compile time, so there is no need to include this header.

Information from devicetree is available to Kconfig, through the functions defined in `kconfigfunctions.py`.

See the Kconfig section of the manual for more information.

**Build Phase**

The build phase begins when the user invokes `make` or `ninja`. Its ultimate output is a complete Zephyr application in a format suitable for loading/flashing on the desired target board (`zephyr.elf`, `zephyr.hex`, etc.) The build phase can be broken down, conceptually, into four stages: the pre-build, first-pass binary, final binary, and post-processing.

**Pre-build** Pre-build occurs before any source files are compiled, because during this phase header files used by the source files are generated.
Offset generation
Access to high-level data structures and members is sometimes required when the definitions of those structures is not immediately accessible (e.g., assembly language). The generation of offsets.h (by gen_offset_header.py) facilitates this.

System call boilerplate
The gen_syscall.py and parse_syscalls.py scripts work together to bind potential system call functions with their implementations.

Intermediate binaries Compilation proper begins with the first intermediate binary. Source files (C and assembly) are collected from various subsystems (which ones is decided during the configuration phase), and compiled into archives (with reference to header files in the tree, as well as those generated during the configuration phase and the pre-build stage(s)).

The exact number of intermediate binaries is decided during the configuration phase.
If memory protection is enabled, then:

**Partition grouping**

The *gen_app_partitions.py* script scans all the generated archives and outputs linker scripts to ensure that application partitions are properly grouped and aligned for the target’s memory protection hardware.

Then *cpp* is used to combine linker script fragments from the target’s architecture/SoC, the kernel tree, optionally the partition output if memory protection is enabled, and any other fragments selected during the configuration process, into a *linkercmd* file. The compiled archives are then linked with *ld* as specified in the *linkercmd*.

**Unfixed size binary**

The unfixed size intermediate binary is produced when *User Mode* is enabled or *Devicetree* is in use. It produces a binary where sizes are not fixed and thus it may be used by post-process steps that will impact the size of the final binary.

**Fixed size binary**

The fixed size intermediate binary is produced when *User Mode* is enabled or when generated IRQ tables are used, *CONFIG_GEN_ISR_TABLES*. It produces a binary where sizes are fixed and thus the size must not change between the intermediate binary and the final binary.

**Intermediate binaries post-processing**

The binaries from the previous stage are incomplete, with empty and/or placeholder sections that must be filled in by, essentially, reflection.

To complete the build procedure the following scripts are executed on the intermediate binaries to produce the missing pieces needed for the final binary.

When *User Mode* is enabled:

**Partition alignment**

The *gen_app_partitions.py* script scans the unfixed size binary and generates an app shared memory aligned linker script snippet where the partitions are sorted in descending order.
When **Devicetree** is used:

**Device dependencies**

The `gen_device_deps.py` script scans the unfixed size binary to determine relationships between devices that were recorded from devicetree data, and replaces the encoded relationships with values that are optimized to locate the devices actually present in the application.

When **CONFIG_GEN_ISR_TABLES** is enabled:

The `gen_isr_tables.py` script scans the fixed size binary and creates an isr_tables.c source file with a hardware vector table and/or software IRQ table.

When **User Mode** is enabled:

**Kernel object hashing**

The `gen_kobject_list.py` scans the ELF DWARF debug data to find the address of the all kernel objects. This list is passed to `gperf`, which generates a perfect hash function and table of those addresses, then that output is optimized by `process_gperf.py`, using known properties of our special case.

When no intermediate binary post-processing is required then the first intermediate binary will be directly used as the final binary.

**Final binary** The binary from the previous stage is incomplete, with empty and/or placeholder sections that must be filled in by, essentially, reflection.

The link from the previous stage is repeated, this time with the missing pieces populated.
Post processing  Finally, if necessary, the completed kernel is converted from ELF to the format expected by the loader and/or flash tool required by the target. This is accomplished in a straightforward manner with objdump.

5.1.2 Supporting Scripts and Tools

The following is a detailed description of the scripts used during the build process.

scripts/build/gen_syscalls.py

Script to generate system call invocation macros

This script parses the system call metadata JSON file emitted by parse_syscalls.py to create several files:

- A file containing weak aliases of any potentially unimplemented system calls, as well as the system call dispatch table, which maps system call type IDs to their handler functions.
- A header file defining the system call type IDs, as well as function prototypes for all system call handler functions.
- A directory containing header files. Each header corresponds to a header that was identified as containing system call declarations. These generated headers contain the inline invocation functions for each system call in that header.

scripts/build/gen_device_deps.py

Translate generic handles into ones optimized for the application.
Immutable device data includes information about dependencies, e.g. that a particular sensor is controlled through a specific I2C bus and that it signals event on a pin on a specific GPIO controller. This information is encoded in the first-pass binary using identifiers derived from the devicetree. This script extracts those identifiers and replaces them with ones optimized for use with the devices actually present.

For example the sensor might have a first-pass handle defined by its devicetree ordinal 52, with the I2C driver having ordinal 24 and the GPIO controller ordinal 14. The runtime ordinal is the index of the corresponding device in the static devicetree array, which might be 6, 5, and 3, respectively.

The output is a C source file that provides alternative definitions for the array contents referenced from the immutable device objects. In the final link these definitions supersede the ones in the driver-specific object file.

**scripts/build/gen_kobject_list.py**

Script to generate gperf tables of kernel object metadata

User mode threads making system calls reference kernel objects by memory address, as the kernel/driver APIs in Zephyr are the same for both user and supervisor contexts. It is necessary for the kernel to be able to validate accesses to kernel objects to make the following assertions:

- That the memory address points to a kernel object
- The kernel object is of the expected type for the API being invoked
- The kernel object is of the expected initialization state
- The calling thread has sufficient permissions on the object

For more details see the Kernel Objects section in the documentation.

The zephyr build generates an intermediate ELF binary, zephyr_prebuilt.elf, which this script scans looking for kernel objects by examining the DWARF debug information to look for instances of data structures that are considered kernel objects. For device drivers, the API struct pointer populated at build time is also examined to disambiguate between various device driver instances since they are all ‘struct device’.

This script can generate five different output files:

- A gperf script to generate the hash table mapping kernel object memory addresses to kernel object metadata, used to track permissions, object type, initialization state, and any object-specific data.
- A header file containing generated macros for validating driver instances inside the system call handlers for the driver subsystem APIs.
- A code fragment included by kernel.h with one enum constant for each kernel object type and each driver instance.
- The inner cases of a switch/case C statement, included by kernel/userspace.c, mapping the kernel object types and driver instances to their human-readable representation in the otype_to_str() function.
- The inner cases of a switch/case C statement, included by kernel/userspace.c, mapping kernel object types to their sizes. This is used for allocating instances of them at runtime (CONFIG_DYNAMIC_OBJECTS) in the obj_size_get() function.

**scripts/build/gen_offset_header.py**

This script scans a specified object file and generates a header file that defined macros for the offsets of various found structure members (particularly symbols ending with _OFFSET or _SIZEOF),
scripts/build/parse_syscalls.py

Script to scan Zephyr include directories and emit system call and subsystem metadata
System calls require a great deal of boilerplate code in order to implement completely. This
script is the first step in the build system's process of auto-generating this code by doing a text
scan of directories containing C or header files, and building up a database of system calls and
their function call prototypes. This information is emitted to a generated JSON file for further
processing.
This script also scans for struct definitions such as __subsystem and __net_socket, emitting a JSON
dictionary mapping tags to all the struct declarations found that were tagged with them.
If the output JSON file already exists, its contents are checked against what information this
script would have outputted; if the result is that the file would be unchanged, it is not modified
to prevent unnecessary incremental builds.

arch/x86/gen_idt.py

Generate Interrupt Descriptor Table for x86 CPUs.
This script generates the interrupt descriptor table (IDT) for x86. Please consult the IA Architec-
ture SW Developer Manual, volume 3, for more details on this data structure.
This script accepts as input the zephyr_prebuilt.elf binary, which is a link of the Zephyr ker-
nel without various build-time generated data structures (such as the IDT) inserted into it. This
kernel image has been properly padded such that inserting these data structures will not dis-
turb the memory addresses of other symbols. From the kernel binary we read a special section
“intList” which contains the desired interrupt routing configuration for the kernel, populated by
instances of the IRQ_CONNECT() macro.
This script outputs three binary tables:
1. The interrupt descriptor table itself.
2. A bitfield indicating which vectors in the IDT are free for installation of dynamic interrupts
   at runtime.
3. An array which maps configured IRQ lines to their associated vector entries in the IDT, used
   to program the APIC at runtime.

arch/x86/gen_gdt.py

Generate a Global Descriptor Table (GDT) for x86 CPUs.
For additional detail on GDT and x86 memory management, please consult the IA Architecture
This script accepts as input the zephyr_prebuilt.elf binary, which is a link of the Zephyr kernel
without various build-time generated data structures (such as the GDT) inserted into it. This
kernel image has been properly padded such that inserting these data structures will not disturb
the memory addresses of other symbols.
The input kernel ELF binary is used to obtain the following information:
• Memory addresses of the Main and Double Fault TSS structures so GDT descriptors can be
  created for them
• Memory addresses of where the GDT lives in memory, so that this address can be populated
  in the GDT pseudo descriptor
whether userspace or HW stack protection are enabled in Kconfig

The output is a GDT whose contents depend on the kernel configuration. With no memory protection features enabled, we generate flat 32-bit code and data segments. If hardware-based stack overflow protection or userspace is enabled, we additionally create descriptors for the main and double-fault IA tasks, needed for userspace privilege elevation and double-fault handling. If userspace is enabled, we also create flat code/data segments for ring 3 execution.

scripts/build/gen_relocate_app.py

This script will relocate .text, .rodata, .data and .bss sections from required files and places it in the required memory region. This memory region and file are given to this python script in the form of a string.

Example of such a string would be:

```
SRAM2:COPY:/home/xyz/zephyr/samples/hello_world/src/main.c,
SRAM1:COPY:/home/xyz/zephyr/samples/hello_world/src/main2.c,
FLASH2:NOCOPY:/home/xyz/zephyr/samples/hello_world/src/main3.c
```

One can also specify the program header for a given memory region:

```
SRAM2\ :phdr0:COPY:/home/xyz/zephyr/samples/hello_world/src/main.c
```

To invoke this script:

```
python3 gen_relocate_app.py -i input_string -o generated_linker -c generated_code
```

Configuration that needs to be sent to the python script.

- If the memory is like SRAM1/SRAM2/CCD/AON then place full object in the sections
- If the memory type is appended with _DATA / _TEXT / _RODATA / _BSS only the selected memory is placed in the required memory region. Others are ignored.
- COPY/NOCOPY defines whether the script should generate the relocation code in code_relocation.c or not
- NOKEEP will suppress the default behavior of marking every relocated symbol with KEEP() in the generated linker script.

Multiple regions can be appended together like SRAM2_DATA_BSS this will place data and bss inside SRAM2.

scripts/build/process_gperf.py

gperf C file post-processor

We use gperf to build up a perfect hashtable of pointer values. The way gperf does this is to create a table ‘wordlist’ indexed by a string representation of a pointer address, and then doing memcmp() on a string passed in for comparison

We are exclusively working with 4-byte pointer values. This script adjusts the generated code so that we work with pointers directly and not strings. This saves a considerable amount of space.

scripts/build/gen_app_partitions.py

Script to generate a linker script organizing application memory partitions

Applications may declare build-time memory domain partitions with K_APPMEM_PARTITION_DEFINE, and assign globals to them using K_APP_DMEM or K_APP_BMEM macros. For each of these partitions, we need to route all their data into
appropriately-sized memory areas which meet the size/alignment constraints of the memory protection hardware.

This linker script is created very early in the build process, before the build attempts to link the kernel binary, as the linker script this tool generates is a necessary pre-condition for kernel linking. We extract the set of memory partitions to generate by looking for variables which have been assigned to input sections that follow a defined naming convention. We also allow entire libraries to be pulled in to assign their globals to a particular memory partition via command line directives.

This script takes as inputs:

- The base directory to look for compiled objects
- key/value pairs mapping static library files to what partitions their globals should end up in.

The output is a linker script fragment containing the definition of the app shared memory section, which is further divided, for each partition found, into data and BSS for each partition.

**scripts/build/check_init_priorities.py**

Checks the initialization priorities

This script parses a Zephyr executable file, creates a list of known devices and their effective initialization priorities and compares that with the device dependencies inferred from the devicetree hierarchy.

This can be used to detect devices that are initialized in the incorrect order, but also devices that are initialized at the same priority but depends on each other, which can potentially break if the linking order is changed.

Optionally, it can also produce a human readable list of the initialization calls for the various init levels.

### 5.2 Devicetree

A *devicetree* is a hierarchical data structure primarily used to describe hardware. Zephyr uses devicetree in two main ways:

- to describe hardware to the *Device Driver Model*
- to provide that hardware's initial configuration

This page links to a high level guide on devicetree as well as reference material.

#### 5.2.1 Devicetree Guide

The pages in this section are a high-level guide to using devicetree for Zephyr development.

**Introduction to devicetree**

*Tip:* This is a conceptual overview of devicetree and how Zephyr uses it. For step-by-step guides and examples, see *Devicetree HOWTOs*.

The following pages introduce general devicetree concepts and how they apply to Zephyr.
**Scope and purpose**  A devicetree is primarily a hierarchical data structure that describes hardware. The Devicetree specification defines its source and binary representations.

Zephyr uses devicetree to describe:

- the hardware available on its boards
- that hardware's initial configuration

As such, devicetree is both a hardware description language and a configuration language for Zephyr. See Devicetree versus Kconfig for some comparisons between devicetree and Zephyr's other main configuration language, Kconfig.

There are two types of devicetree input files: devicetree sources and devicetree bindings. The sources contain the devicetree itself. The bindings describe its contents, including data types. The build system uses devicetree sources and bindings to produce a generated C header. The generated header's contents are abstracted by the devicetree.h API, which you can use to get information from your devicetree.

Here is a simplified view of the process:

![Devicetree build flow](image)

All Zephyr and application source code files can include and use devicetree.h. This includes device drivers, applications, tests, the kernel, etc.

The API itself is based on C macros. The macro names all start with DT_. In general, if you see a macro that starts with DT_ in a Zephyr source file, it's probably a devicetree.h macro. The generated C header contains macros that start with DT_ as well; you might see those in compiler error messages. You always can tell a generated-from a non-generated macro: generated macros have some lowercased letters, while the devicetree.h macro names have all capital letters.

**Syntax and structure**  As the name indicates, a devicetree is a tree. The human-readable text format for this tree is called DTS (for devicetree source), and is defined in the Devicetree specification.

This page's purpose is to introduce devicetree in a more gradual way than the specification. However, you may still need to refer to the specification to understand some detailed cases.
Example

Here is an example DTS file:

```dts-v1/
/
  a-node {
    subnode_nodelabel: a-sub-node {
      foo = <3>;
    };
  };
```

The `/dts-v1/` line means the file's contents are in version 1 of the DTS syntax, which has replaced a now-obsolete “version 0”.

Nodes

Like any tree data structure, a devicetree has a hierarchy of nodes. The above tree has three nodes:

1. A root node: `/`
2. A node named `a-node`, which is a child of the root node
3. A node named `a-sub-node`, which is a child of `a-node`

Nodes can be assigned node labels, which are unique shorthands that refer to the labeled node. Above, `a-sub-node` has the node label `subnode_nodelabel`. A node can have zero, one, or multiple node labels. You can use node labels to refer to the node elsewhere in the devicetree.

Devicetree nodes have paths identifying their locations in the tree. Like Unix file system paths, devicetree paths are strings separated by slashes (`/`), and the root node's path is a single slash: `/`. Otherwise, each node's path is formed by concatenating the node's ancestors' names with the node's own name, separated by slashes. For example, the full path to `a-sub-node` is `/a-node/a-sub-node`.

Properties

Devicetree nodes can also have properties. Properties are name/value pairs. Property values can be any sequence of bytes. In some cases, the values are an array of what are called cells. A cell is just a 32-bit unsigned integer.

Node `a-sub-node` has a property named `foo`, whose value is a cell with value 3. The size and type of `foo`'s value are implied by the enclosing angle brackets (`<` and `>`) in the DTS.

See Writing property values below for more example property values.

Devicetrees reflect hardware

In practice, devicetree nodes usually correspond to some hardware, and the node hierarchy reflects the hardware's physical layout. For example, let's consider a board with three I2C peripherals connected to an I2C bus controller on an SoC, like this:

Nodes corresponding to the I2C bus controller and each I2C peripheral would be present in the devicetree. Reflecting the hardware layout, the I2C peripheral nodes would be children of the bus controller node. Similar conventions exist for representing other types of hardware.

The DTS would look something like this:
Properties in practice  In practice, properties usually describe or configure the hardware the node represents. For example, an I2C peripheral's node has a property whose value is the peripheral's address on the bus.

Here's a tree representing the same example, but with real-world node names and properties you might see when working with I2C devices.

This is the corresponding DTS:

```
/dts-v1/;
/
{
  soc {
    i2c-bus-controller {
      i2c-peripheral-1 {
        i2c-peripheral-2 {
          i2c-peripheral-3 {
            
          }
        }
      }
    }
  }
};
```

(continues on next page)
Unit addresses. In addition to showing more real-world names and properties, the above example introduces a new devicetree concept: unit addresses. Unit addresses are the parts of node names after an “at” sign (@), like 40003000 in i2c@40003000, or 39 in apds9960@39. Unit addresses are optional: the soc node does not have one.

In devicetree, unit addresses give a node’s address in the address space of its parent node. Here are some example unit addresses for different types of hardware.

Memory-mapped peripherals
The peripheral’s register map base address. For example, the node named i2c@40003000 represents an I2C controller whose register map base address is 0x40003000.

I2C peripherals
The peripheral’s address on the I2C bus. For example, the child node apds9960@39 of the I2C controller in the previous section has I2C address 0x39.

SPI peripherals
An index representing the peripheral’s chip select line number. (If there is no chip select line, 0 is used.)
Memory
The physical start address. For example, a node named `memory@2000000` represents RAM starting at physical address 0x2000000.

Memory-mapped flash
Like RAM, the physical start address. For example, a node named `flash@8000000` represents a flash device whose physical start address is 0x8000000.

Fixed flash partitions
This applies when the devicetree is used to store a flash partition table. The unit address is the partition's start offset within the flash memory. For example, take this flash device and its partitions:

```dts
flash@8000000 {
    /* ... */
    partitions {
        partition@0 { /* ... */
        }
        partition@20000 { /* ... */
        }
    }
}
```

The node named `partition@0` has offset 0 from the start of its flash device, so its base address is 0x8000000. Similarly, the base address of the node named `partition@20000` is 0x8020000.

Important properties
The devicetree specification defines several standard properties. Some of the most important ones are:

compatible
The name of the hardware device the node represents.

The recommended format is "vendor,device", like "avago,apds9960", or a sequence of these, like "ti,hdc", "ti,hdc1010". The vendor part is an abbreviated name of the vendor. The file `dts/bindings/vendor-prefixes.txt` contains a list of commonly accepted vendor names. The device part is usually taken from the datasheet.

It is also sometimes a value like `gpio-keys`, `mmio-sram`, or `fixed-clock` when the hardware's behavior is generic.

The build system uses the compatible property to find the right `bindings` for the node. Device drivers use `devicetree.h` to find nodes with relevant compatibles, in order to determine the available hardware to manage.

The compatible property can have multiple values. Additional values are useful when the device is a specific instance of a more general family, to allow the system to match from most- to least-specific device drivers.

Within Zephyr's bindings syntax, this property has type `string-array`.

reg
Information used to address the device. The value is specific to the device (i.e. is different depending on the compatible property).

The `reg` property is a sequence of `(address, length)` pairs. Each pair is called a “register block”. Values are conventionally written in hex.

Here are some common patterns:

- Devices accessed via memory-mapped I/O registers (like `i2c@40003000`): address is usually the base address of the I/O register space, and length is the number of bytes occupied by the registers.
- I2C devices (like `apds9960@39` and its siblings): address is a slave address on the I2C bus. There is no `length` value.
• SPI devices: address is a chip select line number; there is no length.

You may notice some similarities between the reg property and common unit addresses described above. This is not a coincidence. The reg property can be seen as a more detailed view of the addressable resources within a device than its unit address.

status

A string which describes whether the node is enabled.

The devicetree specification allows this property to have values "okay", "disabled", "reserved", "fail", and "fail-sss". Only the values "okay" and "disabled" are currently relevant to Zephyr; use of other values currently results in undefined behavior.

A node is considered enabled if its status property is either "okay" or not defined (i.e. does not exist in the devicetree source). Nodes with status "disabled" are explicitly disabled. (For backwards compatibility, the value "ok" is treated the same as "okay", but this usage is deprecated.) Devicetree nodes which correspond to physical devices must be enabled for the corresponding struct device in the Zephyr driver model to be allocated and initialized.

interrupts

Information about interrupts generated by the device, encoded as an array of one or more interrupt specifiers. Each interrupt specifier has some number of cells. See section 2.4, Interrupts and Interrupt Mapping, in the Devicetree Specification release v0.3 for more details.

Zephyr’s devicetree bindings language lets you give a name to each cell in an interrupt specifier.

Note: Earlier versions of Zephyr made frequent use of the label property, which is distinct from the standard node label. Use of the label property in new devicetree bindings, as well as use of the DT_LABEL macro in new code, are actively discouraged. Label properties continue to persist for historical reasons in some existing bindings and overlays, but should not be used in new bindings or device implementations.

Writing property values This section describes how to write property values in DTS format. The property types in the table below are described in detail in Devicetree bindings. Some specifics are skipped in the interest of keeping things simple; if you’re curious about details, see the devicetree specification.

<table>
<thead>
<tr>
<th>Property type</th>
<th>How to write</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>string</td>
<td>Double quoted</td>
<td>a-string = &quot;hello, world!&quot;;</td>
</tr>
<tr>
<td>int</td>
<td>between angle brackets (&lt; and &gt;)</td>
<td>an-int = &lt;1&gt;;</td>
</tr>
<tr>
<td>boolean</td>
<td>for true, with no value (for false, use / delete-property/)</td>
<td>my-true-boolean;</td>
</tr>
<tr>
<td>array</td>
<td>between angle brackets (&lt; and &gt;), separated by spaces</td>
<td>foo = &lt;0xdeadbeef 1234 0&gt;;</td>
</tr>
<tr>
<td>uint8-array</td>
<td>in hexadecimal without leading 0x, between square brackets ([ and ])</td>
<td>a-byte-array = [00 01 ab];</td>
</tr>
<tr>
<td>string-array</td>
<td>separated by commas</td>
<td>a-string-array = &quot;string one&quot;, &quot;string two&quot;, &quot;string three&quot;;</td>
</tr>
<tr>
<td>phandle</td>
<td>between angle brackets (&lt; and &gt;)</td>
<td>a-phandle = &lt;&amp;mynode&gt;;</td>
</tr>
<tr>
<td>phandles</td>
<td>between angle brackets (&lt; and &gt;), separated by spaces</td>
<td>some-phandles = &lt;&amp;mynode0 &amp;mynode1 &amp;mynode2&gt;;</td>
</tr>
<tr>
<td>handle-array</td>
<td>between angle brackets (&lt; and &gt;), separated by spaces</td>
<td>a-phandle-array = &lt;&amp;mynode0 1 2&gt;, &amp;mynode1 3 4&gt;;</td>
</tr>
</tbody>
</table>
Additional notes on the above:

- The values in the phandle, phandles, and phandle-array types are described further in *Phandles*.
- Boolean properties are true if present. They should not have a value. A boolean property is only false if it is completely missing in the DTS.
- The foo property value above has three cells with values 0xdeadbeef, 1234, and 0, in that order. Note that hexadecimal and decimal numbers are allowed and can be intermixed. Since Zephyr transforms DTS to C sources, it is not necessary to specify the endianness of an individual cell here.
- 64-bit integers are written as two 32-bit cells in big-endian order. The value 0xaaaa0000babb1111 would be written <0xaaaa0000 0xbabb1111>.
- The a-byte-array property value is the three bytes 0x00, 0x01, and 0xab, in that order.
- Parentheses, arithmetic operators, and bitwise operators are allowed. The bar property contains a single cell with value 64:
  
  ```
  bar = <(2 * (1 << 5))>;
  ```

  Note that the entire expression must be parenthesized.

- Property values refer to other nodes in the devicetree by their phandles. You can write a phandle using &foo, where foo is a node label. Here is an example devicetree fragment:

  ```
  foo: device@0 { }
  device@1 {
    sibling = &foo 1 2;
  }
  ```

  The sibling property of node device@1 contains three cells, in this order:

  1. The device@0 node’s phandle, which is written here as &foo since the device@0 node has a node label foo
  2. The value 1
  3. The value 2

  In the devicetree, a phandle value is a cell – which again is just a 32-bit unsigned int. However, the Zephyr devicetree API generally exposes these values as node identifiers. Node identifiers are covered in more detail in *Devicetree access from C/C++*.

- Array and similar type property values can be split into several <> blocks, like this:

  ```
  foo = <1 2>, <3 4>; // Okay for 'type: array'
  foo = <&label1 &label2>, <&label3 &label4>; // Okay for 'type: phandles'
  foo = <&label1 1 2>, <&label2 3 4>; // Okay for 'type: phandle-array'
  ```

  This is recommended for readability when possible if the value can be logically grouped into blocks of sub-values.

**Aliases and chosen nodes** There are two additional ways beyond node labels to refer to a particular node without specifying its entire path: by alias, or by chosen node.

Here is an example devicetree which uses both:

```
/dts-v1/;
/
  chosen {
    zephyr,console = &uart0;
  }
```
The /aliases and /chosen nodes do not refer to an actual hardware device. Their purpose is to specify other nodes in the devicetree.

Above, my-uart is an alias for the node with path /soc/serial@12340000. Using its node label uart0, the same node is set as the value of the chosen zephyr,console node.

Zephyr sample applications sometimes use aliases to allow overriding the particular hardware device used by the application in a generic way. For example, blinky uses this to abstract the LED to blink via the led0 alias.

The /chosen node's properties are used to configure system- or subsystem-wide values. See Chosen nodes for more information.

Input and output files This section describes the input and output files shown in the figure in Scope and purpose in more detail.

Input files There are four types of devicetree input files:

- sources (.dts)
- includes (.dtsi)
- overlays (.overlay)
- bindings (.yaml)

The devicetree files inside the zephyr directory look like this:

- boards/<ARCH>/<BOARD>/<BOARD>.dts
- dts/common/skeleton.dtsi
- dts/<ARCH>/*/<SOC>.dtsi
- dts/bindings/*/binding.yaml

Generally speaking, every supported board has a BOARD.dts file describing its hardware. For example, the reel_board has boards/arm/reel_board/reel_board.dts.

BOARD.dts includes one or more .dtsi files. These .dtsi files describe the CPU or system-on-chip Zephyr runs on, perhaps by including other .dtsi files. They can also describe other common hardware features shared by multiple boards. In addition to these includes, BOARD.dts also describes the board's specific hardware.

The dts/common directory contains skeleton.dtsi, a minimal include file for defining a complete devicetree. Architecture-specific subdirectories (dts/<ARCH>) contain .dtsi files for CPUs or SoCs which extend skeleton.dtsi.

The C preprocessor is run on all devicetree files to expand macro references, and includes are generally done with #include <filename> directives, even though DTS has a /include/ "<filename>" syntax.
Fig. 3: Devicetree input (green) and output (yellow) files
BOARD.dts can be extended or modified using overlays. Overlays are also DTS files; the .overlay extension is just a convention which makes their purpose clear. Overlays adapt the base devicetree for different purposes:

- Zephyr applications can use overlays to enable a peripheral that is disabled by default, select a sensor on the board for an application specific purpose, etc. Along with Configuration System (Kconfig), this makes it possible to reconfigure the kernel and device drivers without modifying source code.

- Overlays are also used when defining Shields.

The build system automatically picks up .overlay files stored in certain locations. It is also possible to explicitly list the overlays to include, via the DTC_OVERLAY_FILE CMake variable. See Set devicetree overlays for details.

The build system combines BOARD.dts and any .overlay files by concatenating them, with the overlays put last. This relies on DTS syntax which allows merging overlapping definitions of nodes in the devicetree. See Example: FRDM-K64F and Hexiwear K64 for an example of how this works (in the context of .dtsi files, but the principle is the same for overlays). Putting the contents of the .overlay files last allows them to override BOARD.dts.

Devicetree bindings (which are YAML files) are essentially glue. They describe the contents of devicetree sources, includes, and overlays in a way that allows the build system to generate C macros usable by device drivers and applications. The dts/bindings directory contains bindings.

Scripts and tools The following libraries and scripts, located in scripts/dts/, create output files from input files. Their sources have extensive documentation.

dtlib.py
A low-level DTS parsing library.
edtlib.py
A library layered on top of dtlib that uses bindings to interpret properties and give a higher-level view of the devicetree. Uses dtlib to do the DTS parsing.
gen_defines.py
A script that uses edtlib to generate C preprocessor macros from the devicetree and bindings.

In addition to these, the standard dtc (devicetree compiler) tool is run on the final devicetree if it is installed on your system. This is just to catch errors or warnings. The output is unused. Boards may need to pass dtc additional flags, e.g. for warning suppression. Board directories can contain a file named pre_dt_board.cmake which configures these extra flags, like this:

```makefile
list(APPEND EXTRA_DTC_FLAGS "-Wno-simple_bus_reg")
```

Output files These are created in your application's build directory.

**Warning:** Don't include the header files directly. Devicetree access from C/C++ explains what to do instead.

<build>/zephyr/zephyr.dts.pre
The preprocessed DTS source. This is an intermediate output file, which is input to gen_defines.py and used to create zephyr.dts and devicetree_generated.h.

<build>/zephyr/include/generated/devicetree_generated.h
The generated macros and additional comments describing the devicetree. Included by devicetree.h.
The final merged devicetree. This file is output by `gen_defines.py`. It is useful for debugging any issues. If the devicetree compiler `dtc` is installed, it is also run on this file, to catch any additional warnings or errors.

**Design goals**

Zephyr’s use of devicetree has evolved significantly over time, and further changes are expected. The following are the general design goals, along with specific examples about how they impact Zephyr’s source code, and areas where more work remains to be done.

**Single source for hardware information**  Zephyr’s built-in device drivers and sample applications shall obtain configurable hardware descriptions from devicetree.

**Examples**

- New device drivers shall use devicetree APIs to determine which devices to create.
- In-tree sample applications shall use **aliases** to determine which of multiple possible generic devices of a given type will be used in the current build. For example, the blinky sample uses this to determine the LED to blink.
- Boot-time pin muxing and pin control for new SoCs shall be accomplished via a devicetree-based pinctrl driver

**Example remaining work**

- Zephyr’s **Test Runner (Twister)** currently use `board.yaml` files to determine the hardware supported by a board. This should be obtained from devicetree instead.
- Legacy device drivers currently use Kconfig to determine which instances of a particular compatible are enabled. This can and should be done with devicetree overlays instead.
- Board-level documentation still contains tables of hardware support which are generated and maintained by hand. This can and should be obtained from the board level devicetree instead.
- Runtime determination of struct **device** relationships should be done using information obtained from devicetree, e.g. for device power management.

**Source compatibility with other operating systems**  Zephyr’s devicetree tooling is based on a generic layer which is interoperable with other devicetree users, such as the Linux kernel.

Zephyr’s binding language **semantics** can support Zephyr-specific attributes, but shall not express Zephyr-specific relationships.

**Examples**

- Zephyr’s devicetree source parser, `dtlib.py`, is source-compatible with other tools like `dtc` in both directions: `dtlib.py` can parse `dtc` output, and `dtc` can parse `dtlib.py` output.
- Zephyr’s “extended dtlib” library, `edtlib.py`, shall not include Zephyr-specific features. Its purpose is to provide a higher-level view of the devicetree for common elements like interrupts and buses. Only the high-level `gen_defines.py` script, which is built on top of `edtlib.py`, contains Zephyr-specific knowledge and features.
Example remaining work

- Zephyr has a custom Devicetree bindings language syntax. While Linux's dtschema does not yet meet Zephyr's needs, we should try to follow what it is capable of representing in Zephyr's own bindings.
- Due to inflexibility in the bindings language, Zephyr cannot support the full set of bindings supported by Linux.
- Devicetree source sharing between Zephyr and Linux is not done.

Devicetree bindings

A devicetree on its own is only half the story for describing hardware, as it is a relatively un-structured format. Devicetree bindings provide the other half.

A devicetree binding declares requirements on the contents of nodes, and provides semantic information about the contents of valid nodes. Zephyr devicetree bindings are YAML files in a custom format (Zephyr does not use the dt-schema tools used by the Linux kernel).

These pages introduce bindings, describe what they do, note where they are found, and explain their data format.

Note: See the Bindings index for reference information on bindings built in to Zephyr.

Introduction to Devicetree Bindings

Note: For a detailed syntax reference, see Devicetree bindings syntax.

Devicetree nodes are matched to bindings using their compatible properties.

During the Configuration Phase, the build system tries to match each node in the devicetree to a binding file. When this succeeds, the build system uses the information in the binding file both when validating the node's contents and when generating macros for the node.

A simple example

Here is an example devicetree node:

```c
/* Node in a DTS file */
bar-device {
    compatible = "foo-company,bar-device";
    num-foos = <3>;
};
```

Here is a minimal binding file which matches the node:

```yaml
# A YAML binding matching the node
compatible: "foo-company,bar-device"

properties:
    num-foos:
        type: int
        required: true
```

The build system matches the bar-device node to its YAML binding because the node's compatible property matches the binding's compatible: line.
What the build system does with bindings

The build system uses bindings both to validate devicetree nodes and to convert the devicetree's contents into the generated `devicetree_generated.h` header file.

For example, the build system would use the above binding to check that the required `num-foos` property is present in the `bar-device` node, and that its value, `<3>`, has the correct type.

The build system will then generate a macro for the `bar-device` node's `num-foos` property, which will expand to the integer literal 3. This macro lets you get the value of the property in C code using the API which is discussed later in this guide in *Devicetree access from C/C++*.

For another example, the following node would cause a build error, because it has no `num-foos` property, and this property is marked required in the binding:

```
bad-node {
  compatible = "foo-company,bar-device";
};
```

Other ways nodes are matched to bindings

If a node has more than one string in its `compatible` property, the build system looks for compatible bindings in the listed order and uses the first match.

Take this node as an example:

```
baz-device {
  compatible = "foo-company,baz-device", "generic-baz-device";
};
```

The `baz-device` node would get matched to a binding with a `compatible: "generic-baz-device"` line if the build system can't find a binding with a `compatible: "foo-company,baz-device"` line.

Nodes without compatible properties can be matched to bindings associated with their parent nodes. These are called “child bindings”. If a node describes hardware on a bus, like I2C or SPI, then the bus type is also taken into account when matching nodes to bindings. (See *On-bus* for details).

See *The/zephyr/user node* for information about a special node that doesn't require any binding.

Where bindings are located

Binding file names usually match their `compatible:` lines. For example, the above example binding would be named `foo-company,bar-device.yaml` by convention.

The build system looks for bindings in `dts/bindings` subdirectories of the following places:

- the zephyr repository
- your *application source directory*
- your *board directory*
- any *shield directories*
- any directories manually included in the *DTS_ROOT* CMake variable
- any *module* that defines a `dts_root` in its *Build settings*

The build system will consider any YAML file in any of these, including in any subdirectories, when matching nodes to bindings. A file is considered YAML if its name ends with `.yaml` or `.yml`. 
Warning: The binding files must be located somewhere inside the dts/bindings subdirectory of the above places.

For example, if my-app is your application directory, then you must place application-specific bindings inside my-app/dts/bindings. So my-app/dts/bindings/serial/my-company, my-serial-port.yaml would be found, but my-app/my-company,my-serial-port.yaml would be ignored.

Devicetree bindings syntax This page documents the syntax of Zephyr's bindings format. Zephyr bindings files are YAML files. A simple example was given in the introduction page.

Contents
- Top level keys
  - Description
  - Compatible
  - Properties
    - Property entry syntax
    - Example property definitions
    - required
    - type
    - deprecated
    - default
    - enum
    - const
    - specifier-space
- Child-binding
- Bus
- On-bus
- Specifier cell names (*)-cells
- Include
- Nexus nodes and maps

Top level keys The top level of a bindings file maps keys to values. The top-level keys look like this:

```yaml
# A high level description of the device the binding applies to:
description: |
  This is the Vendomatic company's foo-device.

  Descriptions which span multiple lines (like this) are OK, and are encouraged for complex bindings.

  See https://yaml-multiline.info/ for formatting help.
```

(continues on next page)
# You can include definitions from other bindings using this syntax:
include: other.yaml

# Used to match nodes to this binding:
compatible: "manufacturer,foo-device"

properties:
  # Requirements for and descriptions of the properties that this
  # binding's nodes need to satisfy go here.

child-binding:
  # You can constrain the children of the nodes matching this binding
  # using this key.

  # If the node describes bus hardware, like an SPI bus controller
  # on an SoC, use 'bus:' to say which one, like this:
  bus: spi

  # If the node instead appears as a device on a bus, like an external
  # SPI memory chip, use 'on-bus:' to say what type of bus, like this.
  # Like 'compatible', this key also influences the way nodes match
  # bindings.
  on-bus: spi

foo-cells:
  # "Specifier" cell names for the 'foo' domain go here; example 'foo'
  # values are 'gpio', 'pwm', and 'dma'. See below for more information.

These keys are explained in the following sections.

Description  A free-form description of node hardware goes here. You can put links to
datasheets or example nodes or properties as well.

Compatible  This key is used to match nodes to this binding as described in Introduction to
Devicetree Bindings. It should look like this in a binding file:

# Note the comma-separated vendor prefix and device name
compatible: "manufacturer,device"

This devicetree node would match the above binding:

device {
    compatible = "manufacturer,device";
};

Assuming no binding has compatible: "manufacturer,device-v2", it would also match this
node:

device-2 {
    compatible = "manufacturer,device-v2", "manufacturer,device";
};

Each node's compatible property is tried in order. The first matching binding is used. The on-bus:
key can be used to refine the search.

If more than one binding for a compatible is found, an error is raised.

The manufacturer prefix identifies the device vendor. See dts/bindings/vendor-prefixes.txt for a
list of accepted vendor prefixes. The device part is usually from the datasheet.
Some bindings apply to a generic class of devices which do not have a specific vendor. In these cases, there is no vendor prefix. One example is the gpio-leds compatible which is commonly used to describe board LEDs connected to GPIOs.

**Properties**  The properties: key describes properties that nodes which match the binding contain. For example, a binding for a UART peripheral might look something like this:

```plaintext
compatible: "manufacturer,serial"

properties:
  reg:
    type: array
    description: UART peripheral MMIO register space
    required: true
  current-speed:
    type: int
    description: current baud rate
    required: true
```

In this example, a node with compatible "manufacturer,serial" must contain a node named current-speed. The property's value must be a single integer. Similarly, the node must contain a reg property.

The build system uses bindings to generate C macros for devicetree properties that appear in DTS files. You can read more about how to get property values in source code from these macros in *Devicetree access from C/C++*. Generally speaking, the build system only generates macros for properties listed in the properties: key for the matching binding. Properties not mentioned in the binding are generally ignored by the build system.

The one exception is that the build system will always generate macros for standard properties, like reg, whose meaning is defined by the devicetree specification. This happens regardless of whether the node has a matching binding or not.

**Property entry syntax**  Property entries in properties: are written in this syntax:

```plaintext
<property name>:
  required: <true | false>
  type: <string | int | boolean | array | uint8-array | string-array |
           phandle | phandles | phandle-array | path | compound>
  deprecated: <true | false>
  default: <default>
  description: <description of the property>
  enum:
    - <item1>
    - <item2>
    ...
  const: <string | int | array | uint8-array | string-array>
  specifier-space: <space-name>
```

**Example property definitions**  Here are some more examples.

```plaintext
properties:
  # Describes a property like 'current-speed = <115200>;'. We pretend that
  # it's obligatory for the example node and set 'required: true'.
  current-speed:
    type: int
    required: true
```

(continues on next page)
**description**: Initial baud rate for bar-device

```yaml
# Describes an optional property like 'keys = "foo", "bar"';
keys:
  type: string-array
  description: Keys for bar-device
```

```yaml
# Describes an optional property like 'maximum-speed = "full-speed"';
# the enum specifies known values that the string property may take
maximum-speed:
  type: string
  description: Configures USB controllers to work up to a specific speed.
  enum:
    - "low-speed"
    - "full-speed"
    - "high-speed"
    - "super-speed"
```

```yaml
# Describes an optional property like 'resolution = <16>;'
# the enum specifies known values that the int property may take
resolution:
  type: int
  enum:
    - 8
    - 16
    - 24
    - 32
```

```yaml
# Describes a required property '#address-cells = <1>'; the const
# specifies that the value for the property is expected to be the value 1
#address-cells:
  type: int
  required: true
  const: 1
```

```yaml
int-with-default:
  type: int
  default: 123
  description: Value for int register, default is power-up configuration.
```

```yaml
array-with-default:
  type: array
  default: [1, 2, 3] # Same as 'array-with-default = <1 2 3>'
```

```yaml
string-with-default:
  type: string
  default: "foo"
```

```yaml
string-array-with-default:
  type: string-array
  default: ["foo", "bar"] # Same as 'string-array-with-default = "foo", "bar"'
```

```yaml
uint8-array-with-default:
  type: uint8-array
  default: [0x12, 0x34] # Same as 'uint8-array-with-default = [12 34]'
```

**required** Adding `required: true` to a property definition will fail the build if a node matches the binding, but does not contain the property.

The default setting is `required: false`; that is, properties are optional by default. Using `required: false` is therefore redundant and strongly discouraged.
type The type of a property constrains its values. The following types are available. See Writing property values for more details about writing values of each type in a DTS file. See Phandles for more information about the phandle* type properties.

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
<th>Example in DTS</th>
</tr>
</thead>
<tbody>
<tr>
<td>string</td>
<td>exactly one string</td>
<td>status = &quot;disabled&quot;;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>current-speed = &lt;115200&gt;;</td>
</tr>
<tr>
<td>int</td>
<td>exactly one 32-bit value (cell)</td>
<td></td>
</tr>
<tr>
<td>boolean</td>
<td>flags that don’t take a value when true, and are absent if false</td>
<td>hw-flow-control;</td>
</tr>
<tr>
<td>array</td>
<td>zero or more 32-bit values (cells)</td>
<td>offsets = &lt;0x100 0x200 0x300&gt;;</td>
</tr>
<tr>
<td>uint8-array</td>
<td>zero or more bytes, in hex (‘bytestring’ in the Devicetree specification)</td>
<td>local-mac-address = [de ad be ef 12 34];</td>
</tr>
<tr>
<td>string-array</td>
<td>zero or more strings</td>
<td>dma-names = &quot;tx&quot;, &quot;rx&quot;;</td>
</tr>
<tr>
<td>phandle</td>
<td>exactly one phandle</td>
<td>interrupt-parent = &lt;&amp;gic&gt;;</td>
</tr>
<tr>
<td>ph(handles)</td>
<td>zero or more phandles</td>
<td></td>
</tr>
<tr>
<td>phandle-array</td>
<td>a list of phandles and 32-bit cells (usually specifiers)</td>
<td>dmas = &lt;&amp;dma0 2&gt;, &lt;&amp;dma0 3&gt;;</td>
</tr>
<tr>
<td>path</td>
<td>a path to a node as a phandle path reference or path string</td>
<td>zephyr, bt-c2h-uart = &amp;uart0; or foo = &quot;/path/to/some/node&quot;;</td>
</tr>
<tr>
<td>compound</td>
<td>a catch-all for more complex types (no macros will be generated)</td>
<td>foo = &lt;&amp;label&gt;, [01 02];</td>
</tr>
</tbody>
</table>

deprecated A property with deprecated: true indicates to both the user and the tooling that the property is meant to be phased out.

The tooling will report a warning if the devicetree includes the property that is flagged as deprecated. (This warning is upgraded to an error in the Test Runner (Twister) for upstream pull requests.)

The default setting is deprecated: false. Using deprecated: false is therefore redundant and strongly discouraged.

default The optional default: setting gives a value that will be used if the property is missing from the devicetree node.

For example, with this binding fragment:

```yaml
properties:
  foo:
    type: int
    default: 3
```

If property foo is missing in a matching node, then the output will be as if `foo = <3>;` had appeared in the DTS (except YAML data types are used for the default value).

Note that combining default: with required: true will raise an error.

For rules related to default in upstream Zephyr bindings, see Rules for default values.

See Example property definitions for examples. Putting default: on any property type besides those used in Example property definitions will raise an error.
**enum**  The enum: line is followed by a list of values the property may contain. If a property value in DTS is not in the enum: list in the binding, an error is raised. See *Example property definitions* for examples.

**const**  This specifies a constant value the property must take. It is mainly useful for constraining the values of common properties for a particular piece of hardware.

**Warning:** It is an abuse of this feature to use it to name properties in unconventional ways. For example, this feature is not meant for cases like naming a property my-pin, then assigning it to the “gpio” specifier space using this feature. Properties which refer to GPIOs should use conventional names, i.e. end in -gpios or -gpio.

**specifier-space**  This property, if present, manually sets the specifier space associated with a property with type phandle-array.

Normally, the specifier space is encoded implicitly in the property name. A property named foos with type phandle-array implicitly has specifier space foo. As a special case, *-gpios properties have specifier space “gpio”, so that foo-gpios will have specifier space “gpio” rather than “foo-gpio”.

You can use specifier-space to manually provide a space if using this convention would result in an awkward or unconventional name.

For example:

```
compatible: ...
properties:
  bar:
    type: phandle-array
    specifier-space: my-custom-space
```

Above, the bar property's specifier space is set to “my-custom-space”.

You could then use the property in a devicetree like this:

```
controller1: custom-controller@1000 {
  #my-custom-space-cells = <2>;
};
controller2: custom-controller@2000 {
  #my-custom-space-cells = <1>;
};
my-node {
  bar = <&controller1 10 20>, <&controller2 30>;
};
```

Generally speaking, you should reserve this feature for cases where the implicit specifier space naming convention doesn’t work. One appropriate example is an mboxes property with specifier space “mbox”, not “mboxe”. You can write this property as follows:

```
properties:
  mboxes:
    type: phandle-array
    specifier-space: mbox
```
**Child-binding**  child-binding can be used when a node has children that all share the same properties. Each child gets the contents of child-binding as its binding, though an explicit compatible = ... on the child node takes precedence, if a binding is found for it.

Consider a binding for a PWM LED node like this one, where the child nodes are required to have a pwms property:

```dts
pwmleds {
    compatible = "pwm-leds";
    red_pwmled {
        pwms = <&pwm3 4 15625000>;
    };
    green_pwmled {
        pwms = <&pwm3 0 15625000>;
    };
    /* ... */
};
```

The binding would look like this:

```dts
compatible: "pwm-leds"

child-binding:
    description: LED that uses PWM
    properties:
        pwms:
            type: phandle-array
            required: true
```

child-binding also works recursively. For example, this binding:

```dts
compatible: foo

child-binding:
    child-binding:
        properties:
            my-property:
                type: int
                required: true
```

will apply to the grandchild node in this DTS:

```dts
parent {
    compatible = "foo";
    child {
        grandchild {
            my-property = <123>;
        };
    };
};
```

**Bus**  If the node is a bus controller, use bus: in the binding to say what type of bus. For example, a binding for a SPI peripheral on an SoC would look like this:

```dts
compatible: "manufacturer,spi-peripheral"
bus: spi
# ...
```

The presence of this key in the binding informs the build system that the children of any node matching this binding appear on this type of bus.
This in turn influences the way on-bus: is used to match bindings for the child nodes.

For a single bus supporting multiple protocols, e.g. I3C and I2C, the bus: in the binding can have a list as value:

```yaml
compatible: "manufacturer,i3c-controller"
bis: [i3c, i2c]
```

**On-bus**

If the node appears as a device on a bus, use on-bus: in the binding to say what type of bus.

For example, a binding for an external SPI memory chip should include this line:

```yaml
on-bus: spi
```

And a binding for an I2C based temperature sensor should include this line:

```yaml
on-bus: i2c
```

When looking for a binding for a node, the build system checks if the binding for the parent node contains `bus: <bus type>`. If it does, then only bindings with a matching `on-bus: <bus type>` and bindings without an explicit on-bus are considered. Bindings with an explicit on-bus: <bus type> are searched for first, before bindings without an explicit on-bus. The search repeats for each item in the node's compatible property, in order.

This feature allows the same device to have different bindings depending on what bus it appears on. For example, consider a sensor device with compatible manufacturer,sensor which can be used via either I2C or SPI.

The sensor node may therefore appear in the devicetree as a child node of either an SPI or an I2C controller, like this:

```yaml
spi-bus@
  /* ... some compatible with 'bus: spi', etc. ... */
  sensor@
    compatible = "manufacturer,sensor"
    reg = <0>
    /* ... */
  
; i2c-bus@
  /* ... some compatible with 'bus: i2c', etc. ... */
  sensor@79
    compatible = "manufacturer,sensor"
    reg = <79>
    /* ... */
  
; 
```

You can write two separate binding files which match these individual sensor nodes, even though they have the same compatible:

```yaml
# manufacturer,sensor-spi.yaml, which matches sensor@0 on the SPI bus:
compatible: "manufacturer,sensor"
on-bus: spi
```

```yaml
# manufacturer,sensor-i2c.yaml, which matches sensor@79 on the I2C bus:
compatible: "manufacturer,sensor"
```
Only sensor@79 can have a use-clock-stretching property. The bus-sensitive logic ignores 
manufacturer, sensor-i2c.yaml when searching for a binding for sensor@0.

**Specifier cell names (⋆-cells)** This section documents how to name the cells in a specifier 
within a binding. These concepts are discussed in detail later in this guide in *phandle-array 
properties*.

Consider a binding for a node whose phandle may appear in a phandle-array property, like the 
PWM controllers pwm1 and pwm2 in this example:

```yaml
pwm1: pwm@deadbeef {
   compatible = "foo,pwm";
   #pwm-cells = <2>;
};
pwm2: pwm@deadbeef {
   compatible = "bar,pwm";
   #pwm-cells = <1>;
};
my-node {
   pwms = <&pwm1 1 2000>, <&pwm2 3000>;
};
```

The bindings for compatible "foo,pwm" and "bar,pwm" must give a name to the cells that appear 
in a PWM specifier using pwn-cells:, like this:

```yaml
# foo,pwm.yaml
compatible: "foo,pwm"
... 
pwm-cells:
   - channel
   - period

# bar,pwm.yaml
compatible: "bar,pwm"
... 
pwm-cells:
   - period
```

A ⋆-names (e.g. pwm-names) property can appear on the node as well, giving a name to each entry.
This allows the cells in the specifiers to be accessed by name, e.g. using APIs like 
*DT_PWMS_CHANNEL_BY_NAME*.

If the specifier is empty (e.g. #clock-cells = <0>), then ⋆-cells can either be omitted (recommended) or set to an empty array. Note that an empty array is specified as e.g. clock-cells: [] 
in YAML.

**Include** Bindings can include other files, which can be used to share common property defini-
tions between bindings. Use the include: key for this. Its value is either a string or a list.
In the simplest case, you can include another file by giving its name as a string, like this:
If any file named `foo.yaml` is found (see *Where bindings are located* for the search process), it will be included into this binding.

Included files are merged into bindings with a simple recursive dictionary merge. The build system will check that the resulting merged binding is well-formed. It is allowed to include at any level, including child-binding, like this:

```yaml
include: foo.yaml

child-binding:
  include: bar.yaml
```

It is an error if a key appears with a different value in a binding and in a file it includes, with one exception: a binding can have `required: true` for a property definition for which the included file has `required: false`. The `required: true` takes precedence, allowing bindings to strengthen requirements from included files.

Note that weakening requirements by having `required: false` where the included file has `required: true` is an error. This is meant to keep the organization clean.

The file `base.yaml` contains definitions for many common properties. When writing a new binding, it is a good idea to check if `base.yaml` already defines some of the needed properties, and include it if it does.

Note that you can make a property defined in `base.yaml` obligatory like this, taking `reg` as an example:

```yaml
reg:
  required: true
```

This relies on the dictionary merge to fill in the other keys for `reg`, like `type`.

To include multiple files, you can use a list of strings:

```yaml
include:
  - foo.yaml
  - bar.yaml
```

This includes the files `foo.yaml` and `bar.yaml`. (You can write this list in a single line of YAML as `include: [foo.yaml, bar.yaml].`)

When including multiple files, any overlapping `required` keys on properties in the included files are ORed together. This makes sure that a `required: true` is always respected.

In some cases, you may want to include some property definitions from a file, but not all of them. In this case, `include:` should be a list, and you can filter out just the definitions you want by putting a mapping in the list, like this:

```yaml
include:
  - name: foo.yaml
    property-allowlist:
      - i-want-this-one
      - and-this-one
  - name: bar.yaml
    property-blocklist:
      - do-not-include-this-one
      - or-this-one
```

Each map element must have a `name` key which is the filename to include, and may have `property-allowlist` and `property-blocklist` keys that filter which properties are included.
You cannot have a single map element with both property-allowlist and property-blocklist keys. A map element with neither property-allowlist nor property-blocklist is valid; no additional filtering is done.

You can freely intermix strings and mappings in a single include:

```yaml
include:
- foo.yaml
- name: bar.yaml
  property-blocklist:
  - do-not-include-this-one
  - or-this-one
```

Finally, you can filter from a child binding like this:

```yaml
include:
- name: bar.yaml
  child-binding:
    property-allowlist:
    - child-prop-to-allow
```

**Nexus nodes and maps** All phandle-array type properties support mapping through *-map properties, e.g. gpio-map, as defined by the Devicetree specification.

This is used, for example, to define connector nodes for common breakout headers, such as the arduino_header nodes that are conventionally defined in the devicetrees for boards with Arduino compatible expansion headers.

**Rules for upstream bindings** This section includes general rules for writing bindings that you want to submit to the upstream Zephyr Project. (You don’t need to follow these rules for bindings you don’t intend to contribute to the Zephyr Project, but it’s a good idea.)

Decisions made by the Zephyr devicetree maintainer override the contents of this section. If that happens, though, please let them know so they can update this page, or you can send a patch yourself.

**Contents**

- Always check for existing bindings
- General rules
  - File names
  - Recommendations are requirements
  - Descriptions
  - Naming conventions
- Rules for vendor prefixes
- Rules for default values
- The zephyr, prefix

**Always check for existing bindings** Zephyr aims for devicetree source compatibility with other operating systems. Therefore, if there is an existing binding for your device in an authoritative location, you should try to replicate its properties when writing a Zephyr binding, and you must justify any Zephyr-specific divergences.
In particular, this rule applies if:

- There is an existing binding in the mainline Linux kernel. See `Documentation/devicetree/bindings` in Linus's tree for existing bindings and the Linux devicetree documentation for more information.
- Your hardware vendor provides an official binding outside of the Linux kernel.

**General rules**

**File names**  Bindings which match a compatible must have file names based on the compatible.

- For example, a binding for compatible `vnd,foo` must be named `vnd,foo.yaml`.
- If the binding is bus-specific, you can append the bus to the file name; for example, if the binding YAML has `on-bus: bar`, you may name the file `vnd,foo-bar.yaml`.

**Recommendations are requirements**  All recommendations in `default` are requirements when submitting the binding.

In particular, if you use the `default:` feature, you must justify the value in the property's description.

**Descriptions**  There are only two acceptable ways to write property description: strings.

If your description is short, it's fine to use this style:

```
description: my short string
```

If your description is long or spans multiple lines, you must use this style:

```
description:
| My very long string goes here.
| Look at all these lines!
```

This style prevents YAML parsers from removing the newlines in multi-line descriptions. This in turn makes these long strings display properly in the *Bindings index*.

**Naming conventions**  Do not use uppercase letters (A through Z) or underscores (_) in property names. Use lowercase letters (a through z) instead of uppercase. Use dashes (-) instead of underscores. (The one exception to this rule is if you are replicating a well-established binding from somewhere like Linux.)

**Rules for vendor prefixes**  The following general rules apply to vendor prefixes in `compatible` properties.

- If your device is manufactured by a specific vendor, then its compatible should have a vendor prefix.

  If your binding describes hardware with a well known vendor from the list in `dts/bindings/vendor-prefixes.txt`, you must use that vendor prefix.

- If your device is not manufactured by a specific hardware vendor, do **not** invent a vendor prefix. Vendor prefixes are not mandatory parts of compatible properties, and compatibles should not include them unless they refer to an actual vendor. There are some exceptions to this rule, but the practice is strongly discouraged.
Do not submit additions to Zephyr's `dts/bindings/vendor-prefixes.txt` file unless you also include users of the new prefix. This means at least a binding and a devicetree using the vendor prefix, and should ideally include a device driver handling that compatible.

For custom bindings, you can add a custom `dts/bindings/vendor-prefixes.txt` file to any directory in your `DTS_ROOT`. The devicetree tooling will respect these prefixes, and will not generate warnings or errors if you use them in your own bindings or devicetrees.

- We sometimes synchronize Zephyr's vendor-prefixes.txt file with the Linux kernel's equivalent file; this process is exempt from the previous rule.
- If your binding is describing an abstract class of hardware with Zephyr specific drivers handling the nodes, it's usually best to use `zephyr` as the vendor prefix. See Zephyr-specific binding (zephyr) for examples.

Rules for default values

In any case where `default:` is used in a devicetree binding, the `description:` for that property **must** explain why the value was selected and any conditions that would make it necessary to provide a different value. Additionally, if changing one property would require changing another to create a consistent configuration, then those properties should be made required.

There is no need to document the default value itself; this is already present in the `Bindings index` output.

There is a risk in using `default:` when the value in the binding may be incorrect for a particular board or hardware configuration. For example, defaulting the capacity of the connected power cell in a charging IC binding is likely to be incorrect. For such properties it's better to make the property `required: true`, forcing the user to make an explicit choice.

Driver developers should use their best judgment as to whether a value can be safely defaulted. Candidates for default values include:

- delays that would be different only under unusual conditions (such as intervening hardware)
- configuration for devices that have a standard initial configuration (such as a USB audio headset)
- defaults which match the vendor-specified power-on reset value (as long as they are independent from other properties)

Examples of how to write descriptions according to these rules:

```
properties:
  cs-interval:
    type: int
    default: 0
    description: |
      Minimum interval between chip select deassertion and assertion.
      The default corresponds to the reset value of the register field.

  hold-time-ms:
    type: int
    default: 20
    description: |
      Amount of time to hold the power enable GPIO asserted before
      initiating communication. The default was recommended in the
      manufacturer datasheet, and would only change under very
      cold temperatures.
```

Some examples of what **not** to do, and why:

```
properties:
  # Description doesn't mention anything about the default
```

(continues on next page)
The `zephyr` prefix You must add this prefix to property names in the following cases:

- Zephyr-specific extensions to bindings we share with upstream Linux. One example is the `zephyr,vref-mv` ADC channel property which is common to ADC controllers defined in `dts/bindings/adc/adc-controller.yaml`. This channel binding is partially shared with an analogous Linux binding, and Zephyr-specific extensions are marked as such with the prefix.

- Configuration values that are specific to a Zephyr device driver. One example is the `zephyr,lazy-load` property in the `ti,bq274xx` binding. Though `devicetree` in general is a hardware description and configuration language, it is Zephyr’s only mechanism for configuring driver behavior for an individual `struct device`. Therefore, as a compromise, we do allow some software configuration in Zephyr’s `devicetree` bindings, as long as they use this prefix to show that they are Zephyr specific.

You may use the `zephyr` prefix when naming a devicetree compatible that is specific to Zephyr. One example is `zephyr,ipc-openamp-static-vrings`. In this case, it’s permitted but not required to add the `zephyr` prefix to properties defined in the binding.

Devicetree access from C/C++

This guide describes Zephyr’s `<zephyr/devicetree.h>` API for reading the devicetree from C source files. It assumes you’re familiar with the concepts in *Introduction to devicetree* and *Devicetree bindings*. See *Devicetree Reference* for reference material.

A note for Linux developers Linux developers familiar with `devicetree` should be warned that the API described here differs significantly from how `devicetree` is used on Linux.

Instead of generating a C header with all the devicetree data which is then abstracted behind a macro API, the Linux kernel would instead read the devicetree data structure in its binary form. The binary representation is parsed at runtime, for example to load and initialize device drivers.

Zephyr does not work this way because the size of the devicetree binary and associated handling code would be too large to fit comfortably on the relatively constrained devices Zephyr supports.
Node identifiers  To get information about a particular devicetree node, you need a node identifier for it. This is a just a C macro that refers to the node.

These are the main ways to get a node identifier:

By path
Use \texttt{DT\_PATH()} along with the node's full path in the devicetree, starting from the root node. This is mostly useful if you happen to know the exact node you're looking for.

By node label
Use \texttt{DT\_NODELABEL()} to get a node identifier from a node label. Node labels are often provided by SoC .dtsi files to give nodes names that match the SoC datasheet, like i2c1, spi2, etc.

By alias
Use \texttt{DT\_ALIAS()} to get a node identifier for a property of the special /aliases node. This is sometimes done by applications (like blinky, which uses the led0 alias) that need to refer to some device of a particular type (“the board's user LED”) but don't care which one is used.

By instance number
This is done primarily by device drivers, as instance numbers are a way to refer to individual nodes based on a matching compatible. Get these with \texttt{DT\_INST()}, but be careful doing so. See below.

By chosen node
Use \texttt{DT\_CHosen()} to get a node identifier for /chosen node properties.

By parent/child
Use \texttt{DT\_PARENT()} and \texttt{DT\_CHILD()} to get a node identifier for a parent or child node, starting from a node identifier you already have.

Two node identifiers which refer to the same node are identical and can be used interchangeably.

Here's a DTS fragment for some imaginary hardware we'll return to throughout this file for examples:

```dts
/dts-v1/;
/
{
    aliases {
        sensor-controller = &i2c1;
    };
    soc {
        i2c1: i2c@40002000 {
            compatible = "vnd,soc-i2c";
            label = "I2C_1";
            reg = <0x40002000 0x1000>;
            status = "okay";
            clock-frequency = <100000 >;
        }
    };
}
```

Here are a few ways to get node identifiers for the i2c@40002000 node:

- \texttt{DT\_PATH(soc, i2c_40002000)}
- \texttt{DT\_NODELABEL(i2c1)}
- \texttt{DT\_ALIAS(sensor\_controller)}
- \texttt{DT\_INST(x, vnd_soc_i2c)} for some unknown number x. See the \texttt{DT\_INST()} documentation for details.
**Important:** Non-alphanumeric characters like dash (-) and the at sign (@) in devicetree names are converted to underscores (_). The names in a DTS are also converted to lowercase.

**Node identifiers are not values** There is no way to store one in a variable. You cannot write:

```c
/* These will give you compiler errors: */
void *i2c_0 = DT_INST(0, vnd_soc_i2c);
unsigned int i2c_1 = DT_INST(1, vnd_soc_i2c);
long my_i2c = DT_NODELABEL(i2c1);
```

If you want something short to save typing, use C macros:

```c
/* Use something like this instead: */
#define MY_I2C DT_NODELABEL(i2c1)
#define INST(i) DT_INST(i, vnd_soc_i2c)
#define I2C_0 INST(0)
#define I2C_1 INST(1)
```

**Property access** The right API to use to read property values depends on the node and property.

- **Checking properties and values**
- **Simple properties**
- **reg properties**
- **interrupts properties**
- **phandle properties**

**Checking properties and values** You can use `DT_NODE_HAS_PROP()` to check if a node has a property. For the example devicetree above:

```c
DT_NODE_HAS_PROP(DT_NODELABEL(i2c1), clock_frequency) /* expands to 1 */
DT_NODE_HAS_PROP(DT_NODELABEL(i2c1), not_a_property) /* expands to 0 */
```

**Simple properties** Use `DT_PROP(node_id, property)` to read basic integer, boolean, string, numeric array, and string array properties.

For example, to read the clock-frequency property's value in the above example:

```c
DT_PROP(DT_PATH(soc, i2c_40002000), clock_frequency) /* This is 100000, */
DT_PROP(DT_NODELABEL(i2c1), clock_frequency) /* and so is this, */
DT_PROP(DT_ALIAS(sensor_controller), clock_frequency) /* and this. */
```

**Important:** The DTS property clock-frequency is spelled `clock_frequency` in C. That is, properties also need special characters converted to underscores. Their names are also forced to lowercase.

Properties with string and boolean types work the exact same way. The `DT_PROP()` macro expands to a string literal in the case of strings, and the number 0 or 1 in the case of booleans. For example:
```c
#define I2C1 DT_NODELABEL(i2c1)
DT_PROP(I2C1, status)  /*!< expands to the string literal "okay" */
```

**Note:** Don’t use DT_NODE_HAS_PROP() for boolean properties. Use DT_PROP() instead as shown above. It will expand to either 0 or 1 depending on if the property is present or absent.

Properties with type array, uint8-array, and string-array work similarly, except DT_PROP() expands to an array initializer in these cases. Here is an example devicetree fragment:

```c
foo: foo@1234 {
    a = <1000 2000 3000>;  /*!< array */
    b = [aa bb cc dd];  /*!< uint8-array */
    c = "bar", "baz";  /*!< string-array */
};
```

Its properties can be accessed like this:

```c
#define FOO DT_NODELABEL(foo)
int a[] = DT_PROP(FOO, a);  /*!< {1000, 2000, 3000} */
unsigned char b[] = DT_PROP(FOO, b);  /*!< {0xaa, 0xbb, 0xcc, 0xdd} */
char* c[] = DT_PROP(FOO, c);  /*!< {"foo", "bar"} */
```

You can use `DT_PROP_LEN()` to get logical array lengths in number of elements.

```c
size_t a_len = DT_PROP_LEN(FOO, a);  /*!< 3 */
size_t b_len = DT_PROP_LEN(FOO, b);  /*!< 4 */
size_t c_len = DT_PROP_LEN(FOO, c);  /*!< 2 */
```

`DT_PROP_LEN()` cannot be used with the special reg or interrupts properties. These have alternative macros which are described next.

**reg properties**  See *Important properties* for an introduction to reg.

Given a node identifier `node_id`, `DT_NUM_REGS(node_id)` is the total number of register blocks in the node’s reg property.

You **cannot** read register block addresses and lengths with `DT_PROP(node, reg)`. Instead, if a node only has one register block, use `DT_REG_ADDR()` or `DT_REG_SIZE()`:

- `DT_REG_ADDR(node_id)`: the given node’s register block address
- `DT_REG_SIZE(node_id)`: its size

Use `DT_REG_ADDR_BY_IDX()` or `DT_REG_SIZE_BY_IDX()` instead if the node has multiple register blocks:

- `DT_REG_ADDR_BY_IDX(node_id, idx)`: address of register block at index `idx`
- `DT_REG_SIZE_BY_IDX(node_id, idx)`: size of block at index `idx`

The `idx` argument to these must be an integer literal or a macro that expands to one without requiring any arithmetic. In particular, `idx` cannot be a variable. This won’t work:

```c
/* This will cause a compiler error. */

for (size_t i = 0; i < DT_NUM_REGS(node_id); i++) {
    size_t addr = DT_REG_ADDR_BY_IDX(node_id, i);
}
```
**interrupts properties**  See *Important properties* for a brief introduction to interrupts.

Given a node identifier `node_id`, `DT_NUM_IRQS(node_id)` is the total number of interrupt specifiers in the node's interrupts property.

The most general purpose API macro for accessing these is `DT_IRQ_BY_IDX()`:

```
DT_IRQ_BY_IDX(node_id, idx, val)
```

Here, `idx` is the logical index into the `interrupts` array, i.e. it is the index of an individual interrupt specifier in the property. The `val` argument is the name of a cell within the interrupt specifier. To use this macro, check the bindings file for the node you are interested in to find the `val` names.

Most Zephyr devicetree bindings have a cell named `irq`, which is the interrupt number. You can use `DT_IRQN()` as a convenient way to get a processed view of this value.

**Warning:** Here, “processed” reflects Zephyr's devicetree *Scripts and tools*, which change the `irq` number in `zephyr.dts` to handle hardware constraints on some SoCs and in accordance with Zephyr's multilevel interrupt numbering.

This is currently not very well documented, and you'll need to read the scripts' source code and existing drivers for more details if you are writing a device driver.

**phandle properties**  
**Note:** See *Phandles* for a detailed guide to phandles.

Property values can refer to other nodes using the `&another-node` phandle syntax introduced in *Writing property values*. Properties which contain phandles have type `phandle`, `phandles`, or `phandle-array` in their bindings. We'll call these “phandle properties” for short.

You can convert a phandle to a node identifier using `DT_PHANDLE()`, `DT_PHANDLE_BY_IDX()`, or `DT_PHANDLE_BY_NAME()`, depending on the type of property you are working with.

One common use case for phandle properties is referring to other hardware in the tree. In this case, you usually want to convert the devicetree-level phandle to a Zephyr driver-level `struct device`. See *Get a struct device from a devicetree node* for ways to do that.

Another common use case is accessing specifier values in a phandle array. The general purpose APIs for this are `DT_PHA_BY_IDX()` and `DT_PHA()`. There are also hardware-specific short-hands like `DT_GPIO_CTLR_BY_IDX()`, `DT_GPIO_CTLR()`, `DT_GPIO_PIN_BY_IDX()`, `DT_GPIO_PIN()`, `DT_GPIO_FLAGS_BY_IDX()`, and `DT_GPIO_FLAGS()`.

See `DT_PHA_HAS_CELL_AT_IDX()` and `DT_PROP_HAS_IDX()` for ways to check if a specifier value is present in a phandle property.

**Other APIs**  Here are pointers to some other available APIs.

- `DT_CHOSEN()`, `DT_HAS_CHOSEN()`: for properties of the special `/chosen` node
- `DT_HAS_COMPAT_STATUS_OKAY()`, `DT_NODE_HAS_COMPAT()`: global- and node-specific tests related to the compatible property
- `DT_BUS()`: get a node's bus controller, if there is one
- `DT_ENUM_IDX()`: for properties whose values are among a fixed list of choices
- Fixed flash partitions: APIs for managing fixed flash partitions. Also see *Flash map*, which wraps this in a more user-friendly API.
Device driver conveniences Special purpose macros are available for writing device drivers, which usually rely on instance identifiers.

To use these, you must define DT_DRV_COMPAT to the compat value your driver implements support for. This compat value is what you would pass to DT_INST().

If you do that, you can access the properties of individual instances of your compatible with less typing, like this:

```c
#include <zephyr/devicetree.h>

#define DT_DRV_COMPAT my_driver_compat

/* This is same thing as DT_INST(0, my_driver_compat): */
DT_DRV_INST(0)

/* This is the same thing as
   DT_PROP(DT_INST(0, my_driver_compat), clock_frequency)
*/
DT_INST_PROP(0, clock_frequency)
```

See Instance-based APIs for a generic API reference.

Hardware specific APIs Convenience macros built on top of the above APIs are also defined to help readability for hardware specific code. See Hardware specific APIs for details.

Generated macros While the zephyr/devicetree.h API is not generated, it does rely on a generated C header which is put into every application build directory: devicetree_generated.h. This file contains macros with devicetree data.

These macros have tricky naming conventions which the Devicetree API API abstracts away. They should be considered an implementation detail, but it's useful to understand them since they will frequently be seen in compiler error messages.

This section contains an Augmented Backus-Naur Form grammar for these generated macros, with examples and more details in comments. See RFC 7405 (which extends RFC 5234) for a syntax specification.

```plaintext
; An RFC 7405 ABNF grammar for devicetree macros.
;
; This does *not* cover macros pulled out of DT via Kconfig,
; like CONFIG_SRAM_BASE_ADDRESS, etc. It only describes the
; ones that start with DT_ and are directly generated.

; dt-macro: the top level nonterminal for a devicetree macro
;
; A dt-macro starts with uppercase "DT",
 ; and is one of:
 ; - a <node-macro>, generated for a particular node
 ; - some <other-macro>, a catch-all for other types of macros
 dt-macro = node-macro / other-macro

; node-macro: a macro related to a node
 node-macro = property-macro
 ; A macro about a property value
 ; A macro about the pinctrl properties in a node.
 node-macro = / pinctrl-macro
```

(continues on next page)
; A macro about the GPIO hog properties in a node.
node-macro =/ gpiohogs-macro
; EXISTS macro: node exists in the devicetree
node-macro =/ %"DT_N" path-id %"_EXISTS"

; Bus macros: the plain BUS is a way to access a node's bus controller.
; The additional dt-name suffix is added to match that node's bus type;
; the dt-name in this case is something like "spi" or "i2c".
node-macro =/ %"DT_N" path-id %"BUS " ["_" dt-name]

; The reg property is special and has its own macros.
node-macro =/ %"DT_N" path-id %"_REG_NUM"
node-macro =/ %"DT_N" path-id %"_REG_IDX_" DIGIT ".EXISTS"
node-macro =/ %"DT_N" path-id %"_REG_IDX_" DIGIT
%".VAL_" dt-name [ %".EXISTS" ]
node-macro =/ %"DT_N" path-id %"_CONTROLLER"
node-macro =/ %"DT_N" path-id %"_IRQ_NAME_" dt-name
%".VAL_" dt-name [ %".EXISTS" ]
node-macro =/ %"DT_N" path-id %"_IRQ_NAME_" dt-name ".CONTROLLER"

; The ranges property is also special.
node-macro =/ %"DT_N" path-id %"_RANGES_NUM"
node-macro =/ %"DT_N" path-id %"_RANGES_IDX_" DIGIT ".EXISTS"
node-macro =/ %"DT_N" path-id %"_RANGES_IDX_" DIGIT
%".VAL_" ( %"CHILD_BUS_FLAGS" / %"CHILD_BUS_ADDRESS" / %"PARENT_BUS_ADDRESS" / %"LENGTH" )
node-macro =/ %"DT_N" path-id %"RANGES_IDX_" DIGIT
%".VAL_CHILD_BUS_FLAGS_EXISTS"
node-macro =/ %"DT_N" path-id %"FOREACH_RANGE"
; Subnodes of the fixed-partitions compatible get macros which contain
; a unique ordinal value for each partition
node-macro =/ %"DT_N" path-id %"_PARTITION_ID" DIGIT
; Macros are generated for each of a node's compatibles;
; dt-name in this case is something like "vnd_device"
node-macro =/ %"DT_N" path-id %"_COMPAT_MATCHES_" dt-name
node-macro =/ %"DT_N" path-id %"_COMPAT_VENDOR_IDX_" DIGIT ".EXISTS"
node-macro =/ %"DT_N" path-id %"_COMPAT_VENDOR_IDX_" DIGIT
%".VAL_" dt-name [ %".EXISTS" ]
node-macro =/ %"DT_N" path-id %"_COMPAT_MODEL_IDX_" DIGIT ".EXISTS"
node-macro =/ %"DT_N" path-id %"_COMPAT_MODEL_IDX_" DIGIT
; Every non-root node gets one of these macros, which expands to the node
; identifier for that node's parent in the devicetree.
node-macro =/ %"DT_N" path-id %"_PARENT"
; These are used internally by DT_FOREACH_PROP_ELEM(SEP)(_VARGS), which
; iterates over each property element.
node-macro =/ %"DT_N" path-id %"_FOREACH_PROP_ELEM" %"_FOREACH_PROP_ELEM_SEP"
node-macro =/ %"DT_N" path-id %"_FOREACH_PROP_ELEM_SEP_VARGS"
node-macro =/ %"DT_N" path-id %"FOREACH_PROP_ELEM_VARGS"
; These are used internally by DT_FOREACH_CHILD, which iterates over
; each child node.
node-macro =/ %"DT_N" path-id %"FOREACH_CHILD"
node-macro =/ %"DT_N" path-id %"FOREACH_CHILD_SEP"
node-macro =/ %"DT_N" path-id %"FOREACH_CHILD_SEP_VARGS"
node-macro =/ %"DT_N" path-id %"FOREACH_CHILD_VARGS"

(continues on next page)
node-macro = %s"DT_N" path-id %s"_FOREACH_CHILD_STATUS_OKAY"
node-macro = %s"DT_N" path-id %s"_FOREACH_CHILD_STATUS_OKAY_SEP"
node-macro = %s"DT_N" path-id %s"_FOREACH_CHILD_STATUS_OKAY_VARGS"
; The node's zero-based index in the list of it's parent's child nodes.
node-macro = %s"DT_N" path-id %s"_CHILD_IDX"
; The node's status macro; dt-name in this case is something like "okay" or "disabled".
node-macro = %s"DT_N" path-id %s"_STATUS_" dt-name
; The node's dependency ordinal. This is a non-negative integer value that is used to represent dependency information.
node-macro = %s"DT_N" path-id %s"_ORD"
; The node's path, as a string literal
node-macro = %s"DT_N" path-id %s"_PATH"
; The node's name@unit-addr, as a string literal
node-macro = %s"DT_N" path-id %s"_FULL_NAME"
; The dependency ordinals of a node's requirements (direct dependencies).
node-macro = %s"DT_N" path-id %s"_REQUIRES_ORDS"
; The dependency ordinals of a node supports (reverse direct dependencies).
node-macro = %s"DT_N" path-id %s"_SUPPORTS_ORDS"

-------------------------------------------------------------------------------------------------

; pinctrl-macro: a macro related to the pinctrl properties in a node

; These are a bit of a special case because they kind of form an array, but the array indexes correspond to pinctrl-DIGIT properties in a node.

; So they're related to a node, but not just one property within the node.

; The following examples assume something like this:

;   foo {
;       pinctrl-0 = <&bar>;
;       pinctrl-1 = <&baz>;
;       pinctrl-names = "default", "sleep";
;   }

; Total number of pinctrl-DIGIT properties in the node. May be zero.

; #define DT_N_<node path>_PINCTRL_NUM 2
pinctrl-macro = %s"DT_N" path-id %s"_PINCTRL_NUM"
; A given pinctrl-DIGIT property exists.

; #define DT_N_<node path>_PINCTRL_IDX_0_EXISTS 1
; #define DT_N_<node path>_PINCTRL_IDX_1_EXISTS 1
pinctrl-macro = %s"DT_N" path-id %s"_PINCTRL_IDX_" DIGIT %s"_EXISTS"
; A given pinctrl property name exists.

; #define DT_N_<node path>_PINCTRL_NAME_default_EXISTS 1
; #define DT_N_<node path>_PINCTRL_NAME_sleep_EXISTS 1
pinctrl-macro = %s"DT_N" path-id %s"_PINCTRL_NAME_" dt-name %s"_EXISTS"
; The corresponding index number of a named pinctrl property.

; #define DT_N_<node path>_PINCTRL_NAME_default_IDX 0
; #define DT_N_<node path>_PINCTRL_NAME_sleep_IDX 1
pinctrl-macro = %s"DT_N" path-id %s"_PINCTRL_NAME_" dt-name %s"_IDX"
; The node identifier for the phandle in a named pinctrl property.

; #define DT_N_<node path>_PINCTRL_NAME_default_IDX_0_PH <node id for 'bar'>
; There's no need for a separate macro for access by index: that's

(continues on next page)
; covered by property-macro. We only need this because the map from
; names to properties is implicit in the structure of the DT.

pitcnel-macro = /%"DT_N" path-id %"_PINCTRL_NAME_" dt-name %"_IDX_" DIGIT %"_PH"

; --------------------------------------------------------------------

gpiohogs-macro: a macro related to GPIO hog nodes

The following examples assume something like this:

gpio1: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;
    
    node-1 {
        gpio-hog;
        gpios = <0x0 0x10>, <0x1 0x20>;
        output-high;
    }
    
    node-2 {
        gpio-hog;
        gpios = <0x2 0x30>;
        output-low;
    }
}

Bindings fragment for the vnd,gpio compatible:

    gpio-cells:
      - pin
      - flags

    The node contains GPIO hogs.

    #define DT_N<node-1 path>_GPIO_HOGS_EXISTS 1
    #define DT_N<node-2 path>_GPIO_HOGS_EXISTS 1

gpiohogs-macro = /%"DT_N" path-id %"_GPIO_HOGS_EXISTS"

    Number of hogged GPIOs in a node.

    #define DT_N<node-1 path>_GPIO_HOGS_NUM 2
    #define DT_N<node-2 path>_GPIO_HOGS_NUM 1

gpiohogs-macro = /%"DT_N" path-id %"_GPIO_HOGS_NUM"

    A given logical GPIO hog array index exists.

    #define DT_N<node-1 path>_GPIO_HOGS_IDX_0_EXISTS 1
    #define DT_N<node-1 path>_GPIO_HOGS_IDX_1_EXISTS 1
    #define DT_N<node-2 path>_GPIO_HOGS_IDX_0_EXISTS 1
    #define DT_N<node-2 path>_GPIO_HOGS_IDX_1_EXISTS 1

gpiohogs-macro = /%"DT_N" path-id %"_GPIO_HOGS_IDX_" DIGIT %"_EXISTS"

    The node identifier for the phandle of a logical index in the GPIO hogs array.

    These macros are currently unused by Zephyr.

    #define DT_N<node-1 path>_GPIO_HOGS_IDX_0_PH <node id for 'gpio1'>
    #define DT_N<node-1 path>_GPIO_HOGS_IDX_1_PH <node id for 'gpio1'>
    #define DT_N<node-2 path>_GPIO_HOGS_IDX_0_PH <node id for 'gpio1'>
    #define DT_N<node-2 path>_GPIO_HOGS_IDX_1_PH <node id for 'gpio1'>

gpiohogs-macro = /%"DT_N" path-id %"_GPIO_HOGS_IDX_" DIGIT %"_PH"

    The pin cell of a logical index in the GPIO hogs array exists.

    #define DT_N<node-1 path>_GPIO_HOGS_IDX_0_VAL_pin_EXISTS 1
    #define DT_N<node-1 path>_GPIO_HOGS_IDX_1_VAL_pin_EXISTS 1
    #define DT_N<node-2 path>_GPIO_HOGS_IDX_0_VAL_pin_EXISTS 1
    #define DT_N<node-2 path>_GPIO_HOGS_IDX_1_VAL_pin_EXISTS 1

gpiohogs-macro = /%"DT_N" path-id %"_GPIO_HOGS_IDX_" DIGIT %"_VAL_pin_EXISTS"

(continues on next page)
The value of the pin cell of a logical index in the GPIO hogs array.

- #define DT_N_<node-1 path>_GPIO_HOGS_IDX_0_VAL_pin 0
- #define DT_N_<node-1 path>_GPIO_HOGS_IDX_1_VAL_pin 1
- #define DT_N_<node-2 path>_GPIO_HOGS_IDX_0_VAL_pin 2

**gpiohogs-macro** =/ %s"DT_N" %s"_GPIO_HOGS_IDX_" %s"_VAL_pin"

The flags cell of a logical index in the GPIO hogs array exists.

- #define DT_N_<node-1 path>_GPIO_HOGS_IDX_0_VAL_flags_EXISTS 1
- #define DT_N_<node-1 path>_GPIO_HOGS_IDX_1_VAL_flags_EXISTS 1
- #define DT_N_<node-2 path>_GPIO_HOGS_IDX_0_VAL_flags_EXISTS 1

**gpiohogs-macro** =/ %s"DT_N" %s"_GPIO_HOGS_IDX_" %s"_VAL_flags_EXISTS"

The value of the flags cell of a logical index in the GPIO hogs array.

- #define DT_N_<node-1 path>_GPIO_HOGS_IDX_0_VAL_flags 0x10
- #define DT_N_<node-1 path>_GPIO_HOGS_IDX_1_VAL_flags 0x20
- #define DT_N_<node-2 path>_GPIO_HOGS_IDX_0_VAL_flags 0x30

**gpiohogs-macro** =/ %s"DT_N" %s"_GPIO_HOGS_IDX_" %s"_VAL_flags"

---

**property-macro**: a macro related to a node property

These combine a node identifier with a "lowercase-and-underscores form" of the property name. The value expands to something related to the property's value.

The optional prop-suf suffix is when there's some specialized subvalue that deserves its own macro, like the macros for an array property's individual elements.

The "plain vanilla" macro for a property's value, with no prop-suf, looks like this:

- DT_N.<node path>._P_.<property name>

Components:

- path-id: node's devicetree path converted to a C token
- prop-id: node's property name converted to a C token
- prop-suf: an optional property-specific suffix

**property-macro** = %s"DT_N" %s"_P_" %s"_" prop-id [prop-suf]

---

**path-id**: a node's path-based macro identifier

This in "lowercase-and-underscores" form. I.e. it is the node's devicetree path converted to a C token by changing:

- each slash (/) to _S_
- all letters to lowercase
- non-alphanumerics characters to underscores

For example, the leaf node "bar-BAZ" in this devicetree:

```
/ {
  foo@123 {
    bar-BAZ {};
  }
};
```
has path-id "_S_foo_123_S_bar_baz".

(continues on next page)
path-id = 1*( %s"_S_" dt-name )

; prop-id: a property identifier
; A property name converted to a C token by changing:
; - all letters to lowercase
; - non-alphanumeric characters to underscores
; Example node:
; chosen {
; zephyr,console = &uart1;
; WHY,AM_I_SHOUTING = "unclear";
; }
; The 'zephyr,console' property has prop-id 'zephyr_console'.
; 'WHY,AM_I_SHOUTING' has prop-id 'why_am_i_shouting'.
prop-id = dt-name

; prop-suf: a property-specific macro suffix
; Extra macros are generated for properties:
; - that are special to the specification ("reg", "interrupts", etc.)
; - with array types (uint8-array, phandle-array, etc.)
; - with "enum:" in their bindings
; - that have zephyr device API specific macros for phandle-arrays
; - related to phandle specifier names ("foo-names")
; Here are some examples:
; _EXISTS: property, index or name existence flag
; _SIZE: logical property length
; _IDX_<i>: values of individual array elements
; _ADDR_<i>: for reg properties, the i-th register block address
; _LEN_<i>: for reg properties, the i-th register block length
; The different cases are not exhaustively documented here to avoid
; this file going stale. Please see devicetree.h if you need to know
; the details.
prop-suf = 1*( %s"_gen-name ["_" dt-name] )

; other-macro: grab bag for everything that isn't a node-macro.
; See examples below.
other-macro = %s"DT_N_" alternate-id
; Total count of enabled instances of a compatible.
other-macro = %s"DT_N_INST_" dt-name %s"_NUM_OKAY"
; These are used internally by DT_FOREACH_NODE and
; DT_FOREACH_STATUS_OKAY_NODE respectively.
other-macro = %s"DT_FOREACH_HELPER"
other-macro = %s"DT_FOREACH_OKAY_HELPER"
; These are used internally by DT_FOREACH_STATUS_OKAY,
; which iterates over each enabled node of a compatible.
other-macro = %s"DT_FOREACH_OKAY_" dt-name

(continues on next page)
other-macro =/ %s"DT_FOREACH_OKAY_VARGS_" dt-name
; These are used internally by DT_INST_FOREACH_STATUS_OKAY,
; which iterates over each enabled instance of a compatible.
other-macro =/ %s"DT_FOREACH_OKAY_INST_" dt-name
other-macro =/ %s"DT_FOREACH_OKAY_INST_VARGS_" dt-name
E.g.: #define DT_CHOSEN_zephyr_flash
other-macro =/ %s"DT_CHOSEN_" dt-name
; Declares that a compatible has at least one node on a bus.
Example:
}

#endif
alternate-id: another way to specify a node besides a path-id
Example devicetree:
{
   aliases {
      dev = &dev_1;
   };
   soc {
      dev_1: device@123 {
         compatible = "vnd,device";
      };
   };
}
Node device@123 has these alternate-id values:
- ALIAS_dev
- NODELABEL_dev_1
- INST_0_vnd_device

The full alternate-id macros are:

#ifndef
#define DT_N_INST_0_vnd_device DT_N_S_soc_S_device_123
#define DT_N_ALIAS_dev DT_N_S_soc_S_device_123
#define DT_N_NODELABEL_dev_1 DT_N_S_soc_S_device_123

These mainly exist to allow pasting an alternate-id macro onto a
"_P<prop-id>" to access node properties given a node’s alias, etc.

Notice that “inst”-type IDs have a leading instance identifier,
which is generated by the devicetree scripts. The other types of
alternate-id begin immediately with names taken from the devicetree.
alternate-id = ( %s"ALIAS_" / %s"NODELABEL_" ) dt-name
alternate-id =/ %s"INST_" 1*DIGIT _" dt-name

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Phandles

The devicetree concept of a phandle is very similar to pointers in C. You can use phandles to refer to nodes in devicetree similarly to the way you can use pointers to refer to structures in C.

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- Using phandles
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- phandle-array properties
  - High level description
  - Example phandle-arrays: GPIOs
- Specifier spaces
  - High level description
  - Example specifier space: gpio
Getting phandles  The usual way to get a phandle for a devicetree node is from one of its node labels. For example, with this devicetree:

```plaintext
/ {
    lbl_a: node-1 {};
    lbl_b: lbl_c: node-2 {};
}
```

You can write the phandle for:
- `/node-1` as `&lbl_a`
- `/node-2` as either `&lbl_b` or `&lbl_c`

Notice how the `&node-label` devicetree syntax is similar to the “address of” C syntax.

Using phandles  

*Note:* “Type” in this section refers to one of the type names documented in *Properties* in the devicetree bindings documentation.

Here are the main ways you will use phandles.

**One node: phandle type**  You can use phandles to refer to `node-b` from `node-a`, where `node-b` is related to `node-a` in some way.

One common example is when `node-a` represents some hardware that generates an interrupt, and `node-b` represents the interrupt controller that receives the asserted interrupt. In this case, you could write:

```plaintext
node_b: node-b {
    interrupt-controller;
};

node_a {
    interrupt-parent = <&node_b>;
};
```

This uses the standard `interrupt-parent` property defined in the devicetree specification to capture the relationship between the two nodes.

These properties have type `phandle`.

**Zero or more nodes: phandles type**  You can use phandles to make an array of references to other nodes.

One common example occurs in *pin control*. Pin control properties like `pinctrl-0`, `pinctrl-1` etc. may contain multiple phandles, each of which “points” to a node containing information
related to pin configuration for that hardware peripheral. Here’s an example of six phandles in a single property:

```
pinctrl-0 = \<&quadspi_clk_pe10 &quadspi_ncs_pe11 &quadspi_bk1_io0_pe12 &quadspi_bk1_io1_pe13 &quadspi_bk1_io2_pe14 &quadspi_bk1_io3_pe15>;
```

These properties have type phandles.

**Zero or more nodes with metadata: phandle-array type** You can use phandles to refer to and configure one or more resources that are “owned” by some other node.

This is the most complex case. There are examples and more details in the next section. These properties have type phandle-array.

**phandle-array properties** These properties are commonly used to specify a resource that is owned by another node along with additional metadata about the resource.

**High level description** Usually, properties with this type are written like `phandle-array-prop` in this example:

```
node {
    phandle-array-prop = \<&foo 1 2>, \<&bar 3>, \<&baz 4 5>;
};
```

That is, the property's value is written as a comma-separated sequence of “groups”, where each “group” is written inside of angle brackets (`< ... >`). Each “group” starts with a phandle (`&foo, &bar, &baz`). The values that follow the phandle in each “group” are called specifiers. There are three specifiers in the above example:

1. 1 2
2. 3
3. 4 5

The phandle in each “group” is used to “point” to the hardware that controls the resource you are interested in. The specifier describes the resource itself, along with any additional necessary metadata.

The rest of this section describes a common example. Subsequent sections document more rules about how to use phandle-array properties in practice.

**Example phandle-arrays: GPIOs** Perhaps the most common use case for phandle-array properties is specifying one or more GPIOs on your SoC that another chip on your board connects to. For that reason, we’ll focus on that use case here. However, there are many other use cases that are handled in devicetree with phandle-array properties.

For example, consider an external chip with an interrupt pin that is connected to a GPIO on your SoC. You will typically need to provide that GPIO's information (GPIO controller and pin number) to the device driver for that chip. You usually also need to provide other metadata about the GPIO, like whether it is active low or high, what kind of internal pull resistor within the SoC should be enabled in order to communicate with the device, etc., to the driver.

In the devicetree, there will be a node that represents the GPIO controller that controls a group of pins. This reflects the way GPIO IP blocks are usually developed in hardware. Therefore, there is no single node in the devicetree that represents a GPIO pin, and you can’t use a single phandle to represent it.

Instead, you would use a phandle-array property, like this:
my-external-ic {
    irq-gpios = <&gpioX pin flags>;
};

In this example, irq-gpios is a phandle-array property with just one “group” in its value. &gpioX is the phandle for the GPIO controller node that controls the pin. pin is the pin number (0, 1, 2, ...). flags is a bit mask describing pin metadata (for example (GPIO_ACTIVE_LOW | GPIO_PULL_UP)); see include/zephyr/dt-bindings/gpio/gpio.h for more details.

The device driver handling the my-external-ic node can then use the irq-gpios property's value to set up interrupt handling for the chip as it is used on your board. This lets you configure the device driver in devicetree, without changing the driver's source code.

Such properties can contain multiple values as well:

my-other-external-ic {
    handshake-gpios = <&gpioX pinX flagsX>, <&gpioY pinY flagsY>;
};

The above example specifies two pins:

• pinX on the GPIO controller with phandle &gpioX, flags flagsX
• pinY on &gpioY, flags flagsY

You may be wondering how the “pin and flags” convention is established and enforced. To answer this question, we'll need to introduce a concept called specifier spaces before moving on to some information about devicetree bindings.

Specifier spaces Specifier spaces are a way to allow nodes to describe how you should use them in phandle-array properties.

We'll start with an abstract, high level description of how specifier spaces work in DTS files, before moving on to a concrete example and providing references to further reading for how this all works in practice using DTS files and bindings files.

High level description As described above, a phandle-array property is a sequence of “groups” of phandles followed by some number of cells:

    node {
        phandle-array-prop = <&foo 1 2>, <&bar 3>;
    };

The cells that follow each phandle are called a specifier. In this example, there are two specifiers:

1. 1 2: two cells
2. 3: one cell

Every phandle-array property has an associated specifier space. This sounds complex, but it's really just a way to assign a meaning to the cells that follow each phandle in a hardware specific way. Every specifier space has a unique name. There are a few “standard” names for commonly used hardware, but you can create your own as well.

Devicetree nodes encode the number of cells that must appear in a specifier, by name, using the #SPACE_NAME-cells property. For example, let's assume that phandle-array-prop's specifier space is named baz. Then we would need the foo and bar nodes to have the following #baz-cells properties:

foo: node@1000 {
    #baz-cells = <2>;
};
bar: node@2000 {
    #baz-cells = <1>;
};

Without the #baz-cells property, the devicetree tooling would not be able to validate the number of cells in each specifier in phandle-array-prop.

This flexibility allows you to write down an array of hardware resources in a single devicetree property, even though the amount of metadata you need to describe each resource might be different for different nodes.

A single node can also have different numbers of cells in different specifier spaces. For example, we might have:

foo: node@1000 {
    #baz-cells = <2>;
    #bob-cells = <1>;
};

With that, if phandle-array-prop-2 has specifier space bob, we could write:

node {
    phandle-array-prop = <&foo 1 2>, <&bar 3>;
    phandle-array-prop-2 = <&foo 4>;
};

This flexibility allows you to have a node that manages multiple different kinds of resources at the same time. The node describes the amount of metadata needed to describe each kind of resource (how many cells are needed in each case) using different #SPACE_NAME-cells properties.

Example specifier space: gpio From the above example, you’re already familiar with how one specifier space works: in the “gpio” space, specifiers almost always have two cells:

1. a pin number
2. a bit mask of flags related to the pin

Therefore, almost all GPIO controller nodes you will see in practice will look like this:

gpioX: gpio-controller@deadbeef {
    gpio-controller;
    #gpio-cells = <2>;
};

Associating properties with specifier spaces Above, we have described that:

- each phandle-array property has an associated specifier space
- specifier spaces are identified by name
- devicetree nodes use #SPECIFIER_NAME-cells properties to configure the number of cells which must appear in a specifier

In this section, we explain how phandle-array properties get their specifier spaces.

High level description In general, a phandle-array property named foos implicitly has specifier space foo. For example:
properties:

dmas:
  type: phandle-array
pwms:
  type: phandle-array

The `dmas` property's specifier space is “dma”. The `pwms` property's specifier space is `pwm`.

**Special case: GPIO**  ***-gpios properties are special-cased so that e.g. foo-gpios resolves to #gpio-cells rather than #foo-gpio-cells.**

**Manually specifying a space**  You can manually specify the specifier space for any `phandle-array` property. See *specifier-space*.

**Naming the cells in a specifier**  You should name the cells in each specifier space your hardware supports when writing bindings. For details on how to do this, see *Specifier cell names (*-cells)*.

This allows C code to query information about and retrieve the values of cells in a specifier by name using devicetree APIs like these:

- `DT_PHA_BY_IDX`
- `DT_PHA_BY_NAME`

This feature and these macros are used internally by numerous hardware-specific APIs. Here are a few examples:

- `DT_GPIO_PIN_BY_IDX`
- `DT_PWMS_CHANNEL_BY_IDX`
- `DT_DMAS_CELL_BY_NAME`
- `DT_IO_CHANNELS_INPUT_BY_IDX`
- `DT_CLOCKS_CELL_BY_NAME`

**See also**

- *Writing property values*: how to write phandles in devicetree properties
- *Properties*: how to write bindings for properties with phandle types (`phandle, phandles, phandle-array`)
- *specifier-space*: how to manually specify a phandle-array property's specifier space

**The /zephyr, user node**

Zephyr’s devicetree scripts handle the `/zephyr, user` node as a special case: you can put essentially arbitrary properties inside it and retrieve their values without having to write a binding. It is meant as a convenient container when only a few simple properties are needed.

**Note**: This node is meant for sample code and user applications. It should not be used in the upstream Zephyr source code for device drivers, subsystems, etc.
Simple values  You can store numeric or array values in /zephyr,user if you want them to be configurable at build time via devicetree.

For example, with this devicetree overlay:

```c
/ {
    zephyr,user {
        boolean;
        bytes = [81 82 83];
        number = <23>;
        numbers = <1>, <2>, <3>;
        string = "text";
        strings = "a", "b", "c",
    }
};
```

You can get the above property values in C/C++ code like this:

```c
#define ZEPHYR_USER_NODE DT_PATH(zephyr_user)

DT_PROP(ZEPHYR_USER_NODE, boolean) // 1
DT_PROP(ZEPHYR_USER_NODE, bytes)  // {0x81, 0x82, 0x83}
DT_PROP(ZEPHYR_USER_NODE, number)  // 23
DT_PROP(ZEPHYR_USER_NODE, numbers) // {1, 2, 3}
DT_PROP(ZEPHYR_USER_NODE, string)  // "text"
DT_PROP(ZEPHYR_USER_NODE, strings) // {"a", "b", "c"}
```

Devices  You can store phandles in /zephyr,user if you want to be able to reconfigure which devices your application uses in simple cases using devicetree overlays.

For example, with this devicetree overlay:

```c
/ {
    zephyr,user {
        handle = &gpio0;
        handles = &gpio0, &gpio1;
    }
};
```

You can convert the phandles in the handle and handles properties to device pointers like this:

```c
/*
 * Same thing as:
 * ...
 * my_dev = DEVICE_DT_GET(DT_NODELABEL(gpio0));
 */
const struct device *my_device =
    DEVICE_DT_GET(DT_PROP(ZEPHYR_USER_NODE, handle));

#define PHANDLE_TO_DEVICE(node_id, prop, idx) \
    DEVICE_DT_GET(DT_PHANDLE_BY_IDX(node_id, prop, idx))

/*
 * Same thing as:
 * ...
 * *my_devices[] = {
 *     DEVICE_DT_GET(DT_NODELABEL(gpio0)),
 *     DEVICE_DT_GET(DT_NODELABEL(gpio1)),
 * }
 */
const struct device *my_devices[] = {
```
GPIOs  The /zephyr/user node is a convenient place to store application-specific GPIOs that you want to be able to reconfigure with a devicetree overlay.

For example, with this devicetree overlay:

```c
#include <zephyr/dt-bindings/gpio/gpio.h>
/
    zephyr, user {
        signal-gpios = &gpio0 1 GPIO_ACTIVE_HIGH;
    };
```

You can convert the pin defined in signal-gpios to a struct gpio_dt_spec in your source code, then use it like this:

```c
#include <zephyr/drivers/gpio.h>
#define ZEPHYR_USER_NODE DT_PATH(zephyr_user)

const struct gpio_dt_spec signal =
    GPIO_DT_SPEC_GET(ZEPHYR_USER_NODE, signal_gpios);

/* Configure the pin */
gpio_pin_configure_dt(&signal, GPIO_OUTPUT_INACTIVE);

/* Set the pin to its active level */
gpio_pin_set_dt(&signal, 1);
```

(See gpio_dt_spec, GPIO_DT_SPEC_GET, and gpio_pin_configure_dt() for details on these APIs.)

Devicetree HOWTOs

This page has step-by-step advice for getting things done with devicetree.

Tip: See Troubleshooting devicetree for troubleshooting advice.

Get your devicetree and generated header  A board’s devicetree (BOARD.dts) pulls in common node definitions via #include preprocessor directives. This at least includes the SoC’s .dtsi. One way to figure out the devicetree’s contents is by opening these files, e.g. by looking in dts/<ARCH>/<vendor>/<soc>.dtsi, but this can be time consuming.

If you just want to see the “final” devicetree for your board, build an application and open the zephyr.dts file in the build directory.

Tip: You can build hello_world to see the “base” devicetree for your board without any additional changes from overlay files.

For example, using the qemu_cortex_m3 board to build hello_world:

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You can change `qemu_cortex_m3` to match your board.

CMake prints the input and output file locations like this:

```
-- Found BOARD.dts: .../zephyr/boards/arm/qemu_cortex_m3/qemu_cortex_m3.dts
-- Generated zephyr.dts: .../zephyr/build/zephyr/zephyr.dts
-- Generated devicetree_generated.h: .../zephyr/build/zephyr/include/generated/devicetree_generated.h
```

The `zephyr.dts` file is the final devicetree in DTS format. The `devicetree_generated.h` file is the corresponding generated header. See *Input and output files* for details about these files.

**Get a struct device from a devicetree node**  When writing Zephyr applications, you'll often want to get a driver-level struct device corresponding to a devicetree node.

For example, with this devicetree fragment, you might want the struct device for `serial@40002000`:

```
/ {
  soc {
    serial0: serial@40002000 {
      status = "okay";
      current-speed = <115200>;
    } /* ... */
  };

  aliases {
    my-serial = &serial0;
  };

  chosen {
    zephyr,console = &serial0;
  };
};
```

Start by making a node identifier for the device you are interested in. There are different ways to do this; pick whichever one works best for your requirements. Here are some examples:

```
/* Option 1: by node label */
#define MY_SERIAL DT_NODELABEL(serial0)

/* Option 2: by alias */
#define MY_SERIAL DT_ALIAS(my_serial)

/* Option 3: by chosen node */
#define MY_SERIAL DT_CHOSEN(zephyr_console)

/* Option 4: by path */
#define MY_SERIAL DT_PATH(soc, serial_40002000)
```

Once you have a node identifier there are two ways to proceed. One way to get a device is to use `DEVICE_DT_GET()`:
const struct device *const uart_dev = DEVICE_DT_GET(MY_SERIAL);

if (!device_is_ready(uart_dev)) {
    /* Not ready, do not use */
    return -ENODEV;
}

There are variants of DEVICE_DT_GET() such as DEVICE_DT_GET_OR_NULL(), DEVICE_DT_GET_ONE() or DEVICE_DT_GET_ANY(). This idiom fetches the device pointer at build-time, which means there is no runtime penalty. This method is useful if you want to store the device pointer as configuration data. But because the device may not be initialized, or may have failed to initialize, you must verify that the device is ready to be used before passing it to any API functions. (This check is done for you by device_get_binding().)

In some situations the device cannot be known at build-time, e.g., if it depends on user input like in a shell application. In this case you can get the struct device by combining device_get_binding() with the device name:

const char *dev_name = /* TODO: insert device name from user */;
const struct device *uart_dev = device_get_binding(dev_name);

You can then use uart_dev with Universal Asynchronous Receiver-Transmitter (UART) API functions like uart_config(). Similar code will work for other device types; just make sure you use the correct API for the device.

If you're having trouble, see Troubleshooting devicetree. The first thing to check is that the node has status = "okay", like this:

#define MY_SERIAL DT_NODELABEL(my_serial)
#if DT_NODE_HAS_STATUS(MY_SERIAL, okay)
const struct device *const uart_dev = DEVICE_DT_GET(MY_SERIAL);
#else
#error "Node is disabled"
#endif

If you see the #error output, make sure to enable the node in your devicetree. In some situations your code will compile but it will fail to link with a message similar to:

...undefined reference to `__device_dts_ord_N'
collect2: error: ld returned 1 exit status

This likely means there's a Kconfig issue preventing the device driver from being built, resulting in a reference that does not exist. If your code compiles successfully, the last thing to check is if the device is ready, like this:

if (!device_is_ready(uart_dev)) {
    printk("Device not ready\n");
}

If you find that the device is not ready, it likely means that the device's initialization function failed. Enabling logging or debugging driver code may help in such situations. Note that you can also use device_get_binding() to obtain a reference at runtime. If it returns NULL it can either mean that device's driver failed to initialize or that it does not exist.

Find a devicetree binding Devicetree bindings are YAML files which declare what you can do with the nodes they describe, so it's critical to be able to find them for the nodes you are using.

If you don't have them already, Get your devicetree and generated header. To find a node's binding, open the generated header file, which starts with a list of nodes in a block comment:
Make note of the path to the node you want to find, like /flash@0. Search for the node's output in the file, which starts with something like this if the node has a matching binding:

```c
/*
 * Devicetree node:
 * /flash@0
 * 
 * Binding (compatible = soc-nv-flash):
 * $ZEPHYR_BASE/dts/bindings/mtd/soc-nv-flash.yaml
 * 
 */
```

See [Check for missing bindings](#) for troubleshooting.

**Set devicetree overlays.** Devicetree overlays are explained in *Introduction to devicetree*. The CMake variable DTC_OVERLAY_FILE contains a space- or semicolon-separated list of overlay files to use. If DTC_OVERLAY_FILE specifies multiple files, they are included in that order by the C preprocessor. A file in a Zephyr module can be referred to by escaping the Zephyr module dir variable like `${ZEPHYR_<module>_MODULE_DIR}/<path-to>/dts.overlay` when setting the DTC_OVERLAY_FILE variable.

You can set DTC_OVERLAY_FILE to contain exactly the files you want to use. Here is an example using `west build`.

If you don’t set DTC_OVERLAY_FILE, the build system will follow these steps, looking for files in your application configuration directory to use as devicetree overlays:

1. If the file `boards/<BOARD>.overlay` exists, it will be used.
2. If the current board has *multiple revisions* and `boards/<BOARD>_<revision>.overlay` exists, it will be used. This file will be used in addition to `boards/<BOARD>.overlay` if both exist.
3. If one or more files have been found in the previous steps, the build system stops looking and just uses those files.
4. Otherwise, if `<BOARD>.overlay` exists, it will be used, and the build system will stop looking for more files.
5. Otherwise, if `app.overlay` exists, it will be used.

Extra devicetree overlays may be provided using EXTRA_DTC_OVERLAY_FILE which will still allow the build system to automatically use devicetree overlays described in the above steps.

The build system appends overlays specified in EXTRA_DTC_OVERLAY_FILE to the overlays in DTC_OVERLAY_FILE when processing devicetree overlays. This means that changes made via EXTRA_DTC_OVERLAY_FILE have higher precedence than those made via DTC_OVERLAY_FILE.

All configuration files will be taken from the application's configuration directory except for files with an absolute path that are given with the DTC_OVERLAY_FILE or EXTRA_DTC_OVERLAY_FILE argument.
See Application Configuration Directory on how the application configuration directory is defined.

Using Shields will also add devicetree overlay files. The DTC_OVERLAY_FILE value is stored in the CMake cache and used in successive builds. The build system prints all the devicetree overlays it finds in the configuration phase, like this:

```bash
-- Found devicetree overlay: .../some/file.overlay
```

Use devicetree overlays  See Set devicetree overlays for how to add an overlay to the build.

Overlays can override node property values in multiple ways. For example, if your BOARD.dts contains this node:

```dts
/ {
    soc { 
        serial0: serial@40002000 {
            status = "okay";
            current-speed = <115200>;
            /* ... */
        };
    };
}
```

These are equivalent ways to override the current-speed value in an overlay:

```dts
/* Option 1 */
&serial0 {
    current-speed = <9600>;
};
/* Option 2 */
&{/soc serial0@40002000} {
    current-speed = <9600>;
};
```

We'll use the &serial0 style for the rest of these examples.

You can add aliases to your devicetree using overlays: an alias is just a property of the /aliases node. For example:

```dts
/ {
    aliases {
        my-serial = &serial0;
    };
}
```

Chosen nodes work the same way. For example:

```dts
/ {
    chosen {
        zephyr,console = &serial0;
    };
}
```

To delete a property (in addition to deleting properties in general, this is how to set a boolean property to false if it's true in BOARD.dts):

```dts
&serial0 {
    /delete-property/ some-unwanted-property;
};
```
You can add subnodes using overlays. For example, to configure a SPI or I2C child device on an existing bus node, do something like this:

```c
/* SPI device example */
&spi1 {
  my_spi_device: temp-sensor@0 {
    compatible = "...";
    label = "TEMP_SENSOR_0";
    /* reg is the chip select number, if needed;
       * If present, it must match the node's unit address. */
    reg = <0>;
    /* Configure other SPI device properties as needed.
       * Find your device’s DT binding for details. */
    spi-max-frequency = <4000000>;
  }
};

/* I2C device example */
&i2c2 {
  my_i2c_device: touchscreen@76 {
    compatible = "...";
    label = "TOUCHSCREEN";
    /* reg is the I2C device address.
       * It must match the node's unit address. */
    reg = <76>;
    /* Configure other I2C device properties as needed.
       * Find your device’s DT binding for details. */
  }
};
```

Other bus devices can be configured similarly:

- create the device as a subnode of the parent bus
- set its properties according to its binding

Assuming you have a suitable device driver associated with the `my_spi_device` and `my_i2c_device` compatibles, you should now be able to enable the driver via Kconfig and get the struct device for your newly added bus node, then use it with that driver API.

**Write device drivers using devicetree APIs**  “Devicetree-aware” device drivers should create a struct device for each status = “okay” devicetree node with a particular compatible (or related set of compatibles) supported by the driver.

Writing a devicetree-aware driver begins by defining a devicetree binding for the devices supported by the driver. Use existing bindings from similar drivers as a starting point. A skeletal binding to get started needs nothing more than this:

```yaml
description: <Human-readable description of your binding>
compatible: "foo-company,bar-device"
include: base.yaml
```

See [Find a devicetree binding](#) for more advice on locating existing bindings.

After writing your binding, your driver C file can then use the devicetree API to find status = “okay” nodes with the desired compatible, and instantiate a struct device for each one. There are two options for instantiating each struct device: using instance numbers, and using node labels.

In either case:
• Each struct device's name should be set to its devicetree node's label property. This allows the driver's users to Get a struct device from a devicetree node in the usual way.

• Each device's initial configuration should use values from devicetree properties whenever practical. This allows users to configure the driver using devicetree overlays.

Examples for how to do this follow. They assume you've already implemented the device-specific configuration and data structures and API functions, like this:

```c
/* my_driver.c */
#include <zephyr/drivers/some_api.h>

/* Define data (RAM) and configuration (ROM) structures: */
struct my_dev_data {
    /* per-device values to store in RAM */
};
struct my_dev_cfg {
    uint32_t freq; /* Just an example: initial clock frequency in Hz */
    /* other configuration to store in ROM */
};

/* Implement driver API functions (drivers/some_api.h callbacks): */
static int my_driver_api_func1(const struct device *dev, uint32_t *foo) { /* ... */ }
static int my_driver_api_func2(const struct device *dev, uint64_t bar) { /* ... */ }
static struct some_api my_api_funcs = {
    .func1 = my_driver_api_func1,
    .func2 = my_driver_api_func2,
};
```

**Option 1: create devices using instance numbers** Use this option, which uses Instance-based APIs, if possible. However, they only work when devicetree nodes for your driver's compatible are all equivalent, and you do not need to be able to distinguish between them.

To use instance-based APIs, begin by defining DT_DRV_COMPAT to the lowercase-and-underscores version of the compatible that the device driver supports. For example, if your driver's compatible is "vnd,my-device" in devicetree, you would define DT_DRV_COMPAT to vnd_my_device in your driver C file:

```c
/*
 * Put this near the top of the file. After the includes is a good place.
 * (Note that you can therefore run "git grep DT_DRV_COMPAT drivers" in
 * the zephyr Git repository to look for example drivers using this style).
 * /
#define DT_DRV_COMPAT vnd_my_device
```

**Important:** As shown, the DT_DRV_COMPAT macro should have neither quotes nor special characters. Remove quotes and convert special characters to underscores when creating DT_DRV_COMPAT from the compatible property.

Finally, define an instantiation macro, which creates each struct device using instance numbers. Do this after defining my_api_funcs.

```c
/*
 * This instantiation macro is named "CREATE_MY_DEVICE".
 * Its "inst" argument is an arbitrary instance number.
 * *
 * Put this near the end of the file, e.g. after defining "my_api_funcs".
 * /
#define CREATE_MY_DEVICE(inst)
```
static struct my_dev_data my_data_##inst = { 
    /* initialize RAM values as needed, e.g.: */ 
    .freq = DT_INST_PROP(inst, clock_frequency), 
};
static const struct my_dev_cfg my_cfg_##inst = { 
    /* initialize ROM values as needed. */ 
};
DEVICE_DT_INST_DEFINE(inst, 
    my_dev_init_function, 
    NULL, 
    &my_data_##inst, 
    &my_cfg_##inst, 
    MY_DEV_INIT_LEVEL, MY_DEV_INIT_PRIORITY, 
    &my_api_funcs);

Notice the use of APIs like DT_INST_PROP() and DEVICE_DT_INST_DEFINE() to access devicetree node data. These APIs retrieve data from the devicetree for instance number inst of the node with compatible determined by DT_DRV_COMPAT.

Finally, pass the instantiation macro to DT_INST_FOREACH_STATUS_OKAY():

/* Call the device creation macro for each instance: */
DT_INST_FOREACH_STATUS_OKAY(CREATE_MY_DEVICE)

DT_INST_FOREACH_STATUS_OKAY expands to code which calls CREATE_MY_DEVICE once for each enabled node with the compatible determined by DT_DRV_COMPAT. It does not append a semicolon to the end of the expansion of CREATE_MY_DEVICE, so the macro's expansion must end in a semicolon or function definition to support multiple devices.

Option 2: create devices using node labels Some device drivers cannot use instance numbers. One example is an SoC peripheral driver which relies on vendor HAL APIs specialized for individual IP blocks to implement Zephyr driver callbacks. Cases like this should use DT_NODELABEL() to refer to individual nodes in the devicetree representing the supported peripherals on the SoC. The devicetree.h Generic APIs can then be used to access node data.

For this to work, your SoC's dts file must define node labels like mydevice0, mydevice1, etc. appropriately for the IP blocks your driver supports. The resulting devicetree usually looks something like this:

/ {
    soc {
        mydevice0: dev@0 {
            compatible = "vnd,my-device";
        };
        mydevice1: dev@1 {
            compatible = "vnd,my-device";
        };
    };
}

The driver can use the mydevice0 and mydevice1 node labels in the devicetree to operate on specific device nodes:

/*
 * This is a convenience macro for creating a node identifier for
 * the relevant devices. An example use is MYDEV(0) to refer to
 * the node with label "mydevice0".
 */
#define MYDEV(idx) DT_NODELABEL(mydevice ## idx)

(continues on next page)
/* Define your instantiation macro; "idx" is a number like 0 for mydevice0
* or 1 for mydevice1. It uses MYDEV() to create the node label from the
* index.
*/

#define CREATE_MY_DEVICE(idx) 
static struct my_dev_data my_data_##idx = { 
    .freq = DT_PROP(MYDEV(idx), clock_frequency), 
}; 
static const struct my_dev_cfg my_cfg_##idx = { /* ... */ }; 
DEVICE_DT_DEFINE(MYDEV(idx), 
    my_dev_init_function, 
    NULL, 
    &my_data_##idx, 
    &my_cfg_##idx, 
    &my_api_funcs) 

Notice the use of APIs like DT_PROP() and DEVICE_DT_DEFINE() to access devicetree node data. Finally, manually detect each enabled devicetree node and use CREATE_MY_DEVICE to instantiate each struct device:

#if DT_NODE_HAS_STATUS(DT_NODELABEL(mydevice0), okay)
CREATE_MY_DEVICE(0)
#endif

#if DT_NODE_HAS_STATUS(DT_NODELABEL(mydevice1), okay)
CREATE_MY_DEVICE(1)
#endif

Since this style does not use DT_INST_FOREACH_STATUS_OKAY(), the driver author is responsible for calling CREATE_MY_DEVICE() for every possible node, e.g. using knowledge about the peripherals available on supported SoCs.

Device drivers that depend on other devices At times, one struct device depends on another struct device and requires a pointer to it. For example, a sensor device might need a pointer to its SPI bus controller device. Some advice:

- Write your devicetree binding in a way that permits use of Hardware specific APIs from devicetree.h if possible.

- In particular, for bus devices, your driver's binding should include a file like dts/bindings/spi/spi-device.yaml which provides common definitions for devices addressable via a specific bus. This enables use of APIs like DT_BUS() to obtain a node identifier for the bus node. You can then Get a struct device from a devicetree node for the bus in the usual way.

Search existing bindings and device drivers for examples.

Applications that depend on board-specific devices One way to allow application code to run unmodified on multiple boards is by supporting a devicetree alias to specify the hardware specific portions, as is done in the blinky sample. The application can then be configured in BOARD.dts files or via devicetree overlays.

---

5.2. Devicetree 1269
Troubleshooting devicetree

Here are some tips for fixing misbehaving devicetree related code.
See Devicetree HOWTOs for other “HOWTO” style information.

Try again with a pristine build directory

Important: Try this first, before doing anything else.

See Pristine Builds for examples, or just delete the build directory completely and retry.
This is general advice which is especially applicable to debugging devicetree issues, because the outputs are created during the CMake configuration phase, and are not always regenerated when one of their inputs changes.

Make sure <devicetree.h> is included

Unlike Kconfig symbols, the devicetree.h header must be included explicitly.
Many Zephyr header files rely on information from devicetree, so including some other API may transitively include devicetree.h, but that’s not guaranteed.

undefined reference to __device_dts_ord_<N>

This usually happens on a line like this:

```c
const struct device *dev = DEVICE_DT_GET(NODE_ID);
```

where NODE_ID is a valid node identifier, but no device driver has allocated a struct device for this devicetree node. You thus get a linker error, because you’re asking for a pointer to a device that isn’t defined.
To fix it, you need to make sure that:

1. The node is enabled: the node must have status = "okay";
   (Recall that a missing status property means the same thing as status = "okay";; see Important properties for more information about status).
2. A device driver responsible for allocating the struct device is enabled. That is, the Kconfig option which makes the build system compile the driver sources into your application needs to be set to y.
   (See Setting Kconfig configuration values for more information on setting Kconfig options.)

Below, <build> means your build directory.

Making sure the node is enabled:

To find the devicetree node you need to check, use the number <N> from the linker error. Look for this number in the list of nodes at the top of <build>/zephyr/include/generated/devicetree_generated.h. For example, if <N> is 15, and your devicetree_generated.h file looks like this, the node you are interested in is /soc/i2c@deadbeef:

```c
/*
 * Generated by gen_defines.py
 */

/* DTS input file:
 * <build>/zephyr/zephyr.dts.pre
 */

/* Directories with bindings:
 * $ZEPHYR_BASE/dts/bindings
 */

/* Node dependency ordering (ordinal and path):
*/
```

(continues on next page)
Now look for this node in <build>/zephyr/zephyr.dts, which is the final devicetree for your application build. (See Get your devicetree and generated header for information and examples.) If the node has status = "disabled"; in zephyr.dts, then you need to enable it by setting status = "okay"; probably by using a devicetree overlay. For example, if zephyr.dts looks like this:

```dts
i2c0:
  i2c@deadbeef {
    status = "disabled";
  };
```

Then you should put this into your devicetree overlay and Try again with a pristine build directory:

```dts
&i2c0 {
  status = "okay";
};
```

Make sure that you see status = "okay"; in zephyr.dts after you rebuild.

**Making sure the device driver is enabled:**

The first step is to figure out which device driver is responsible for handling your devicetree node and allocating devices for it. To do this, you need to start with the compatible property in your devicetree node, and find the driver that allocates struct device instances for that compatible.

If you're not familiar with how devices are allocated from devicetree nodes based on compatible properties, the ZDS 2021 talk A deep dive into the Zephyr 2.5 device model may be a useful place to start, along with the Device Driver Model pages. See Important properties and the Devicetree specification for more information about compatible.

There is currently no documentation for what device drivers exist and which devicetree compatibles they are associated with. You will have to figure this out by reading the source code:

- Look in drivers for the appropriate subdirectory that corresponds to the API your device implements
- Look inside that directory for relevant files until you figure out what the driver is, or realize there is no such driver.

Often, but not always, you can find the driver by looking for a file that sets the DT_DRV_COMPAT macro to match your node's compatible property, except lowercased and with special characters converted to underscores. For example, if your node's compatible is vnd,foo-device, look for a file with this line:

```
#define DT_DRV_COMPAT vnd_foo_device
```

**Important:** This does not always work since not all drivers use DT_DRV_COMPAT.

If you find a driver, you next need to make sure the Kconfig option that compiles it is enabled. (If you don’t find a driver, and you are sure the compatible property is correct, then you need to write a driver. Writing drivers is outside the scope of this documentation page.)

Continuing the above example, if your devicetree node looks like this now:

```dts
i2c0:
  i2c@deadbeef {
    status = "disabled";
  };
```
Then you would look inside of `drivers/i2c` for the driver file that handles the compatible `nordic,nrf-twim`. In this case, that is `drivers/i2c/i2c_nrfx_twim.c`. Notice how even in cases where `DT_DRV_COMPAT` is not set, you can use information like driver file names as clues.

Once you know the driver you want to enable, you need to make sure its Kconfig option is set to `y`. You can figure out which Kconfig option is needed by looking for a line similar to this one in the `CMakeLists.txt` file in the `drivers` subdirectory. Continuing the above example, `drivers/i2c/CMakeLists.txt` has a line that looks like this:

```makefile
zephyr_library_sources_ifdef(CONFIG_NRFX_TWIM i2c_nrfx_twim.c)
```

This means that `CONFIG_NRFX_TWIM` must be set to `y` in `<build>/zephyr/.config` file.

If your driver's Kconfig is not set to `y`, you need to figure out what you need to do to make that happen. Often, this will happen automatically as soon as you enable the devicetree node. Otherwise, it is sometimes as simple as adding a line like this to your application’s `prj.conf` file and then making sure to `Try again with a pristine build directory`:

```plaintext
CONFIG_FOO=y
```

where `CONFIG_FOO` is the option that `CMakeLists.txt` uses to decide whether or not to compile the driver.

However, there may be other problems in your way, such as unmet Kconfig dependencies that you also have to enable before you can enable your driver.

Consult the Kconfig file that defines `CONFIG_FOO` (for your value of `FOO`) for more information.

### Make sure you’re using the right names

Remember that:

- In C/C++, devicetree names must be lowercased and special characters must be converted to underscores. Zephyr’s generated devicetree header has DTS names converted in this way into the C tokens used by the preprocessor-based `<devicetree.h>` API.
- In overlays, use devicetree node and property names the same way they would appear in any DTS file. Zephyr overlays are just DTS fragments.

For example, if you're trying to **get** the clock-frequency property of a node with path `/soc/i2c@12340000` in a C/C++ file:

```c
/*
 * foo.c: lowercase-and-underscores names
 */

/* Don't do this: */
#define MY_CLOCK_FREQ DT_PROP(DT_PATH(soc, i2c@1234000), clock-frequency)
/*                ^           ^  @ should be _ - should be _ */

/* Do this instead: */
#define MY_CLOCK_FREQ DT_PROP(DT_PATH(soc, i2c_1234000), clock_frequency)
/*                ^           ^ */
```

And if you're trying to **set** that property in a devicetree overlay:

```c
/*
 * foo.overlay: DTS names with special characters, etc.
 */
```
Look at the preprocessor output  To save preprocessor output files, enable the CONFIG_COMPILER_SAVE_TEMPS option. For example, to build hello_world with west with this option set, use:

```
west build -b BOARD samples/hello_world --DCONFIG_COMPILER_SAVE_TEMPS=y
```

This will create a preprocessor output file named foo.c.i in the build directory for each source file foo.c.

You can then search for the file in the build directory to see what your devicetree macros expanded to. For example, on macOS and Linux, using find to find main.c.i:

```
$ find build -name main.c.i
build/CMakeFiles/app.dir/src/main.c.i
```

It's usually easiest to run a style formatter on the results before opening them. For example, to use clang-format to reformat the file in place:

```
clang-format -i build/CMakeFiles/app.dir/src/main.c.i
```

You can then open the file in your favorite editor to view the final C results after preprocessing.

Do not track macro expansion  Compiler messages for devicetree errors can sometimes be very long. This typically happens when the compiler prints a message for every step of a complex macro expansion that has several intermediate expansion steps.

To prevent the compiler from doing this, you can disable the CONFIG_COMPILER_TRACK_MACRO_EXPANSION option. This typically reduces the output to one message per error.

For example, to build hello_world with west and this option disabled, use:

```
west build -b BOARD samples/hello_world --DCONFIG_COMPILER_TRACK_MACRO_EXPANSION=n
```

Validate properties  If you're getting a compile error reading a node property, check your node identifier and property. For example, if you get a build error on a line that looks like this:

```
int baud_rate = DT_PROP(DT_NODELABEL(my_serial), current_speed);
```

Try checking the node by adding this to the file and recompiling:

```
#if !DT_NODE_EXISTS(DT_NODELABEL(my_serial))
#error "whoops"
#endif
```
If you see the “whoops” error message when you rebuild, the node identifier isn’t referring to a valid node. Get your devicetree and generated header and debug from there.

Some hints for what to check next if you don’t see the “whoops” error message:

- did you *Make sure you’re using the right names*?
- does the *property exist*?
- does the node have a *matching binding*?
- does the binding define the property?

**Check for missing bindings**  See Devicetree bindings for information about bindings, and Bindings index for information on bindings built into Zephyr.

If the build fails to *Find a devicetree binding* for a node, then either the node’s compatible property is not defined, or its value has no matching binding. If the property is set, check for typos in its name. In a devicetree source file, compatible should look like "vnd,some-device" – *Make sure you’re using the right names*.

If your binding file is not under zephyr/dts, you may need to set DTS_ROOT; see Where bindings are located.

**Errors with DT_INST_() APIs**  If you’re using an API like DT_INST_PROP(), you must define DT_DRV_COMPAT to the lowercase-and-underscores version of the compatible you are interested in. See Option 1: create devices using instance numbers.

### Devicetree versus Kconfig

Along with devicetree, Zephyr also uses the Kconfig language to configure the source code. Whether to use devicetree or Kconfig for a particular purpose can sometimes be confusing. This section should help you decide which one to use.

In short:

- Use devicetree to describe **hardware** and its **boot-time configuration**. Examples include peripherals on a board, boot-time clock frequencies, interrupt lines, etc.
- Use Kconfig to configure **software support** to build into the final image. Examples include whether to add networking support, which drivers are needed by the application, etc.

In other words, devicetree mainly deals with hardware, and Kconfig with software.

For example, consider a board containing a SoC with 2 UART, or serial port, instances.

- The fact that the board has this UART **hardware** is described with two UART nodes in the devicetree. These provide the UART type (via the compatible property) and certain settings such as the address range of the hardware peripheral registers in memory (via the reg property).
- Additionally, the UART **boot-time configuration** is also described with devicetree. This could include configuration such as the RX IRQ line’s priority and the UART baud rate. These may be modifiable at runtime, but their boot-time configuration is described in devicetree.
- Whether or not to include **software support** for UART in the build is controlled via Kconfig. Applications which do not need to use the UARTs can remove the driver source code from the build using Kconfig, even though the board’s devicetree still includes UART nodes.

As another example, consider a device with a 2.4GHz, multi-protocol radio supporting both the Bluetooth Low Energy and 802.15.4 wireless technologies.

- Devicetree should be used to describe the presence of the radio **hardware**, what driver or drivers it’s compatible with, etc.
• **Boot-time configuration** for the radio, such as TX power in dBm, should also be specified using devicetree.

• Kconfig should determine which **software features** should be built for the radio, such as selecting a BLE or 802.15.4 protocol stack.

As another example, Kconfig options that formerly enabled a particular instance of a driver (that is itself enabled by Kconfig) have been removed. The devices are selected individually using devicetree’s **status** keyword on the corresponding hardware instance.

There are **exceptions** to these rules:

• Because Kconfig is unable to flexibly control some instance-specific driver configuration parameters, such as the size of an internal buffer, these options may be defined in device-tree. However, to make clear that they are specific to Zephyr drivers and not hardware description or configuration these properties should be prefixed with `zephyr`, e.g. `zephyr,random-mac-address in the common Ethernet devicetree properties`.

• Devicetree’s **chosen** keyword, which allows the user to select a specific instance of a hardware device to be used for a particular purpose. An example of this is selecting a particular UART for use as the system’s console.

### 5.2.2 Devicetree Reference

These pages contain reference material for Zephyr’s devicetree APIs and built-in bindings. For the platform-independent details, see the [Devicetree specification](#).

**Devicetree API**

This is a reference page for the `<zephyr/devicetree.h>` API. The API is macro based. Use of these macros has no impact on scheduling. They can be used from any calling context and at file scope.

Some of these – the ones beginning with `DT_INST_` – require a special macro named `DT_DRV_COMPAT` to be defined before they can be used; these are discussed individually below. These macros are generally meant for use within `device drivers`, though they can be used outside of drivers with appropriate care.

**Contents**

• **Generic APIs**
  – Node identifiers and helpers
  – Property access
  – ranges property
  – reg property
  – interrupts property
  – For-each macros
  – Existence checks
  – Inter-node dependencies
  – Bus helpers

• **Instance-based APIs**

• **Hardware specific APIs**
Generic APIs  The APIs in this section can be used anywhere and do not require `DT_DRV_COMPAT` to be defined.

Node identifiers and helpers  A node identifier is a way to refer to a devicetree node at C preprocessor time. While node identifiers are not C values, you can use them to access devicetree data in C rvalue form using, for example, the `Property access` API.

The root node `/` has node identifier `DT_ROOT`. You can create node identifiers for other devicetree nodes using `DT_PATH()`, `DT_NODELABEL()`, `DT_ALIAS()`, and `DT_INST()`.

There are also `DT_PARENT()` and `DT_CHILD()` macros which can be used to create node identifiers for a given node’s parent node or a particular child node, respectively.

The following macros create or operate on node identifiers.

Related code samples

GPIO with custom Devicetree binding

Use custom Devicetree binding to control a GPIO.

```c
#include <board/gpio.h>

#define GPIO6

/*
 *  C code that uses GPIO control
 */

int gpio_setup()
{
    struct gpio_config conf;

    /* Configure GPIO6 as output */
    conf.type = GPIO_OUTPUT;
    conf.pin = GPIO6;
    conf.direction = GPIO_OUT;

    /* Configure the value register */
    conf.value = GPIO_OUTPUT_VALUE;

    /* Register the configuration */
    return gpio_config(&conf);
}
```

`group devicetree-generic-id`

Defines

- `DT_INVALID_NODE`
  
  Name for an invalid node identifier.
  
  This supports cases where factored macros can be invoked from paths where devicetree data may or may not be available. It is a preprocessor identifier that does not match any valid devicetree node identifier.

- `DT_ROOT`
  
  Node identifier for the root node in the devicetree.
**DT_PATH(…)**

Get a node identifier for a devicetree path.

The arguments to this macro are the names of non-root nodes in the tree required to reach the desired node, starting from the root. Non-alphanumeric characters in each name must be converted to underscores to form valid C tokens, and letters must be lowercased.

Example devicetree fragment:

```
/ {
    soc {
        serial1: serial@40001000 {
            status = "okay";
            current-speed = <115200>;
            ...;
        };
    };
}
```

You can use `DT_PATH(soc, serial_40001000)` to get a node identifier for the `serial@40001000` node. Node labels like `serial1` cannot be used as `DT_PATH()` arguments; use `DT_NODELABEL()` for those instead.

Example usage with `DT_PROP()` to get the `current-speed` property:

```
DT_PROP(DT_PATH(soc, serial_40001000), current_speed) // 115200
```

(The `current-speed` property is also in lowercase-and-underscores form when used with this API.)

When determining arguments to `DT_PATH()`:

- the first argument corresponds to a child node of the root (`soc` above)
- a second argument corresponds to a child of the first argument (`serial_40001000` above, from the node name `serial@40001000` after lowercasing and changing `@` to `_`)
- and so on for deeper nodes in the desired node's path

**Note:** This macro returns a node identifier from path components. To get a path string from a node identifier, use `DT_NODE_PATH()` instead.

**Parameters**

- ...—lowercase-and-underscores node names along the node's path, with each name given as a separate argument

**Returns**

node identifier for the node with that path

---

**DT_NODELABEL(label)**

Get a node identifier for a node label.

Convert non-alphanumeric characters in the node label to underscores to form valid C tokens, and lowercase all letters. Note that node labels are not the same thing as label properties.

Example devicetree fragment:
The only node label in this example is serial1.

The string UART_0 is not a node label; it’s the value of a property named label.

You can use `DT_NODELABEL(serial1)` to get a node identifier for the `serial@40001000` node. Example usage with `DT_PROP()` to get the current-speed property:

```
DT_PROP(DT_NODELABEL(serial1), current_speed) // 115200
```

Another example devicetree fragment:

```
cpu@0 {
    L2_0: l2-cache {
        cache-level = <2>;
        ...
    };
}
```

Example usage to get the cache-level property:

```
DT_PROP(DT_NODELABEL(L2_0), cache_level) // 2
```

Notice how L2_0 in the devicetree is lowercased to l2_0 in the `DT_NODELABEL()` argument.

**Parameters**

- `label` – lowercase-and-underscores node label name

**Returns**

node identifier for the node with that label

**DT_ALIAS(alias)**

Get a node identifier from /aliases.

This macro’s argument is a property of the /aliases node. It returns a node identifier for the node which is aliased. Convert non-alphanumeric characters in the alias property to underscores to form valid C tokens, and lowercase all letters.

Example devicetree fragment:

```
/ {
    aliases {
        my-serial = &serial1;
    };

    soc {
        serial1: serial@40001000 {
            status = "okay";
            current-speed = <115200>;
            ...
        };
    }
}
```

You can use `DT_ALIAS(my_serial)` to get a node identifier for the `serial@40001000` node. Notice how my-serial in the devicetree becomes my_serial in the `DT_ALIAS()` argument. Example usage with `DT_PROP()` to get the current-speed property:
Parameters
• alias – lowercase-and-underscores alias name.

Returns
node identifier for the node with that alias

DT_INST(inst, compat)
Get a node identifier for an instance of a compatible.

All nodes with a particular compatible property value are assigned instance numbers, which are zero-based indexes specific to that compatible. You can get a node identifier for these nodes by passing DT_INST() an instance number, inst, along with the lowercase-and-underscores version of the compatible, compat.

Instance numbers have the following properties:

• for each compatible, instance numbers start at 0 and are contiguous
• exactly one instance number is assigned for each node with a compatible, including disabled nodes
• enabled nodes (status property is okay or missing) are assigned the instance numbers starting from 0, and disabled nodes have instance numbers which are greater than those of any enabled node

No other guarantees are made. In particular:

• instance numbers in no way reflect any numbering scheme that might exist in SoC documentation, node labels or unit addresses, or properties of the /aliases node (use DT_NODELABEL() or DT_ALIAS() for those)
• there is no general guarantee that the same node will have the same instance number between builds, even if you are building the same application again in the same build directory

Example devicetree fragment:

```
serial1: serial@00001000 {
    compatible = "vnd,soc-serial";
    status = "disabled";
    current-speed = <9600>;
    ...
};

serial2: serial@00002000 {
    compatible = "vnd,soc-serial";
    status = "okay";
    current-speed = <57600>;
    ...
};

serial3: serial@00003000 {
    compatible = "vnd,soc-serial";
    current-speed = <115200>;
    ...
};
```
Assuming no other nodes in the devicetree have compatible "vnd,soc-serial", that compatible has nodes with instance numbers 0, 1, and 2.

The nodes serial@040002000 and serial@040003000 are both enabled, so their instance numbers are 0 and 1, but no guarantees are made regarding which node has which instance number.

Since serial@040001000 is the only disabled node, it has instance number 2, since disabled nodes are assigned the largest instance numbers. Therefore:

```markdown
// Could be 57600 or 115200. There is no way to be sure:
// either serial@040002000 or serial@040003000 could
// have instance number 0, so this could be the current-speed
// property of either of those nodes.
DT_PROP(DT_INST(0, vnd_soc_serial), current_speed)

// Could be 57600 or 115200, for the same reason.
// If the above expression expands to 57600, then
// this expands to 115200, and vice-versa.
DT_PROP(DT_INST(1, vnd_soc_serial), current_speed)

// 9600, because there is only one disabled node, and
// disabled nodes are "at the the end" of the instance
// number "list".
DT_PROP(DT_INST(2, vnd_soc_serial), current_speed)
```

Notice how "vnd,soc-serial" in the devicetree becomes vnd_soc_serial (without quotes) in the `DT_INST()` arguments. (As usual, current-speed in the devicetree becomes current_speed as well.)

Nodes whose compatible property has multiple values are assigned independent instance numbers for each compatible.

### Parameters
- `inst` – instance number for compatible `compat`
- `compat` – lowercase-and-underscores compatible, without quotes

### Returns
- node identifier for the node with that instance number and compatible

**DT_PARENT(node_id)**

Get a node identifier for a parent node.

Example devicetree fragment:

```markdown
parent: parent-node {
    child: child-node {
        ...
    };
}
```

The following are equivalent ways to get the same node identifier:

```markdown
DT_NODELABEL(parent)
DT_PARENT(DT_NODELABEL(child))
```

### Parameters
- `node_id` – node identifier

### Returns
- a node identifier for the node's parent
DT_GPARENT(node_id)
Get a node identifier for a grandparent node.

Example devicetree fragment:

```
gparent: grandparent-node {
    parent: parent-node {
        child: child-node { ... }
    };
};
```

The following are equivalent ways to get the same node identifier:

```
DT_GPARENT(DT_NODELABEL(child))
DT_PARENT(DT_PARENT(DT_NODELABEL(child))
```

**Parameters**

- node_id – node identifier

**Returns**

a node identifier for the node's parent's parent

DT_CHILD(node_id, child)
Get a node identifier for a child node.

Example devicetree fragment:

```
/ {
    soc-label: soc {
        serial1: serial@40001000 {
            status = "okay";
            current-speed = <115200>;
            ... 
        }
    };
};
```

Example usage with DT_PROP() to get the status of the serial@40001000 node:

```
#define SOC_NODE DT_NODELABEL(soc_label)
DT_PROP(DT_CHILD(SOC_NODE, serial_40001000), status) // "okay"
```

Node labels like serial1 cannot be used as the child argument to this macro. Use DT_NODELABEL() for that instead.

You can also use DT_FOREACH_CHILD() to iterate over node identifiers for all of a node's children.

**Parameters**

- node_id – node identifier
- child – lowercase-and-underscores child node name

**Returns**

node identifier for the node with the name referred to by ‘child’

DT_COMPAT_GET_ANY_STATUS_OKAY(compat)
Get a node identifier for a status okay node with a compatible.

Use this if you want to get an arbitrary enabled node with a given compatible, and you do not care which one you get. If any enabled nodes with the given compatible exist, a node identifier for one of them is returned. Otherwise, DT_INVALID_NODE is returned.
Example devicetree fragment:

```c
node-a {
    compatible = "vnd,device";
    status = "okay";
};

node-b {
    compatible = "vnd,device";
    status = "okay";
};

node-c {
    compatible = "vnd,device";
    status = "disabled";
};
```

Example usage:

```c
DT_COMPAT_GET_ANY_STATUS_OKAY(vnd_device)
```

This expands to a node identifier for either node-a or node-b. It will not expand to a node identifier for node-c, because that node does not have status okay.

**Parameters**

- `compat` – lowercase-and-underscores compatible, without quotes

**Returns**

node identifier for a node with that compatible, or `DT_INVALID_NODE`

`DT_NODE_PATH(node_id)`

Get a devicetree node's full path as a string literal.

This returns the path to a node from a node identifier. To get a node identifier from path components instead, use `DT_PATH()`.

Example devicetree fragment:

```c
/ {
    soc {
        node: my-node@12345678 { ... };
    };
};
```

Example usage:

```c
DT_NODE_PATH(DT_NODELABEL(node)) // "/soc/my-node@12345678"
DT_NODE_PATH(DT_PATH(soc)) // "/soc"
DT_NODE_PATH(DT_ROOT) // "/
```

**Parameters**

- `node_id` – node identifier

**Returns**

the node's full path in the devicetree

`DT_NODE_FULL_NAME(node_id)`

Get a devicetree node's name with unit-address as a string literal.

This returns the node name and unit-address from a node identifier.

Example devicetree fragment:
Example usage:

```c
DT_NODE_FULL_NAME(DT_NODELABEL(node)) // "my-node@12345678"
```

**Parameters**
- `node_id` – node identifier

**Returns**
the node’s name with unit-address as a string in the devicetree

### DT_NODE_CHILD_IDX(node_id)

Get a devicetree node’s index into its parent’s list of children.
Indexes are zero-based.
It is an error to use this macro with the root node.

Example devicetree fragment:

```
parent {
  c1: child-1 {};
  c2: child-2 {};
};
```

Example usage:

```c
DT_NODE_CHILD_IDX(DT_NODELABEL(c1)) // 0
DT_NODE_CHILD_IDX(DT_NODELABEL(c2)) // 1
```

**Parameters**
- `node_id` – node identifier

**Returns**
the node’s index in its parent node’s list of children

### DT_SAME_NODE(node_id1, node_id2)

Do `node_id1` and `node_id2` refer to the same node?

Both `node_id1` and `node_id2` must be node identifiers for nodes that exist in the devicetree (if unsure, you can check with `DT_NODE_EXISTS()`).
The expansion evaluates to 0 or 1, but may not be a literal integer 0 or 1.

**Parameters**
- `node_id1` – first node identifier
- `node_id2` – second node identifier

**Returns**
an expression that evaluates to 1 if the node identifiers refer to the same node, and evaluates to 0 otherwise

5.2. Devicetree
Property access  
The following general-purpose macros can be used to access node properties. There are special-purpose APIs for accessing the `ranges property`, `reg property` and `interrupts property`.

Property values can be read using these macros even if the node is disabled, as long as it has a matching binding.

```c
DT_PROP(node_id, prop)
```

Get a devicetree property value.

For properties whose bindings have the following types, this macro expands to:

- string: a string literal
- boolean: 0 if the property is false, or 1 if it is true
- int: the property's value as an integer literal
- array, uint8-array, string-array: an initializer expression in braces, whose elements are integer or string literals (like `{0, 1, 2}, {"hello", "world"}`, etc.)
- phandle: a node identifier for the node with that phandle

A property's type is usually defined by its binding. In some special cases, it has an assumed type defined by the devicetree specification even when no binding is available: `compatible` has type string-array, `status` has type string, and `interrupt-controller` has type boolean.

For other properties or properties with unknown type due to a missing binding, behavior is undefined.

For usage examples, see `DT_PATH()`, `DT_ALIAS()`, `DT_NODELABEL()`, and `DT_INST()` above.

Parameters

- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name

Returns

a representation of the property's value

```c
DT_PROP_LEN(node_id, prop)
```

Get a property's logical length.

Here, “length” is a number of elements, which may differ from the property’s size in bytes.

The return value depends on the property's type:

- for types array, string-array, and uint8-array, this expands to the number of elements in the array
- for type phandles, this expands to the number of phandles
- for type phandle-array, this expands to the number of phandle and specifier blocks in the property
• for type phandle, this expands to 1 (so that a phandle can be treated as a degenerate case of phandles with length 1)
• for type string, this expands to 1 (so that a string can be treated as a degenerate case of string-array with length 1)

These properties are handled as special cases:

• reg property: use `DT_NUM_REGS(node_id)` instead
• interrupts property: use `DT_NUM_IRQS(node_id)` instead

It is an error to use this macro with the `ranges`, `dma-ranges`, `reg` or `interrupts` properties.

For other properties, behavior is undefined.

**Parameters**

- `node_id` – node identifier
- `prop` – a lowercase-and-underscores property with a logical length

**Returns**

the property's length

`DT_PROP_LEN_OR(node_id, prop, default_value)`

Like `DT_PROP_LEN()`, but with a fallback to `default_value`.

If the property is defined (as determined by `DT_NODE_HAS_PROP()`), this expands to `DT_PROP_LEN(node_id, prop)`. The `default_value` parameter is not expanded in this case.

Otherwise, this expands to `default_value`.

**Parameters**

- `node_id` – node identifier
- `prop` – a lowercase-and-underscores property with a logical length
- `default_value` – a fallback value to expand to

**Returns**

the property's length or the given default value

`DT_PROP_HAS_IDX(node_id, prop, idx)`

Is index `idx` valid for an array type property?

If this returns 1, then `DT_PROP_BY_IDX(node_id, prop, idx)` or `DT_PHA_BY_IDX(node_id, prop, idx, ...)` are valid at index `idx`. If it returns 0, it is an error to use those macros with that index.

These properties are handled as special cases:

• reg property: use `DT_REG_HAS_IDX(node_id, idx)` instead
• interrupts property: use `DT_IRQ_HAS_IDX(node_id, idx)` instead

It is an error to use this macro with the `reg` or `interrupts` properties.

**Parameters**

- `node_id` – node identifier
- `prop` – a lowercase-and-underscores property with a logical length
- `idx` – index to check
Returns
An expression which evaluates to 1 if idx is a valid index into the given property, and 0 otherwise.

DT_PROP_HAS_NAME(node_id, prop, name)
Is name name available in a foo-names property?
This property is handled as special case:

• interrupts property: use DT_IRQ_HAS_NAME(node_id, idx) instead
It is an error to use this macro with the interrupts property.

Example devicetree fragment:
```c
nx: node-x {
    foos = <&bar xx yy>, <&baz xx zz>;
    foo-names = "event", "error";
    status = "okay";
};
```

Example usage:
```
DT_PROP_HAS_NAME(DT_NODELABEL(nx), foos, event) // 1
DT_PROP_HAS_NAME(DT_NODELABEL(nx), foos, failure) // 0
```

Parameters
• node_id – node identifier
• prop – a lowercase-and-underscores prop-names type property
• name – a lowercase-and-underscores name to check

Returns
An expression which evaluates to 1 if “name” is an available name into the given property, and 0 otherwise.

DT_PROP_BY_IDX(node_id, prop, idx)
Get the value at index idx in an array type property.
It might help to read the argument order as being similar to node->property[index].
The return value depends on the property's type:

• for types array, string-array, uint8-array, and phandles, this expands to the idx-th array element as an integer, string literal, integer, and node identifier respectively
• for type phandle, idx must be 0 and the expansion is a node identifier (this treats phandle like a phandles of length 1)
• for type string, idx must be 0 and the expansion is the the entire string (this treats string like string-array of length 1)
These properties are handled as special cases:

• reg: use DT_REG_ADDR_BY_IDX() or DT_REG_SIZE_BY_IDX() instead
• interrupts: use DT_IRQ_BY_IDX()
For properties of other types, behavior is undefined.

**Parameters**

- node_id – node identifier
- prop – lowercase-and-underscores property name
- idx – the index to get

**Returns**

a representation of the idx-th element of the property

\[
\text{DT\_PROP\_OR}(\text{node\_id}, \text{prop}, \text{default\_value})
\]

Like \( \text{DT\_PROP} \), but with a fallback to default_value.

If the value exists, this expands to \( \text{DT\_PROP}(\text{node\_id}, \text{prop}) \). The default_value parameter is not expanded in this case.

Otherwise, this expands to default_value.

**Parameters**

- node_id – node identifier
- prop – lowercase-and-underscores property name
- default_value – a fallback value to expand to

**Returns**

the property's value or default_value

\[
\text{DT\_ENUM\_IDX}(\text{node\_id}, \text{prop})
\]

Get a property value's index into its enumeration values.

The return values start at zero.

Example devicetree fragment:

```
usb1: usb@12340000 {
    maximum-speed = "full-speed";
};
usb2: usb@12341000 {
    maximum-speed = "super-speed";
};
```

Example bindings fragment:

```
properties:
  maximum-speed:
    type: string
    enum:
      - "low-speed"
      - "full-speed"
      - "high-speed"
      - "super-speed"
```

Example usage:

```
DT\_ENUM\_IDX(DT\_NODELABEL(usb1), maximum-speed) // 1
DT\_ENUM\_IDX(DT\_NODELABEL(usb2), maximum-speed) // 3
```

**Parameters**

- node_id – node identifier
- prop – lowercase-and-underscores property name
Returns
zero-based index of the property's value in its enum: list

DT_ENUM_IDX_OR(node_id, prop, default_idx_value)
Like DT_ENUM_IDX(), but with a fallback to a default enum index.
If the value exists, this expands to its zero based index value thanks to DT_ENUM_IDX(node_id, prop).
Otherwise, this expands to provided default index enum value.

Parameters
• node_id – node identifier
• prop – lowercase-and-underscores property name
• default_idx_value – a fallback index value to expand to

Returns
zero-based index of the property's value in its enum if present, default_idx_value otherwise

DT_ENUM_HAS_VALUE(node_id, prop, value)
Does a node enumeration property have a given value?

Parameters
• node_id – node identifier
• prop – lowercase-and-underscores property name
• value – lowercase-and-underscores enumeration value

Returns
1 if the node property has the value value, 0 otherwise.

DT_STRING_TOKEN(node_id, prop)
Get a string property's value as a token.
This removes “the quotes” from a string property's value, converting any non-alphanumeric characters to underscores. This can be useful, for example, when programatically using the value to form a C variable or code.

DT_STRING_TOKEN() can only be used for properties with string type.
It is an error to use DT_STRING_TOKEN() in other circumstances.

Example devicetree fragment:

```
n1: node-1 {
    prop = "foo";
};
n2: node-2 {
    prop = "FOO";
}
n3: node-3 {
    prop = "123 foo";
};
```

Example bindings fragment:

```
properties:
    prop:
        type: string
```

Example usage:
Notice how:

- Unlike C identifiers, the property values may begin with a number. It's the user's responsibility not to use such values as the name of a C identifier.
- The uppercased "F00" in the DTS remains F00 as a token. It is not converted to foo.
- The whitespace in the DTS "123 foo" string is converted to 123_foo as a token.

**Parameters**

- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name

**Returns**

the value of `prop` as a token, i.e. without any quotes and with special characters converted to underscores

`DT_STRING_TOKEN(node_id, prop, default_value)`

Like `DT_STRING_TOKEN()`, but with a fallback to `default_value`.

If the value exists, this expands to `DT_STRING_TOKEN(node_id, prop)`. The `default_value` parameter is not expanded in this case.

Otherwise, this expands to `default_value`.

**Parameters**

- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name
- `default_value` – a fallback value to expand to

**Returns**

the property's value as a token, or `default_value`

`DT_STRING_UPPER_TOKEN(node_id, prop)`

Like `DT_STRING_TOKEN()`, but uppercased.

This removes “the quotes” from a string property's value, converting any non-alphanumeric characters to underscores, and capitalizing the result. This can be useful, for example, when programmatically using the value to form a C variable or code.

`DT_STRING_UPPER_TOKEN()` can only be used for properties with string type.

It is an error to use `DT_STRING_UPPER_TOKEN()` in other circumstances.

Example devicetree fragment:

```plaintext
n1: node-1 {
    prop = "foo";
};
n2: node-2 {
    prop = "123 foo";
};
```

Example bindings fragment:
properties:
  prop:
    type: string

Example usage:

DT_STRING_UPPER_TOKEN(DT_NODELABEL(n1), prop) // FOO
DT_STRING_UPPER_TOKEN(DT_NODELABEL(n2), prop) // 123_FOO

Notice how:

- Unlike C identifiers, the property values may begin with a number. It's the user's responsibility not to use such values as the name of a C identifier.
- The lowercased "foo" in the DTS becomes FOO as a token, i.e. it is uppercased.
- The whitespace in the DTS "123 foo" string is converted to 123_FOO as a token, i.e. it is uppercased and whitespace becomes an underscore.

Parameters

- node_id – node identifier
- prop – lowercase-and-underscores property name

Returns

the value of prop as an uppercased token, i.e. without any quotes and with special characters converted to underscores

DT_STRING_UPPER_TOKEN_OR(node_id, prop, default_value)

Like DT_STRING_UPPER_TOKEN(), but with a fallback to default_value.

If the value exists, this expands to DT_STRING_UPPER_TOKEN(node_id, prop). The default_value parameter is not expanded in this case.

Otherwise, this expands to default_value.

Parameters

- node_id – node identifier
- prop – lowercase-and-underscores property name
- default_value – a fallback value to expand to

Returns

the property's value as an uppercased token, or default_value

DT_STRING_UNQUOTED(node_id, prop)

Get a string property's value as an unquoted sequence of tokens.

This removes "the quotes" from string-valued properties. That can be useful, for example, when defining floating point values as a string in devicetree that you would like to use to initialize a float or double variable in C.

DT_STRING_UNQUOTED() can only be used for properties with string type.

It is an error to use DT_STRING_UNQUOTED() in other circumstances.

Example devicetree fragment:
Example bindings fragment:

```
p3: node-3 {
    prop = "A B C";
};
```

Example usage:

```
DT_STRING_UNQUOTED(DT_NODELABEL(n1), prop)  // 12.7
DT_STRING_UNQUOTED(DT_NODELABEL(n2), prop)  // 0.5
DT_STRING_UNQUOTED(DT_NODELABEL(n3), prop)  // A B C
```

Parameters
- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name

Returns
the property's value as a sequence of tokens, with no quotes

**DT_STRING_UNQUOTED_OR(node_id, prop, default_value)**
Like `DT_STRING_UNQUOTED()`, but with a fallback to default_value.

If the value exists, this expands to `DT_STRING_UNQUOTED(node_id, prop)`. The default_value parameter is not expanded in this case.

Otherwise, this expands to default_value.

Parameters
- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name
- `default_value` – a fallback value to expand to

Returns
the property's value as a sequence of tokens, with no quotes, or default_value

**DT_STRING_TOKEN_BY_IDX(node_id, prop, idx)**
Get an element out of a string-array property as a token.

This removes “the quotes” from an element in the array, and converts non-alphanumeric characters to underscores. That can be useful, for example, when programmatically using the value to form a C variable or code.

`DT_STRING_TOKEN_BY_IDX()` can only be used for properties with string-array type.

It is an error to use `DT_STRING_TOKEN_BY_IDX()` in other circumstances.

Example devicetree fragment:

```
n1: node-1 {
    prop = "f1", "F2";
};
n2: node-2 {
```

(continues on next page)
Example bindings fragment:

```
   prop = "123 foo", "456 FOO";
```

Example usage:

```
DT_STRING_TOKEN_BY_IDX(DT_NODELABEL(n1), prop, 0) // f1
DT_STRING_TOKEN_BY_IDX(DT_NODELABEL(n1), prop, 1) // F2
DT_STRING_TOKEN_BY_IDX(DT_NODELABEL(n2), prop, 0) // 123_foo
DT_STRING_TOKEN_BY_IDX(DT_NODELABEL(n2), prop, 1) // 456_FOO
```

For more information, see `DT_STRING_TOKEN`.

**Parameters**

- node_id – node identifier
- prop – lowercase-and-underscores property name
- idx – the index to get

**Returns**

the element in prop at index idx as a token

`DT_STRING_UPPER_TOKEN_BY_IDX(node_id, prop, idx)`

Like `DT_STRING_TOKEN_BY_IDX()`, but uppercased.

This removes “the quotes” and capitalizes an element in the array, and converts non-alphanumeric characters to underscores. That can be useful, for example, when programmatically using the value to form a C variable or code.

`DT_STRING_UPPER_TOKEN_BY_IDX()` can only be used for properties with string-array type.

It is an error to use `DT_STRING_UPPER_TOKEN_BY_IDX()` in other circumstances.

Example devicetree fragment:

```
n1: node-1 {
    prop = "f1", "F2";
};
n2: node-2 {
    prop = "123 foo", "456 FOO";
};
```

Example bindings fragment:

```
   prop: string-array
```

Example usage:

```
DT_STRING_UPPER_TOKEN_BY_IDX(DT_NODELABEL(n1), prop, 0) // F1
DT_STRING_UPPER_TOKEN_BY_IDX(DT_NODELABEL(n1), prop, 1) // F2
DT_STRING_UPPER_TOKEN_BY_IDX(DT_NODELABEL(n2), prop, 0) // 123_FOO
DT_STRING_UPPER_TOKEN_BY_IDX(DT_NODELABEL(n2), prop, 1) // 456_FOO
```

For more information, see `DT_STRING_UPPER_TOKEN`.
Parameters

- node_id – node identifier
- prop – lowercase-and-underscores property name
- idx – the index to get

Returns

the element in prop at index idx as an uppercased token

\[
\text{DT_STRING_UNQUOTED_BY_IDX}(\text{node_id}, \text{prop}, \text{idx})
\]

Get a string array item value as an unquoted sequence of tokens.

This removes “the quotes” from string-valued item. That can be useful, for example, when defining floating point values as a string in devicetree that you would like to use to initialize a float or double variable in C.

\[\text{DT_STRING_UNQUOTED_BY_IDX()}\] can only be used for properties with string-array type.

It is an error to use \[\text{DT_STRING_UNQUOTED_BY_IDX()}\] in other circumstances.

Example devicetree fragment:

```plaintext
n1: node-1 {
    prop = "12.7", "34.1";
};
n2: node-2 {
    prop = "A B", "C D";
}
```

Example bindings fragment:

```plaintext
properties:
    prop:
        type: string-array
```

Example usage:

```plaintext
DT_STRING_UNQUOTED_BY_IDX(DT_NODELABEL(n1), prop, 0) // 12.7
DT_STRING_UNQUOTED_BY_IDX(DT_NODELABEL(n1), prop, 1) // 34.1
DT_STRING_UNQUOTED_BY_IDX(DT_NODELABEL(n2), prop, 0) // A B
DT_STRING_UNQUOTED_BY_IDX(DT_NODELABEL(n2), prop, 1) // C D
```

Parameters

- node_id – node identifier
- prop – lowercase-and-underscores property name
- idx – the index to get

Returns

the property's value as a sequence of tokens, with no quotes

\[
\text{DT_PROP_BY_PHANDLE_IDX}(\text{node_id}, \text{phs}, \text{idx}, \text{prop})
\]

Get a property value from a phandle in a property.

This is a shorthand for:

\[
\text{DT_PROP(}\text{DT_PHANDLE_BY_IDX(}\text{node_id}, \text{phs, idx}), \text{prop})
\]

That is, prop is a property of the phandle’s node, not a property of node_id.

Example devicetree fragment:
Example usage:

```c
#define N1 DT_NODELABEL(n1)

DT_PROP_BY_PHANDLE_IDX(N1, foo, 0, bar) // 42
DT_PROP_BY_PHANDLE_IDX(N1, foo, 1, baz) // 43
```

**Parameters**
- `node_id` – node identifier
- `phs` – lowercase-and-underscores property with type phandle, phandles, or phandle-array
- `idx` – logical index into phs, which must be zero if phs has type phandle
- `prop` – lowercase-and-underscores property of the phandle's node

**Returns**
the property's value

`DT_PROP_BY_PHANDLE_IDX_OR(node_id, phs, idx, prop, default_value)`

Like `DT_PROP_BY_PHANDLE_IDX()`, but with a fallback to `default_value`.

If the value exists, this expands to `DT_PROP_BY_PHANDLE_IDX(node_id, phs, idx, prop)`.

The `default_value` parameter is not expanded in this case.

Otherwise, this expands to `default_value`.

**Parameters**
- `node_id` – node identifier
- `phs` – lowercase-and-underscores property with type phandle, phandles, or phandle-array
- `idx` – logical index into phs, which must be zero if phs has type phandle
- `prop` – lowercase-and-underscores property of the phandle's node
- `default_value` – a fallback value to expand to

**Returns**
the property's value

`DT_PROP_BY_PHANDLE(node_id, ph, prop)`

Get a property value from a phandle's node.

This is equivalent to `DT_PROP_BY_PHANDLE_IDX(node_id, ph, 0, prop)`.

**Parameters**
- `node_id` – node identifier
- `ph` – lowercase-and-underscores property of `node_id` with type phandle
• prop – lowercase-and-underscores property of the phandle's node

Returns
the property's value

\(\text{DT\_PHA\_BY\_IDX}(\text{node}\_\text{id}, \text{pha}, \text{idx}, \text{cell})\)

Get a phandle-array specifier cell value at an index.

It might help to read the argument order as being similar to
node->phandle_array[index].cell. That is, the cell value is in the pha property
of node\_id, inside the specifier at index \text{idx}.

Example devicetree fragment:

```
gpio0: gpio@abcd1234 {
    #gpio-cells = <2>;
};
gpio1: gpio@1234abcd {
    #gpio-cells = <2>;
};
led: led_0 {
    gpios = <@gpio0 17 0x1>, <@gpio1 5 0x3>;
};
```

Bindings fragment for the gpio0 and gpio1 nodes:

```
gpio-cells:
- pin
- flags
```

Above, gpios has two elements:

• index 0 has specifier <17 0x1>, so its pin cell is 17, and its flags cell is 0x1
• index 1 has specifier <5 0x3>, so pin is 5 and flags is 0x3

Example usage:

```
#define LED DT\_NODELABEL(led)

DT\_PHA\_BY\_IDX(LED, gpios, 0, pin)  // 17
DT\_PHA\_BY\_IDX(LED, gpios, 1, flags) // 0x3
```

Parameters

• node\_id – node identifier
• pha – lowercase-and-underscores property with type phandle\_array
• idx – logical index into pha
• cell – lowercase-and-underscores cell name within the specifier at pha
  index \text{idx}

Returns
the cell's value

\(\text{DT\_PHA\_BY\_IDX\_OR}(\text{node}\_\text{id}, \text{pha}, \text{idx}, \text{cell}, \text{default}\_\text{value})\)

Like \(\text{DT\_PHA\_BY\_IDX()}\), but with a fallback to \text{default}\_\text{value}.

If the value exists, this expands to \(\text{DT\_PHA\_BY\_IDX}(\text{node}\_\text{id}, \text{pha}, \text{idx}, \text{cell})\). The default\_value parameter is not expanded in this case.
Otherwise, this expands to default_value.

**Parameters**
- node_id – node identifier
- pha – lowercase-and-underscores property with type phandle-array
- idx – logical index into pha
- cell – lowercase-and-underscores cell name within the specifier at pha index idx
- default_value – a fallback value to expand to

**Returns**
the cell’s value or default_value

DT_PHA(node_id, pha, cell)
Equivalent to DT_PHA_BY_IDX(node_id, pha, 0, cell)

**Parameters**
- node_id – node identifier
- pha – lowercase-and-underscores property with type phandle-array
- cell – lowercase-and-underscores cell name

**Returns**
the cell’s value

DT_PHA_OR(node_id, pha, cell, default_value)
Like DT_PHA(), but with a fallback to default_value.
If the value exists, this expands to DT_PHA(node_id, pha, cell). The default_value parameter is not expanded in this case.
Otherwise, this expands to default_value.

**Parameters**
- node_id – node identifier
- pha – lowercase-and-underscores property with type phandle-array
- cell – lowercase-and-underscores cell name
- default_value – a fallback value to expand to

**Returns**
the cell’s value or default_value

DT_PHA_BY_NAME(node_id, pha, name, cell)
Get a value within a phandle-array specifier by name.
This is like DT_PHA_BY_IDX(), except it treats pha as a structure where each array element has a name.
It might help to read the argument order as being similar to node->phandle_struct.name.cell. That is, the cell value is in the pha property of node_id, treated as a data structure where each array element has a name.

Example devicetree fragment:

```
  n: node {
    io-channels = <&adc1 10>, <&adc2 20>;
    io-channel-names = "SENSOR", "BANDGAP";
  };
```

Bindings fragment for the “adc1” and “adc2” nodes:
io-channel-cells:
  - input

Example usage:

```markdown
DT_PHA_BY_NAME(DT_NODELABEL(n), io_channels, sensor, input) // 10
DT_PHA_BY_NAME(DT_NODELABEL(n), io_channels, bandgap, input) // 20
```

**Parameters**

- node_id – node identifier
- pha – lowercase-and-underscores property with type phandle-array
- name – lowercase-and-underscores name of a specifier in pha
- cell – lowercase-and-underscores cell name in the named specifier

**Returns**

the cell's value

**DT_PHA_BY_NAME_OR(node_id, pha, name, cell, default_value)**

Like *DT_PHA_BY_NAME()*, but with a fallback to default_value.

If the value exists, this expands to *DT_PHA_BY_NAME(node_id, pha, name, cell)*. The default_value parameter is not expanded in this case.

Otherwise, this expands to default_value.

**Parameters**

- node_id – node identifier
- pha – lowercase-and-underscores property with type phandle-array
- name – lowercase-and-underscores name of a specifier in pha
- cell – lowercase-and-underscores cell name in the named specifier
- default_value – a fallback value to expand to

**Returns**

the cell's value or default_value

**DT_PHANDLE_BY_NAME(node_id, pha, name)**

Get a phandle's node identifier from a phandle array by name.

It might help to read the argument order as being similar to node->phandle_struct.name.phandle. That is, the phandle array is treated as a structure with named elements. The return value is the node identifier for a phandle inside the structure.

Example devicetree fragment:

```markdown
adc1: adc@abcd1234 {
   foobar = "ADC_1";
};

adc2: adc@234abcd {
   foobar = "ADC_2";
};

n: node {
   io-channels = <adc1 10>, <adc2 20>;
   io-channel-names = "SENSOR", "BANDGAP";
};
```
Above, “io-channels” has two elements:

- the element named “SENSOR” has phandle &adc1
- the element named “BANDGAP” has phandle &adc2

Example usage:

```c
#define NODE DT_NODELABEL(n)

define NODE DT_NODELABEL(n)

DT_PROP(DT_PHANDLE_BY_NAME(NODE, io_channels, sensor), foobar) // "ADC_1"
DT_PROP(DT_PHANDLE_BY_NAME(NODE, io_channels, bandgap), foobar) // "ADC_2"
```

Notice how devicetree properties and names are lowercased, and non-alphanumeric characters are converted to underscores.

**Parameters**

- node_id – node identifier
- pha – lowercase-and-underscores property with type phandle-array
- name – lowercase-and-underscores name of an element in pha

**Returns**

a node identifier for the node with that phandle

**DT_PHANDLE_BY_IDX(node_id, prop, idx)**

Get a node identifier for a phandle in a property.

When a node's value at a logical index contains a phandle, this macro returns a node identifier for the node with that phandle.

Therefore, if prop has type phandle, idx must be zero. (A phandle type is treated as a phandles with a fixed length of 1).

Example devicetree fragment:

```c
n1: node-1 {
    foo = &n2 &n3;
};

n2: node-2 {
    ...
};

n3: node-3 {
    ...
};
```

Above, foo has type phandles and has two elements:

- index 0 has phandle &n2, which is node-2’s phandle
- index 1 has phandle &n3, which is node-3’s phandle

Example usage:

```c
#define N1 DT_NODELABEL(n1)

DT_PHANDLE_BY_IDX(N1, foo, 0) // node identifier for node-2
DT_PHANDLE_BY_IDX(N1, foo, 1) // node identifier for node-3
```

Behavior is analogous for phandle-arrays.

**Parameters**

- node_id – node identifier
- prop – lowercase-and-underscores property name in node_id with type phandle, phandles or phandle-array
• idx – index into prop

**Returns**
node identifier for the node with the phandle at that index

**DT_PHANDLE**(node_id, prop)
Get a node identifier for a phandle property's value.
This is equivalent to **DT_PHANDLE_BY_IDX**(node_id, prop, 0). Its primary benefit is readability when prop has type phandle.

**Parameters**

• node_id – node identifier
• prop – lowercase-and-underscores property of node_id with type phandle

**Returns**
a node identifier for the node pointed to by “ph”

ranges property  Use these APIs instead of Property access to access the ranges property. Because this property's semantics are defined by the devicetree specification, these macros can be used even for nodes without matching bindings. However, they take on special semantics when the node's binding indicates it is a PCIe bus node, as defined in the PCI Bus Binding to: IEEE Std 1275-1994 Standard for Boot (Initialization Configuration) Firmware

group devicetree-ranges-prop

**Defines**

**DT_NUM_RANGES**(node_id)
Get the number of range blocks in the ranges property.
Use this instead of **DT_PROP_LEN**(node_id, ranges).

Example devicetree fragment:

```markdown
PCIE0: pcie0 @0 {
  compatible = "pcie-controller";
  reg = <0 1>
  #address-cells = <3>
  #size-cells = <2>
  ranges = <0x1000000 0 0 0x3eff0000 0 0x10000>,
              <0x2000000 0x10000000 0x10000000 0x2eff0000>,
              <0x3000000 0x80 0x80 0x80 0x80 0x80 0x80>;
}

OTHER: other @1 {
  reg = <1 1>
  ranges = <0x0 0x0 0x3eff0000 0x10000>,
              <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
}
```

Example usage:

```markdown
DT_NUM_RANGES(DT_NODELABEL(pcie0)) // 3
DT_NUM_RANGES(DT_NODELABEL(other)) // 2
```
Parameters

- **node_id** – node identifier

**DT_RANGES_HAS_IDX(node_id, idx)**

Is idx a valid range block index?

If this returns 1, then **DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(node_id, idx)**, **DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(node_id, idx)** or **DT_RANGES_LENGTH_BY_IDX(node_id, idx)** are valid. For **DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(node_id, idx)** the return value of **DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(node_id, idx)** will indicate validity. If it returns 0, it is an error to use those macros with index idx, including **DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(node_id, idx)**.

Example devicetree fragment:

```dts
pcie0: pcie@0 {
    compatible = "pcie-controller";
    reg = <0 1>;
    #address-cells = <3>;
    #size-cells = <2>;
    ranges = <0x1000000 0 0 0 0x3eff0000 0 0x10000>,
             <0x2000000 0 0x10000000 0 0x10000000 0x2eff0000>,
             <0x3000000 0x80 0 x80 0 0x80 0>;
};
other: other@1 {
    reg = <1 1>;
    ranges = <0x0 0x0 0x0 0x3eff0000 0x10000>,
             <0x0 0x1000000 0x0 0x1000000 0x2eff0000>;
};
```

Example usage:

```c
DT_RANGES_HAS_IDX(DT_NODELABEL(pcie0), 0) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(pcie0), 1) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(pcie0), 2) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(pcie0), 3) // 0
DT_RANGES_HAS_IDX(DT_NODELABEL(other), 0) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(other), 1) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(other), 2) // 0
DT_RANGES_HAS_IDX(DT_NODELABEL(other), 3) // 0
```

Parameters

- **node_id** – node identifier
- **idx** – index to check

Returns

1 if idx is a valid register block index, 0 otherwise.

**DT_RANGES_HAS.Child_BUS_FLAGS_AT_IDX(node_id, idx)**

Does a ranges property have child bus flags at index?

If this returns 1, then **DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(node_id, idx)** is valid. If it returns 0, it is an error to use this macro with index idx. This macro only returns 1 for PCIe buses (i.e. nodes whose bindings specify they are “pcie” bus nodes.)

Example devicetree fragment:
Example usage:

```c
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(pcie0), 0) // 1
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(pcie0), 1) // 1
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(pcie0), 2) // 1
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(pcie0), 3) // 0
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(other), 0) // 0
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(other), 1) // 0
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(other), 2) // 0
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(other), 3) // 0
```

**Parameters**

- **node_id** – node identifier
- **idx** – logical index into the ranges array

**Returns**

1 if idx is a valid child bus flags index, 0 otherwise.

**Example devicetree fragments:**

```c
parent {
    #address-cells = <2>;

    pcie0: pcie0 {  
        compatible = "pcie-controller";
        reg = <0 @1>;
        #address-cells = <3>;
        #size-cells = <2>;
        ranges = <0x1000000 0 0 0x3eff0000 0x10000>,
                 <0x2000000 0x10000000 0x10000000 0x2eff0000>,
                 <0x3000000 0x80 0x80 0x80 0x80 0>
    };

    other: other0 {  
        reg = <0 @1>;
        ranges = <0x0 0x0 0x3eff0000 0x10000>,
                 <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
    };
}
```

When the node is a PCIe bus, the Child Bus Address has an extra cell used to store some flags, thus this cell is extracted from the Child Bus Address as Child Bus Flags field.

**Parameters**

- **node_id** – node identifier
- **idx** – logical index into the ranges array

**Returns**

1 if idx is a valid child bus flags index, 0 otherwise.

**Example devicetree fragments:**

```c
parent {
    #address-cells = <2>;

    pcie0: pcie0 {  
        compatible = "pcie-controller";
        reg = <0 @1>;
        #address-cells = <3>;
        #size-cells = <2>;
        ranges = <0x1000000 0 0 0x3eff0000 0x10000>,
                 <0x2000000 0x10000000 0x10000000 0x2eff0000>,
                 <0x3000000 0x80 0x80 0x80 0x80 0>
    };

    other: other0 {  
        reg = <0 @1>;
        ranges = <0x0 0x0 0x3eff0000 0x10000>,
                 <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
    };
}
```
Example usage:

```c
DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(DT_NODELABEL(pcie0), 0) // 0x1000000
DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(DT_NODELABEL(pcie0), 1) // 0x2000000
DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(DT_NODELABEL(pcie0), 2) // 0x3000000
```

### Parameters

- `node_id` – node identifier
- `idx` – logical index into the ranges array

### Returns

range child bus flags field at idx

### DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(node_id, idx)

Get the ranges property child bus address at index.

When the node is a PCIe bus, the Child Bus Address has an extra cell used to store some flags, thus this cell is removed from the Child Bus Address.

Example devicetree fragments:

```c
parent {
    #address-cells = <2>;
    pcie0: pcie0 { 
        compatible = "pcie-controller";
        reg = <0 0 1>;
        #address-cells = <3>;
        #size-cells = <2>;
        ranges = <0x1000000 0 0 0x3eff0000 0 0x10000>,
                 <0x2000000 0x10000000 0x10000000 0x2eff0000>,
                 <0x3000000 0x80 0 x80 0 x80 0>;
    };
    other: other@1 { 
        reg = <0 1 1>;
        ranges = <0x0 0x0 0x0 0x3eff0000 0x10000>,
                 <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
    };
};
```

Example usage:

```c
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 0) // 0
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 1) // 0x1000000
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 2) // 0x8000000000
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(other), 0) // 0
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(other), 1) // 0x1000000
```

### Parameters

- `node_id` – node identifier
- `idx` – logical index into the ranges array
Returns
range child bus address field at idx

DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(node_id, idx)
Get the ranges property parent bus address at index.

Similarly to DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(), this properly accounts for
child bus flags cells when the node is a PCIe bus.

Example devicetree fragment:

```devicetree
parent {
    #address-cells = <2>;

    pcie0: pcie@0 {
        compatible = "pcie-controller";
        reg = <0 0>;
        #address-cells = <3>;
        #size-cells = <2>;
        ranges = <0x1000000 0 0 0x3eff0000 0x10000>,
                <0x2000000 0x10000000 0x10000000 0x2eff0000>,
                <0x3000000 0x80 0 0x80 0 0x80 0>;
    };

    other: other@1 {
        reg = <0 1 1>;
        ranges = <0x0 0x0 0x3eff0000 0x10000>,
                 <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
    };
};
```

Example usage:

```devicetxt
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 0) // 0x3eff0000
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 1) // 0x10000000
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 2) // 0x8000000000
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(other), 0) // 0x3eff0000
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(other), 1) // 0x10000000
```

Parameters
• node_id – node identifier
• idx – logical index into the ranges array

Returns
range parent bus address field at idx

DT_RANGES_LENGTH_BY_IDX(node_id, idx)
Get the ranges property length at index.

Similarly to DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(), this properly accounts for
child bus flags cells when the node is a PCIe bus.

Example devicetree fragment:

```devicetree
parent {
    #address-cells = <2>;

    pcie0: pcie@0 {
        compatible = "pcie-controller";
```

(continues on next page)
reg = <0 0 1>;  
#address-cells = <3>;  
#size-cells = <2>;  

ranges = <0x1000000 0 0 0x3eff0000 0x10000>,  
  <0x2000000 0x10000000 0x10000000 0x2eff0000>,  
  <0x3000000 0x80 0 0x80 0x80 0>;  
};  

other: other@1 {  
  reg = <0 1 1>;  

ranges = <0x0 0x0 0x0 0x3eff0000 0x10000>,  
  <0x0 0x1000000 0x0 0x10000000 0x2eff0000>;  
};  

Parameters

- node_id – node identifier
- fn – macro to invoke

**reg property** Use these APIs instead of *Property access* to access the reg property. Because this property's semantics are defined by the devicetree specification, these macros can be used even for nodes without matching bindings.

**group devicetree-reg-prop**

**Defines**

`DT_NUM_REGS(node_id)`
Get the number of register blocks in the reg property.
Use this instead of `DT_PROP_LEN(node_id, reg)`.

**Parameters**

- node_id – node identifier

**Returns**

Number of register blocks in the node's “reg” property.

`DT_REG_HAS_IDX(node_id, idx)`
Is idx a valid register block index?
If this returns 1, then `DT_REG_ADDR_BY_IDX(node_id, idx)` or `DT_REG_SIZE_BY_IDX(node_id, idx)` are valid. If it returns 0, it is an error to use those macros with index idx.

**Parameters**

- node_id – node identifier
- idx – index to check

**Returns**

1 if idx is a valid register block index, 0 otherwise.

`DT_REG_ADDR_BY_IDX(node_id, idx)`
Get the base address of the register block at index idx.

**Parameters**

- node_id – node identifier
- idx – index of the register whose address to return

**Returns**

address of the idx-th register block

`DT_REG_SIZE_BY_IDX(node_id, idx)`
Get the size of the register block at index idx.
This is the size of an individual register block, not the total number of register blocks in the property; use `DT_NUM_REGS()` for that.

**Parameters**

- node_id – node identifier
- idx – index of the register whose size to return
Returns
size of the idx-th register block

DT_REG_ADDR(node_id)
Get a node's (only) register block address.
Equivalent to DT_REG_ADDR_BY_IDX(node_id, 0).

Parameters
• node_id – node identifier

Returns
node's register block address

DT_REG_ADDR_U64(node_id)
64-bit version of DT_REG_ADDR()
This macro version adds the appropriate suffix for 64-bit unsigned integer literals.
Note that this macro is equivalent to DT_REG_ADDR() in linker/ASM context.

Parameters
• node_id – node identifier

Returns
node's register block address

DT_REG_SIZE(node_id)
Get a node's (only) register block size.
Equivalent to DT_REG_SIZE_BY_IDX(node_id, 0).

Parameters
• node_id – node identifier

Returns
node's only register block's size

DT_REG_ADDR_BY_NAME(node_id, name)
Get a register block's base address by name.

Parameters
• node_id – node identifier
• name – lowercase-and-underscores register specifier name

Returns
address of the register block specified by name

DT_REG_ADDR_BY_NAME_U64(node_id, name)
64-bit version of DT_REG_ADDR_BY_NAME()
This macro version adds the appropriate suffix for 64-bit unsigned integer literals.
Note that this macro is equivalent to DT_REG_ADDR_BY_NAME() in linker/ASM context.

Parameters
• node_id – node identifier
• name – lowercase-and-underscores register specifier name

Returns
address of the register block specified by name
DT_REG_SIZE_BY_NAME(node_id, name)
Get a register block's size by name.

Parameters
• node_id – node identifier
• name – lowercase-and-underscores register specifier name

Returns
size of the register block specified by name

interrupts property  Use these APIs instead of Property access to access the interrupts property.
Because this property's semantics are defined by the devicetree specification, some of these macros can be used even for nodes without matching bindings. This does not apply to macros which take cell names as arguments.

group devicetree-interrupts-prop

Defines

DT_NUM_IRQS(node_id)
Get the number of interrupt sources for the node.
Use this instead of DT_PROP_LEN(node_id, interrupts).

Parameters
• node_id – node identifier

Returns
Number of interrupt specifiers in the node's “interrupts” property.

DT_IRQ_LEVEL(node_id)
Get the interrupt level for the node.

Parameters
• node_id – node identifier

Returns
interrupt level

DT_IRQ_HAS_IDX(node_id, idx)
Is idx a valid interrupt index?
If this returns 1, then DT_IRQ_BY_IDX(node_id, idx) is valid. If it returns 0, it is an error to use that macro with this index.

Parameters
• node_id – node identifier
• idx – index to check

Returns
1 if the idx is valid for the interrupt property 0 otherwise.

DT_IRQ_HAS_CELL_AT_IDX(node_id, idx, cell)
Does an interrupts property have a named cell specifier at an index? If this returns 1, then DT_IRQ_BY_IDX(node_id, idx, cell) is valid.
If it returns 0, it is an error to use that macro.
Parameters
- node_id – node identifier
- idx – index to check
- cell – named cell value whose existence to check

Returns
1 if the named cell exists in the interrupt specifier at index idx 0 otherwise.

```
DT_IRQ_HAS_CELL(node_id, cell)
```
Equivalent to `DT_IRQ_HAS_CELL_AT_IDX(node_id, 0, cell)`

Parameters
- node_id – node identifier
- cell – named cell value whose existence to check

Returns
1 if the named cell exists in the interrupt specifier at index 0 0 otherwise.

```
DT_IRQ_HAS_NAME(node_id, name)
```
Does an interrupts property have a named specifier value at an index? If this returns 1, then `DT_IRQ_BY_NAME(node_id, name, cell)` is valid.

If it returns 0, it is an error to use that macro.

Parameters
- node_id – node identifier
- name – lowercase-and-underscores interrupt specifier name

Returns
1 if “name” is a valid named specifier 0 otherwise.

```
DT_IRQ_BY_IDX(node_id, idx, cell)
```
Get a value within an interrupt specifier at an index.

It might help to read the argument order as being similar to “node->interrupts[index].cell”.

This can be used to get information about an individual interrupt when a device generates more than one.

Example devicetre fragment:

```
my-serial: serial@abcd1234 {
    interrupts = < 33 0 >, < 34 1 >;
};
```

Assuming the node's interrupt domain has “#interrupt-cells = <2>;” and the individual cells in each interrupt specifier are named “irq” and “priority” by the node's binding, here are some examples:

```
#define SERIAL DT_NODELABEL(my_serial)
```

<table>
<thead>
<tr>
<th>Example usage</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>DT_IRQ_BY_IDX(SERIAL, 0, irq)</td>
<td>33</td>
</tr>
<tr>
<td>DT_IRQ_BY_IDX(SERIAL, 0, priority)</td>
<td>0</td>
</tr>
<tr>
<td>DT_IRQ_BY_IDX(SERIAL, 1, irq)</td>
<td>34</td>
</tr>
<tr>
<td>DT_IRQ_BY_IDX(SERIAL, 1, priority)</td>
<td>1</td>
</tr>
</tbody>
</table>
• node_id – node identifier
• idx – logical index into the interrupt specifier array
• cell – cell name specifier

Returns
the named value at the specifier given by the index

DT_IRQ_BY_NAME(node_id, name, cell)
Get a value within an interrupt specifier by name.
It might help to read the argument order as being similar to node->interrupts.name.
cell.
This can be used to get information about an individual interrupt when a device generates more than one, if the bindings give each interrupt specifier a name.

Parameters
• node_id – node identifier
• name – lowercase-and-underscores interrupt specifier name
• cell – cell name specifier

Returns
the named value at the specifier given by the index

DT_IRQ(node_id, cell)
Get an interrupt specifier's value Equivalent to DT_IRQ_BYidx(node_id, 0, cell).

Parameters
• node_id – node identifier
• cell – cell name specifier

Returns
the named value at that index

DT_IRQ_INTC_BY_IDX(node_id, idx)
Get an interrupt specifier's interrupt controller by index.
Example usage:

```c
DT_IRQ_INTC_BY_IDX(DT_NODELABEL(foo), 0) // &gpio0
DT_IRQ_INTC_BY_IDX(DT_NODELABEL(foo), 1) // &gpio0
DT_IRQ_INTC_BY_IDX(DT_NODELABEL(bar), 0) // &gpio0
DT_IRQ_INTC_BY_IDX(DT_NODELABEL(bar), 1) // &pic0
DT_IRQ_INTC_BY_IDX(DT_NODELABEL(qux), 0) // &pic0
DT_IRQ_INTC_BY_IDX(DT_NODELABEL(qux), 1) // &pic0
```

**Parameters**
- `node_id` – node identifier
- `idx` – interrupt specifier's index

**Returns**
node_id of interrupt specifier's interrupt controller

**DT_IRQ_INTC_BY_NAME(node_id, name)**
Get an interrupt specifier's interrupt controller by name.

```c
gpio0: gpio0 {
    interrupt-controller;
    #interrupt-cells = <2>;
};
foo: foo {
    interrupt-parent = &gpio0;
    interrupts = <1 1>, <2 2>;
    interrupt-names = "int1", "int2";
};
bar: bar {
    interrupts-extended = &gpio0 3 3>, &pic0 4>; 
    interrupt-names = "int1", "int2";
};
pic0: pic0 {
    interrupt-controller;
    #interrupt-cells = <1>;
    qux: qux {
        interrupts = <5>, <6>;
        interrupt-names = "int1", "int2";
    }; 
};
```

Example usage:

```c
DT_IRQ_INTC_BY_NAME(DT_NODELABEL(foo), int1) // &gpio0
DT_IRQ_INTC_BY_NAME(DT_NODELABEL(foo), int2) // &gpio0
DT_IRQ_INTC_BY_NAME(DT_NODELABEL(bar), int1) // &gpio0
DT_IRQ_INTC_BY_NAME(DT_NODELABEL(bar), int2) // &pic0
DT_IRQ_INTC_BY_NAME(DT_NODELABEL(qux), int1) // &pic0
DT_IRQ_INTC_BY_NAME(DT_NODELABEL(qux), int2) // &pic0
```

**Parameters**
- `node_id` – node identifier
- `name` – interrupt specifier's name

**Returns**
node_id of interrupt specifier's interrupt controller
DT_IRQ_INTC(node_id)
Get an interrupt specifier's interrupt controller.

Example usage:
DT_IRQ_INTC(DT_NODELABEL(foo)) // &gpio0
DT_IRQ_INTC(DT_NODELABEL(bar)) // &gpio0
DT_IRQ_INTC(DT_NODELABEL(qux)) // &pic0

See also:
DT_IRQ_INTC_BY_IDX()

Note: Equivalent to DT_IRQ_INTC_BY_IDX(node_id, 0)

Parameters
• node_id – node identifier

Returns
node_id of interrupt specifier's interrupt controller

DT_IRQN_BY_IDX(node_id, idx)
Get the node's Zephyr interrupt number at index If CONFIG_MULTI_LEVEL_INTERRUPTS is enabled, the interrupt number at index will be multi-level encoded.

Parameters
• node_id – node identifier
• idx – logical index into the interrupt specifier array

Returns
the Zephyr interrupt number

DT_IRQN(node_id)
Get a node's (only) irq number.
Equivalent to \textit{DT_IRQ(node\_id, irq)}. This is provided as a convenience for the common case where a node generates exactly one interrupt, and the IRQ number is in a cell named irq.

**Parameters**
- \textit{node\_id} – node identifier

**Returns**
the interrupt number for the node’s only interrupt

**For-each macros** There is currently only one “generic” for-each macro, \textit{DT\_FOREACH\_CHILD()}, which allows iterating over the children of a devicetree node.

There are special-purpose for-each macros, like \textit{DT\_INST\_FOREACH\_STATUS\_OKAY()}, but these require \texttt{DT\_DRV\_COMPAT} to be defined before use.

\textit{group devicetree\_generic\_foreach}

**Defines**

\texttt{DT\_FOREACH\_NODE(fn)}
Invokes \textit{fn} for every node in the tree.

The macro \textit{fn} must take one parameter, which will be a node identifier. The macro is expanded once for each node in the tree. The order that nodes are visited in is not specified.

**Parameters**
- \textit{fn} – macro to invoke

\texttt{DT\_FOREACH\_NODE\_VARGS(fn, ...)}
Invokes \textit{fn} for every node in the tree with multiple arguments.

The macro \textit{fn} takes multiple arguments. The first should be the node identifier for the node. The remaining are passed-in by the caller.

The macro is expanded once for each node in the tree. The order that nodes are visited in is not specified.

**Parameters**
- \textit{fn} – macro to invoke
- \ldots – variable number of arguments to pass to \textit{fn}

\texttt{DT\_FOREACH\_STATUS\_OKAY\_NODE(fn)}
Invokes \textit{fn} for every status okay node in the tree.

The macro \textit{fn} must take one parameter, which will be a node identifier. The macro is expanded once for each node in the tree with status okay (as usual, a missing status property is treated as status okay). The order that nodes are visited in is not specified.

**Parameters**
- \textit{fn} – macro to invoke

\texttt{DT\_FOREACH\_STATUS\_OKAY\_NODE\_VARGS(fn, ...)}
Invokes \textit{fn} for every status okay node in the tree with multiple arguments.

The macro \textit{fn} takes multiple arguments. The first should be the node identifier for the node. The remaining are passed-in by the caller.
The macro is expanded once for each node in the tree with status okay (as usual, a missing status property is treated as status okay). The order that nodes are visited in is not specified.

**Parameters**

- fn – macro to invoke
- ... – variable number of arguments to pass to fn

### DT_FOREACH_CHILD(node_id, fn)

Invokes fn for each child of node_id.

The macro fn must take one parameter, which will be the node identifier of a child node of node_id.

The children will be iterated over in the same order as they appear in the final device-tree.

**Example devicetree fragment:**

```plaintext
n: node {
    child-1 {
        foobar = "foo";
    };
    child-2 {
        foobar = "bar";
    };
};
```

**Example usage:**

```plaintext
#define FOOBAR_AND_COMMA(node_id) DT_PROP(node_id, foobar),
const char *child_foobars[] = {
    DT_FOREACH_CHILD(DT_NODELABEL(n), FOOBAR_AND_COMMA)
};
```

This expands to:

```plaintext
const char *child_foobars[] = {
    "foo", "bar",
};
```

**Parameters**

- node_id – node identifier
- fn – macro to invoke

### DT_FOREACH_CHILD_SEP(node_id, fn, sep)

Invokes fn for each child of node_id with a separator.

The macro fn must take one parameter, which will be the node identifier of a child node of node_id.

**Example devicetree fragment:**

```plaintext
n: node {
    child-1 {
        ...
    };
    child-2 {
        ...
};
```
Example usage:

```c
const char *child_names[] = {
    DT_FOREACH_CHILD_SEP(DT_NODELABEL(n), DT_NODE_FULL_NAME, (,,))
};
```

This expands to:

```c
const char *child_names[] = {
    "child-1", "child-2"
};
```

**Parameters**
- node_id – node identifier
- fn – macro to invoke
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

**DT_FOREACH_CHILD_VARGS** (node_id, fn, ...)
Invokes fn for each child of node_id with multiple arguments.
The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.
The children will be iterated over in the same order as they appear in the final device-tree.

**See also:**
**DT_FOREACH_CHILD**

**Parameters**
- node_id – node identifier
- fn – macro to invoke
- ... – variable number of arguments to pass to fn

**DT_FOREACH_CHILD_SEP_VARGS** (node_id, fn, sep, ...)
Invokes fn for each child of node_id with separator and multiple arguments.
The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

**See also:**
**DT_FOREACH_CHILD_VARGS**

**Parameters**
- node_id – node identifier
- fn – macro to invoke
• sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
• . . . – variable number of arguments to pass to fn

\textbf{DT_FOREACH_CHILD_STATUS_OKAY} (node\_id, fn)  
Call fn on the child nodes with status okay  
The macro fn should take one argument, which is the node identifier for the child node. As usual, both a missing status and an ok status are treated as okay.  
The children will be iterated over in the same order as they appear in the final device-tree.  

\textbf{Parameters}  
• node\_id – node identifier  
• fn – macro to invoke

\textbf{DT_FOREACH_CHILD_STATUS_OKAY\_SEP} (node\_id, fn, sep)  
Call fn on the child nodes with status okay with separator.  
The macro fn should take one argument, which is the node identifier for the child node. As usual, both a missing status and an ok status are treated as okay.

\textbf{See also:}  
\textbf{DT_FOREACH_CHILD_STATUS_OKAY}

\textbf{Parameters}  
• node\_id – node identifier  
• fn – macro to invoke

\textbf{DT_FOREACH_CHILD_STATUS_OKAY\_VARGS} (node\_id, fn, ...)  
Call fn on the child nodes with status okay with multiple arguments.  
The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller. As usual, both a missing status and an ok status are treated as okay.  
The children will be iterated over in the same order as they appear in the final device-tree.

\textbf{See also:}  
\textbf{DT_FOREACH_CHILD_STATUS_OKAY}

\textbf{Parameters}  
• node\_id – node identifier  
• fn – macro to invoke
• . . . – variable number of arguments to pass to fn
DT_FOREACH_CHILD_STATUS_OKAY_SEP_VARGS(node_id, fn, sep, ...)
Call fn on the child nodes with status okay with separator and multiple arguments.
The macro fn takes multiple arguments. The first should be the node identifier for the
child node. The remaining are passed-in by the caller.
As usual, both a missing status and an ok status are treated as okay.

See also:
DT_FOREACH_CHILD_SEP_STATUS_OKAY

Parameters
- node_id – node identifier
- fn – macro to invoke
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this
  is required to enable providing a comma as separator:
- ... – variable number of arguments to pass to fn

DT_FOREACH_PROP_ELEM(node_id, prop, fn)
Invokes fn for each element in the value of property prop.
The macro fn must take three parameters: fn(node_id, prop, idx). node_id and prop
are the same as what is passed to DT_FOREACH_PROP_ELEM(), and idx is the current
index into the array. The idx values are integer literals starting from 0.
The prop argument must refer to a property that can be passed to DT_PROP_LEN().
Example devicetree fragment:

```
n: node {
  my-ints = <1 2 3>;
};
```
Example usage:

```
#define TIMES_TWO(node_id, prop, idx) \
  (2 * DT_PROP_BY_IDX(node_id, prop, idx)),
int array[] = {
  DT_FOREACH_PROP_ELEM(DT_NODELABEL(n), my_ints, TIMES_TWO)
};
```
This expands to:

```
int array[] = {
  (2 * 1), (2 * 2), (2 * 3),
};
```
In general, this macro expands to:

```
fn(node_id, prop, 0) fn(node_id, prop, 1) [...] fn(node_id, prop, n-1)
```
where n is the number of elements in prop, as it would be returned by
DT_PROP_LEN(node_id, prop).

See also:

DT_PROP_LEN
Parameters

- node_id – node identifier
- prop – lowercase-and-underscores property name
- fn – macro to invoke

DT_FOREACH_PROP_ELEM_SEP(node_id, prop, fn, sep)
Invokes fn for each element in the value of property prop with separator.

Example devicetree fragment:

```c
n: node {
    my-gpios = <&gpioa 0 GPIO_ACTIVE_HIGH>,
    <&gpiob 1 GPIO_ACTIVE_HIGH>;
}
```

Example usage:

```c
struct gpio_dt_spec specs[] = {
    DT_FOREACH_PROP_ELEM_SEP(DT_NODELABEL(n),
        my_gpios,
        GPIO_DT_SPEC_GET_BY_IDX,
        (,))
};
```

This expands as a first step to:

```c
struct gpio_dt_spec specs[] = {
    GPIO_DT_SPEC_GET_BY_IDX(DT_NODELABEL(n),
        my_gpios,
        0),
    GPIO_DT_SPEC_GET_BY_IDX(DT_NODELABEL(n),
        my_gpios,
        1)
};
```

The prop parameter has the same restrictions as the same parameter given to
`DT_FOREACH_PROP_ELEM()`. See also:

`DT_FOREACH_PROP_ELEM` Parameters

- node_id – node identifier
- prop – lowercase-and-underscores property name
- fn – macro to invoke
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this
  is required to enable providing a comma as separator.

DT_FOREACH_PROP_ELEM_VARGS(node_id, prop, fn, ...)
Invokes fn for each element in the value of property prop with multiple arguments.

The macro fn must take multiple parameters: fn(node_id, prop, idx, ...). node_id
and prop are the same as what is passed to `DT_FOREACH_PROP_ELEM()`, and idx is the
current index into the array. The idx values are integer literals starting from 0. The
remaining arguments are passed-in by the caller.

The prop parameter has the same restrictions as the same parameter given to
`DT_FOREACH_PROP_ELEM()`. See also:

`DT_FOREACH_PROP_ELEM`
Parameters

- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name
- `fn` – macro to invoke
- `...` – variable number of arguments to pass to `fn`

**DT_FOREACH_PROP_ELEM_SEP_VARGS**

Invokes `fn` for each element in the value of property `prop` with multiple arguments and a separator.

The `prop` parameter has the same restrictions as the same parameter given to `DT_FOREACH_PROP_ELEM()`.

See also:

**DT_FOREACH_PROP_ELEM_VARGS**

Parameters

- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name
- `fn` – macro to invoke
- `sep` – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- `...` – variable number of arguments to pass to `fn`

**DT_FOREACH_STATUS_OKAY**

Invokes `fn` for each status okay node of a compatible.

This macro expands to:

\[
\text{fn(node_id}_1) \text{ fn(node_id}_2) \ldots \text{ fn(node_id}_n)\\n\]

where each `node_id_{<i>}` is a node identifier for some node with compatible `compat` and status okay. Whitespace is added between expansions as shown above.

Example devicetree fragment:

```
/ {
    a {
        compatible = "foo";
        status = "okay";
    };
    b {
        compatible = "foo";
        status = "disabled";
    };
    c {
        compatible = "foo";
    };
};
```

Example usage:

**DT_FOREACH_STATUS_OKAY**

This expands to one of the following:
“One of the following” is because no guarantees are made about the order that node identifiers are passed to \texttt{fn} in the expansion.

(The /c string literal is present because a missing status property is always treated as if the status were set to \texttt{okay}.)

Note also that \texttt{fn} is responsible for adding commas, semicolons, or other terminators as needed.

\textbf{Parameters}

- \texttt{compat} – lowercase-and-underscores devicetree compatible
- \texttt{fn} – Macro to call for each enabled node. Must accept a node_id as its only parameter.

\texttt{DT_FOREACH_STATUS_OKAY_VARGS} (compat, \texttt{fn}, \ldots )

Invokes \texttt{fn} for each status okay node of a compatible with multiple arguments.

This is like \texttt{DT_FOREACH_STATUS_OKAY()} except you can also pass additional arguments to \texttt{fn}.

Example devicetree fragment:

\begin{verbatim}
/ {
    a {
        compatible = "foo";
        val = <3>;
    };
    b {
        compatible = "foo";
        val = <4>;
    };
};
\end{verbatim}

Example usage:

\begin{verbatim}
#define MY_FN(node_id, operator) DT_PROP(node_id, val) operator
x = DT_FOREACH_STATUS_OKAY_VARGS(foo, MY_FN, +) 0;
\end{verbatim}

This expands to one of the following:

\begin{verbatim}
x = 3 + 4 + 0;
x = 4 + 3 + 0;
\end{verbatim}

i.e. it sets \texttt{x} to 7. As with \texttt{DT_FOREACH_STATUS_OKAY()}, there are no guarantees about the order nodes appear in the expansion.

\textbf{Parameters}

- \texttt{compat} – lowercase-and-underscores devicetree compatible
- \texttt{fn} – Macro to call for each enabled node. Must accept a node_id as its only parameter.
- \ldots – Additional arguments to pass to \texttt{fn}

\textbf{Existence checks} This section documents miscellaneous macros that can be used to test if a node exists, how many nodes of a certain type exist, whether a node has certain properties, etc. Some macros used for special purposes (such as \texttt{DT_IRQ_HAS_IDX()} and all macros which require \texttt{DT_DRV_COMPAT}) are documented elsewhere on this page.
Related code samples

**GPIO with custom Devicetree binding**

Use custom Devicetree binding to control a GPIO.

```plaintext
group devicetree-generic-exist

Defines

**DT_NODE_EXISTS**(node_id)

Does a node identifier refer to a node?

Tests whether a node identifier refers to a node which exists, i.e. is defined in the devicetree.

It doesn’t matter whether or not the node has a matching binding, or what the node’s status value is. This is purely a check of whether the node exists at all.

**Parameters**

- node_id – a node identifier

**Returns**

1 if the node identifier refers to a node, 0 otherwise.

**DT_NODE_HAS_STATUS**(node_id, status)

Does a node identifier refer to a node with a status?

Example uses:

```plaintext
DT_NODE_HAS_STATUS(DT_PATH(soc, i2c_12340000), okay)
DT_NODE_HAS_STATUS(DT_PATH(soc, i2c_12340000), disabled)
```

Tests whether a node identifier refers to a node which:

- exists in the devicetree, and
- has a status property matching the second argument (except that either a missing status or an ok status in the devicetree is treated as if it were okay instead)

**Parameters**

- node_id – a node identifier
- status – a status as one of the tokens okay or disabled, not a string

**Returns**

1 if the node has the given status, 0 otherwise.

**DT_HAS_COMPAT_STATUS_OKAY**(compat)

Does the devicetree have a status okay node with a compatible?

Test for whether the devicetree has any nodes with status okay and the given compatible. That is, this returns 1 if and only if there is at least one node_id for which both of these expressions return 1:

```plaintext
DT_NODE_HAS_STATUS(node_id, okay)
DT_NODE_HAS_COMPAT(node_id, compat)
```

As usual, both a missing status and an ok status are treated as okay.
Parameters

- `compat` – lowercase-and-underscores compatible, without quotes

Returns

1 if both of the above conditions are met, 0 otherwise

`DT_NUM_INST_STATUS_OKAY(compat)`

Get the number of instances of a given compatible with status okay

Parameters

- `compat` – lowercase-and-underscores compatible, without quotes

Returns

Number of instances with status okay

`DT_NODE_HAS_COMPAT(node_id, compat)`

Does a devicetree node match a compatible?

Example devicetree fragment:

```
node {
  compatible = "vnd,specific-device", "generic-device";
}
```

Example usages which evaluate to 1:

```
DT_NODE_HAS_COMPAT(DT_NODELABEL(n), vnd_specific_device)
DT_NODE_HAS_COMPAT(DT_NODELABEL(n), generic_device)
```

This macro only uses the value of the compatible property. Whether or not a particular compatible has a matching binding has no effect on its value, nor does the node's status.

Parameters

- `node_id` – node identifier
- `compat` – lowercase-and-underscores compatible, without quotes

Returns

1 if the node's compatible property contains `compat`, 0 otherwise.

`DT_NODE_HAS_COMPAT_STATUS(node_id, compat, status)`

Does a devicetree node have a compatible and status?

This is equivalent to:

```
(DT_NODE_HAS_COMPAT(node_id, compat) &&
 DT_NODE_HAS_STATUS(node_id, status))
```

Parameters

- `node_id` – node identifier
- `compat` – lowercase-and-underscores compatible, without quotes
- `status` – okay or disabled as a token, not a string

`DT_NODE_HAS_PROP(node_id, prop)`

Does a devicetree node have a property?

Tests whether a devicetree node has a property defined.

This tests whether the property is defined at all, not whether a boolean property is true or false. To get a boolean property's truth value, use `DT_PROP(node_id, prop)` instead.

Parameters
• `node_id` – node identifier
• `prop` – lowercase-and-underscores property name

**Returns**
1 if the node has the property, 0 otherwise.

`DT_PHA_HAS_CELL_AT_IDX(node_id, pha, idx, cell)`

Does a phandle array have a named cell specifier at an index?

If this returns 1, then the phandle-array property `pha` has a cell named `cell` at index `idx`, and therefore `DT_PHA_BY_IDX(node_id, pha, idx, cell)` is valid. If it returns 0, it’s an error to use `DT_PHA_BY_IDX()` with the same arguments.

**Parameters**
• `node_id` – node identifier
• `pha` – lowercase-and-underscores property with type `phandle-array`
• `idx` – index to check within `pha`
• `cell` – lowercase-and-underscores cell name whose existence to check at index `idx`

**Returns**
1 if the named cell exists in the specifier at index `idx`, 0 otherwise.

`DT_PHA_HAS_CELL(node_id, pha, cell)`

Equivalent to `DT_PHA_HAS_CELL_AT_IDX(node_id, pha, 0, cell)`

**Parameters**
• `node_id` – node identifier
• `pha` – lowercase-and-underscores property with type `phandle-array`
• `cell` – lowercase-and-underscores cell name whose existence to check at index `idx`

**Returns**
1 if the named cell exists in the specifier at index 0, 0 otherwise.

**Inter-node dependencies**
The devicetree.h API has some support for tracking dependencies between nodes. Dependency tracking relies on a binary “depends on” relation between devicetree nodes, which is defined as the [transitive closure](#) of the following “directly depends on” relation:

• every non-root node directly depends on its parent node
• a node directly depends on any nodes its properties refer to by phandle
• a node directly depends on its `interrupt-parent` if it has an `interrupts` property
• a parent node inherits all dependencies from its child nodes

A [dependency ordering](#) of a devicetree is a list of its nodes, where each node `n` appears earlier in the list than any nodes that depend on `n`. A node’s [dependency ordinal](#) is then its zero-based index in that list. Thus, for two distinct devicetree nodes `n1` and `n2` with dependency ordinals `d1` and `d2`, we have:

• `d1` != `d2`
• if `n1` depends on `n2`, then `d1` > `d2`
• `d1` > `d2` does **not** necessarily imply that `n1` depends on `n2`
The Zephyr build system chooses a dependency ordering of the final devicetree and assigns a dependency ordinal to each node. Dependency related information can be accessed using the following macros. The exact dependency ordering chosen is an implementation detail, but cyclic dependencies are detected and cause errors, so it's safe to assume there are none when using these macros.

There are instance number-based conveniences as well; see \texttt{DT_INST_DEP_ORD()} and subsequent documentation.

\begin{description}
\item[group devicetree-dep-ord]
\item[Defines]
\begin{description}
\item[DT_DEP_ORD(node_id)]
Get a node's dependency ordinal.
\begin{description}
\item[Parameters]
\begin{itemize}
\item node_id \textendash{} Node identifier
\end{itemize}
\item[Returns]
the node's dependency ordinal as an integer literal
\end{description}
\item[DT_DEP_ORD_STR_SORTABLE(node_id)]
Get a node's dependency ordinal in string sortable form.
\begin{description}
\item[Parameters]
\begin{itemize}
\item node_id \textendash{} Node identifier
\end{itemize}
\item[Returns]
the node's dependency ordinal as a zero-padded integer literal
\end{description}
\item[DT_REQUIRES_DEP_ORDS(node_id)]
Get a list of dependency ordinals of a node's direct dependencies.
There is a comma after each ordinal in the expansion, including the last one:
\begin{verbatim}
DT_REQUIRES_DEP_ORDS(my_node) // required_ord_1, ..., required_ord_n,
\end{verbatim}
The one case \texttt{DT_REQUIRES_DEP_ORDS()} expands to nothing is when given the root node identifier \texttt{DT_ROOT} as argument. The root has no direct dependencies; every other node at least depends on its parent.
\begin{description}
\item[Parameters]
\begin{itemize}
\item node_id \textendash{} Node identifier
\end{itemize}
\item[Returns]
a list of dependency ordinals, with each ordinal followed by a comma (,),
or an empty expansion
\end{description}
\item[DT_SUPPORTS_DEP_ORDS(node_id)]
Get a list of dependency ordinals of what depends directly on a node.
There is a comma after each ordinal in the expansion, including the last one:
\begin{verbatim}
DT_SUPPORTS_DEP_ORDS(my_node) // supported_ord_1, ..., supported_ord_n,
\end{verbatim}
\texttt{DT_SUPPORTS_DEP_ORDS()} may expand to nothing. This happens when \texttt{node_id} refers to a leaf node that nothing else depends on.
\begin{description}
\item[Parameters]
\begin{itemize}
\item node_id \textendash{} Node identifier
\end{itemize}
\end{description}
\end{description}
\end{description}
\end{verbatim}
Returns
a list of dependency ordinals, with each ordinal followed by a comma (,), or an empty expansion

DT_INST_DEP_ORD(inst)
Get a DT_DRV_COMPAT instance's dependency ordinal.
Equivalent to DT_DEP_ORD(DT_DRV_INST(inst)).

Parameters
• inst – instance number

Returns
The instance's dependency ordinal

DT_INST_REQUIRES_DEP_ORDS(inst)
Get a list of dependency ordinals of a DT_DRV_COMPAT instance's direct dependencies.
Equivalent to DT_REQUIRES_DEP_ORDS(DT_DRV_INST(inst)).

Parameters
• inst – instance number

Returns
a list of dependency ordinals for the nodes the instance depends on directly

DT_INST_SUPPORTS_DEP_ORDS(inst)
Get a list of dependency ordinals of what depends directly on a DT_DRV_COMPAT instance.
Equivalent to DT_SUPPORTS_DEP_ORDS(DT_DRV_INST(inst)).

Parameters
• inst – instance number

Returns
a list of node identifiers for the nodes that depend directly on the instance

Bus helpers  Zephyr's devicetree bindings language supports a bus: key which allows bindings to declare that nodes with a given compatible describe system buses. In this case, child nodes are considered to be on a bus of the given type, and the following APIs may be used.

**group devicetree-generic-bus**

**Defines**

DT_BUS(node_id)
Node's bus controller.
Get the node identifier of the node's bus controller. This can be used with DT_PROP() to get properties of the bus controller.
It is an error to use this with nodes which do not have bus controllers.

Example devicetree fragment:

```c
i2c@deadbeef {
  status = "okay";
  clock-frequency = < 100000 >;
}
```
Example usage:

```c
DT_PROP(DT_BUS(DT_NODELABEL(i2c_device)), clock_frequency) // 100000
```

**Parameters**
- **node_id** – node identifier

**Returns**
a node identifier for the node's bus controller

```c
DT_ON_BUS(node_id, bus)
```

Is a node on a bus of a given type?

Example devicetree overlay:

```c
&i2c0 {
    temp: temperature-sensor@76 {
        compatible = "vnd,some-sensor";
        reg = <0x76>;
    };
};
```

Example usage, assuming i2c0 is an I2C bus controller node, and therefore temp is on an I2C bus:

```c
DT_ON_BUS(DT_NODELABEL(temp), i2c) // 1
DT_ON_BUS(DT_NODELABEL(temp), spi) // 0
```

**Parameters**
- **node_id** – node identifier
- **bus** – lowercase-and-underscores bus type as a C token (i.e. without quotes)

**Returns**
1 if the node is on a bus of the given type, 0 otherwise

**Instance-based APIs** These are recommended for use within device drivers. To use them, define DT_DRV_COMPAT to the lowercase-and-underscores compatible the device driver implements support for. Here is an example devicetree fragment:

```c
serial@40001000 {
    compatible = "vnd,serial";
    status = "okay";
    current-speed = <115200>;
};
```

Example usage, assuming serial@40001000 is the only enabled node with compatible vnd, serial:

```c
#define DT_DRV_COMPAT vnd_serial
DT_DRV_INST(0) // node identifier for serial@40001000
DT_INST_PROP(0, current_speed) // 115200
```
Warning: Be careful making assumptions about instance numbers. See \texttt{DT_INST()} for the API guarantees.

As shown above, the \texttt{DT_INST_*} APIs are conveniences for addressing nodes by instance number. They are almost all defined in terms of one of the \textit{Generic APIs}. The equivalent generic API can be found by removing \texttt{INST} from the macro name. For example, \texttt{DT_INST_PROP(inst, prop)} is equivalent to \texttt{DT_PROP(DT_DRV_INST(inst), prop)}. Similarly, \texttt{DT_INST_REG_ADDR(inst)} is equivalent to \texttt{DT_REG_ADDR(DT_DRV_INST(inst))}, and so on. There are some exceptions: \texttt{DT_ANY_INST_ON_BUS_STATUS_OKAY()} and \texttt{DT_INST_FOREACH_STATUS_OKAY()} are special-purpose helpers without straightforward generic equivalents.

Since \texttt{DT_DRV_INST()} requires \texttt{DT_DRV_COMPAT} to be defined, it’s an error to use any of these without that macro defined.

Note that there are also helpers available for specific hardware; these are documented in \textit{Hardware specific APIs}.

\textit{group devicetree-inst}

\textbf{Defines}

\texttt{DT_DRV_INST(inst)}

Node identifier for an instance of a \texttt{DT_DRV_COMPAT compatible}.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} -- instance number
\end{itemize}

\textbf{Returns}

a node identifier for the node with \texttt{DT_DRV_COMPAT compatible} and instance number \texttt{inst}

\texttt{DT_INST_PARENT(inst)}

Get a \texttt{DT_DRV_COMPAT parent’s node identifier}.

\textbf{See also:}

\texttt{DT_PARENT}

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} -- instance number
\end{itemize}

\textbf{Returns}

a node identifier for the instance’s parent

\texttt{DT_INST_GPARENT(inst)}

Get a \texttt{DT_DRV_COMPAT grandparent’s node identifier}.

\textbf{See also:}

\texttt{DT_GPARENT}

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} -- instance number
\end{itemize}
Returns
a node identifier for the instance's grandparent

\texttt{DT_INST\_CHILD}(inst, child)

Get a node identifier for a child node of \texttt{DT\_DRV\_INST(inst)}

\textbf{See also:}
\texttt{DT\_CHILD}

\textbf{Parameters}

- \texttt{inst} – instance number
- \texttt{child} – lowercase-and-underscores child node name

\textbf{Returns}
node identifier for the node with the name referred to by 'child'

\texttt{DT\_INST\_FOREACH\_CHILD}(inst, fn)

Call \texttt{fn} on all child nodes of \texttt{DT\_DRV\_INST(inst)}.

The macro \texttt{fn} should take one argument, which is the node identifier for the child node.

The children will be iterated over in the same order as they appear in the final device-tree.

\textbf{See also:}
\texttt{DT\_FOREACH\_CHILD}

\textbf{Parameters}

- \texttt{inst} – instance number
- \texttt{fn} – macro to invoke on each child node identifier

\texttt{DT\_INST\_FOREACH\_CHILD\_SEP}(inst, fn, sep)

Call \texttt{fn} on all child nodes of \texttt{DT\_DRV\_INST(inst)} with a separator.

The macro \texttt{fn} should take one argument, which is the node identifier for the child node.

\textbf{See also:}
\texttt{DT\_FOREACH\_CHILD\_SEP}

\textbf{Parameters}

- \texttt{inst} – instance number
- \texttt{fn} – macro to invoke on each child node identifier
- \texttt{sep} – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

\texttt{DT\_INST\_FOREACH\_CHILD\_VARGS}(inst, fn, ...)

Call \texttt{fn} on all child nodes of \texttt{DT\_DRV\_INST(inst)}.

The macro \texttt{fn} takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.
The children will be iterated over in the same order as they appear in the final device-tree.

See also:

\texttt{DT_FOREACH_CHILD}

Parameters

- \texttt{inst} – instance number
- \texttt{fn} – macro to invoke on each child node identifier
- \ldots – variable number of arguments to pass to \texttt{fn}

\texttt{DT_INST_FOREACH_CHILD_SEP_VARGS(\ldots)}

Call \texttt{fn} on all child nodes of \texttt{DT_DRV_INST(inst)} with separator.

The macro \texttt{fn} takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

See also:

\texttt{DT_FOREACH_CHILD_SEP_VARGS}

Parameters

- \texttt{inst} – instance number
- \texttt{fn} – macro to invoke on each child node identifier
- \texttt{sep} – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- \ldots – variable number of arguments to pass to \texttt{fn}

\texttt{DT_INST_FOREACH_CHILD_STATUS_OKAY(\ldots)}

Call \texttt{fn} on all child nodes of \texttt{DT_DRV_INST(inst)} with status okay.

The macro \texttt{fn} should take one argument, which is the node identifier for the child node.

See also:

\texttt{DT_FOREACH_CHILD_STATUS_OKAY}

Parameters

- \texttt{inst} – instance number
- \texttt{fn} – macro to invoke on each child node identifier

\texttt{DT_INST_FOREACH_CHILD_STATUS_OKAY_SEP(\ldots)}

Call \texttt{fn} on all child nodes of \texttt{DT_DRV_INST(inst)} with status okay and with separator.

The macro \texttt{fn} should take one argument, which is the node identifier for the child node.

See also:

\texttt{DT_FOREACH_CHILD_STATUS_OKAY_SEP}
• *inst* – instance number
• *fn* – macro to invoke on each child node identifier
• *sep* – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

`DT_INST_FOREACH_CHILD_STATUS_OKAY_VARGS(inst, fn, ...)`

Call *fn* on all child nodes of `DT_DRV_INST(inst)` with status okay and multiple arguments.

The macro *fn* takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

**See also:**

`DT_FOREACH_CHILD_STATUS_OKAY_VARGS`

**Parameters**

• *inst* – instance number
• *fn* – macro to invoke on each child node identifier
• ... – variable number of arguments to pass to *fn*

`DT_INST_FOREACH_CHILD_STATUS_OKAY_SEP_VARGS(inst, fn, sep, ...)`

Call *fn* on all child nodes of `DT_DRV_INST(inst)` with status okay and with separator and multiple arguments.

The macro *fn* takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

**See also:**

`DT_FOREACH_CHILD_STATUS_OKAY_SEP_VARGS`

**Parameters**

• *inst* – instance number
• *fn* – macro to invoke on each child node identifier
• *sep* – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
• ... – variable number of arguments to pass to *fn*

`DT_INST_ENUM_IDX(inst, prop)`

Get a `DT_DRV_COMPAT` value's index into its enumeration values.

**Parameters**

• *inst* – instance number
• *prop* – lowercase-and-underscores property name

**Returns**

zero-based index of the property's value in its enum: list

`DT_INST_ENUM_IDX_OR(inst, prop, default_idx_value)`

Like `DT_INST_ENUM_IDX()`, but with a fallback to a default enum index.

**Parameters**
• inst – instance number
• prop – lowercase-and-underscores property name
• default_idx_value – a fallback index value to expand to

Returns
zero-based index of the property's value in its enum if present, default_idx_value otherwise

DT_INST_ENUM_HAS_VALUE(inst, prop, value)
Does a DT_DRV_COMPAT enumeration property have a given value?

Parameters
• inst – instance number
• prop – lowercase-and-underscores property name
• value – lowercase-and-underscores enumeration value

Returns
1 if the node property has the value value, 0 otherwise.

DT_INST_PROP(inst, prop)
Get a DT_DRV_COMPAT instance property.

Parameters
• inst – instance number
• prop – lowercase-and-underscores property name

Returns
a representation of the property's value

DT_INST_PROP_LEN(inst, prop)
Get a DT_DRV_COMPAT property length.

Parameters
• inst – instance number
• prop – lowercase-and-underscores property name

Returns
logical length of the property

DT_INST_PROP_HAS_IDX(inst, prop, idx)
Is index idx valid for an array type property on a DT_DRV_COMPAT instance?

Parameters
• inst – instance number
• prop – lowercase-and-underscores property name
• idx – index to check

Returns
1 if idx is a valid index into the given property, 0 otherwise.

DT_INST_PROP_HAS_NAME(inst, prop, name)
Is name name available in a foo-names property?

Parameters
• inst – instance number
• prop – a lowercase-and-underscores prop-names type property
• name – a lowercase-and-underscores name to check
Returns
An expression which evaluates to 1 if name is an available name into the given property, and 0 otherwise.

\texttt{DT_INST_PROP\_BY\_IDX}(\textit{inst}, \textit{prop}, \textit{idx})
Get a DT\_DRV\_COMPAT element value in an array property.

Parameters
\begin{itemize}
\item \textit{inst} – instance number
\item \textit{prop} – lowercase-and-underscores property name
\item \textit{idx} – the index to get
\end{itemize}

Returns
a representation of the idx-th element of the property

\texttt{DT_INST_PROP\_OR}(\textit{inst}, \textit{prop}, \textit{default\_value})
Like \texttt{DT\_INST\_PROP()}, but with a fallback to default_value.

Parameters
\begin{itemize}
\item \textit{inst} – instance number
\item \textit{prop} – lowercase-and-underscores property name
\item \textit{default\_value} – a fallback value to expand to
\end{itemize}

Returns
\texttt{DT\_INST\_PROP(}\textit{inst}, \textit{prop}) or \textit{default\_value}

\texttt{DT\_INST\_PROP\_LEN\_OR}(\textit{inst}, \textit{prop}, \textit{default\_value})
Like \texttt{DT\_INST\_PROP\_LEN()}, but with a fallback to default_value.

Parameters
\begin{itemize}
\item \textit{inst} – instance number
\item \textit{prop} – lowercase-and-underscores property name
\item \textit{default\_value} – a fallback value to expand to
\end{itemize}

Returns
\texttt{DT\_INST\_PROP\_LEN(}\textit{inst}, \textit{prop}) or \textit{default\_value}

\texttt{DT\_INST\_STRING\_TOKEN}(\textit{inst}, \textit{prop})
Get a DT\_DRV\_COMPAT instance's string property's value as a token.

Parameters
\begin{itemize}
\item \textit{inst} – instance number
\item \textit{prop} – lowercase-and-underscores property name
\end{itemize}

Returns
the value of \textit{prop} as a token, i.e. without any quotes and with special characters converted to underscores

\texttt{DT\_INST\_STRING\_UPPER\_TOKEN}(\textit{inst}, \textit{prop})
Like \texttt{DT\_INST\_STRING\_TOKEN()}, but uppercased.

Parameters
\begin{itemize}
\item \textit{inst} – instance number
\item \textit{prop} – lowercase-and-underscores property name
\end{itemize}

Returns
the value of \textit{prop} as an uppercased token, i.e. without any quotes and with special characters converted to underscores
**DT_INST_STRING_UNQUOTED**(inst, prop)
Get a DT_DRV_COMPAT instance's string property's value as an unquoted sequence of tokens.

**Parameters**
- inst – instance number
- prop – lowercase-and-underscores property name

**Returns**
the value of prop as a sequence of tokens, with no quotes

**DT_INST_STRING_TOKEN_BY_IDX**(inst, prop, idx)
Get an element out of string-array property as a token.

**Parameters**
- inst – instance number
- prop – lowercase-and-underscores property name
- idx – the index to get

**Returns**
the element in prop at index idx as a token

**DT_INST_STRING_UPPER_TOKEN_BY_IDX**(inst, prop, idx)
Like **DT_INST_STRING_TOKEN_BY_IDX()**, but uppercased.

**Parameters**
- inst – instance number
- prop – lowercase-and-underscores property name
- idx – the index to get

**Returns**
the element in prop at index idx as an uppercased token

**DT_INST_STRING_UNQUOTED_BY_IDX**(inst, prop, idx)
Get an element out of string-array property as an unquoted sequence of tokens.

**Parameters**
- inst – instance number
- prop – lowercase-and-underscores property name
- idx – the index to get

**Returns**
the value of prop at index idx as a sequence of tokens, with no quotes

**DT_INST_PROP_BY_PHANDLE**(inst, ph, prop)
Get a DT_DRV_COMPAT instance's property value from a phandle's node.

**Parameters**
- inst – instance number
- ph – lowercase-and-underscores property of inst with type phandle
- prop – lowercase-and-underscores property of the phandle's node

**Returns**
the value of prop as described in the **DT_PROP()** documentation
DT_INST_PROP_BY_PHANDLE_IDX(inst, phs, idx, prop)
Get a DT_DRV_COMPAT instance's property value from a phandle in a property.

**Parameters**
- inst – instance number
- phs – lowercase-and-underscores property with type phandle, phandles, or phandle-array
- idx – logical index into “phs”, which must be zero if “phs” has type phandle
- prop – lowercase-and-underscores property of the phandle's node

**Returns**
the value of prop as described in the DT_PROP() documentation

DT_INST_PHA_BY_IDX(inst, pha, idx, cell)
Get a DT_DRV_COMPAT instance's phandle-array specifier value at an index.

**Parameters**
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- idx – logical index into the property pha
- cell – binding’s cell name within the specifier at index idx

**Returns**
the value of the cell inside the specifier at index idx

DT_INST_PHA_BY_IDX_OR(inst, pha, idx, cell, default_value)
Like DT_INST_PHA_BY_IDX(), but with a fallback to default_value.

**Parameters**
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- idx – logical index into the property pha
- cell – binding's cell name within the specifier at index idx
- default_value – a fallback value to expand to

**Returns**
DT_INST_PHA_BY_IDX(inst, pha, idx, cell) or default_value

DT_INST_PHA(inst, pha, cell)
Get a DT_DRV_COMPAT instance's phandle-array specifier value Equivalent to

**Parameters**
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- cell – binding's cell name for the specifier at pha index 0

**Returns**
the cell value

DT_INST_PHA_OR(inst, pha, cell, default_value)
Like DT_INST_PHA(), but with a fallback to default_value.

**Parameters**
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- \textit{inst} – instance number
- \textit{pha} – lowercase-and-underscores property with type \texttt{phandle-array}
- \textit{cell} – binding's cell name for the specifier at \textit{pha} index 0
- \textit{default_value} – a fallback value to expand to

Returns\n\texttt{DT_INST_PHA(inst, pha, cell)} or default_value

\texttt{DT_INST_PHA_BY_NAME}(inst, pha, name, cell)
Get a DT_DRV_COMPAT instance's value within a phandle-array specifier by name.

Parameters
- \textit{inst} – instance number
- \textit{pha} – lowercase-and-underscores property with type \texttt{phandle-array}
- \textit{name} – lowercase-and-underscores name of a specifier in \textit{pha}
- \textit{cell} – binding's cell name for the named specifier

Returns the cell value

\texttt{DT_INST_PHA_BY_NAME_OR}(inst, pha, name, cell, default_value)
Like \texttt{DT_INST_PHA_BY_NAME()}, but with a fallback to default_value.

Parameters
- \textit{inst} – instance number
- \textit{pha} – lowercase-and-underscores property with type \texttt{phandle-array}
- \textit{name} – lowercase-and-underscores name of a specifier in \textit{pha}
- \textit{cell} – binding's cell name for the named specifier
- \textit{default_value} – a fallback value to expand to

Returns \texttt{DT_INST_PHA_BY_NAME(inst, pha, name, cell)} or default_value

\texttt{DT_INST_PHANDLE_BY_NAME}(inst, pha, name)
Get a DT_DRV_COMPAT instance's phandle node identifier from a phandle array by name.

Parameters
- \textit{inst} – instance number
- \textit{pha} – lowercase-and-underscores property with type \texttt{phandle-array}
- \textit{name} – lowercase-and-underscores name of an element in \textit{pha}

Returns node identifier for the phandle at the element named “name”

\texttt{DT_INST_PHANDLE_BY_IDX}(inst, prop, idx)
Get a DT_DRV_COMPAT instance's node identifier for a phandle in a property.

Parameters
- \textit{inst} – instance number
- \textit{prop} – lowercase-and-underscores property name in \textit{inst} with type \texttt{phandle, phandles or phandle-array}
- \textit{idx} – index into \textit{prop}

Returns a node identifier for the phandle at index \textit{idx} in \textit{prop}
DT_INST_PHANDLE(inst, prop)
Get a DT_DRV_COMPAT instance's node identifier for a phandle property's value.

Parameters
• inst – instance number
• prop – lowercase-and-underscores property of inst with type phandle

Returns
a node identifier for the node pointed to by “ph”

DT_INST_REG_HAS_IDX(inst, idx)
is idx a valid register block index on a DT_DRV_COMPAT instance?

Parameters
• inst – instance number
• idx – index to check

Returns
1 if idx is a valid register block index, 0 otherwise.

DT_INST_REG_ADDR_BY_IDX(inst, idx)
Get a DT_DRV_COMPAT instance's idx-th register block's address.

Parameters
• inst – instance number
• idx – index of the register whose address to return

Returns
address of the instance's idx-th register block

DT_INST_REG_SIZE_BY_IDX(inst, idx)
Get a DT_DRV_COMPAT instance's idx-th register block's size.

Parameters
• inst – instance number
• idx – index of the register whose size to return

Returns
size of the instance's idx-th register block

DT_INST_REG_ADDR_BY_NAME(inst, name)
Get a DT_DRV_COMPAT's register block address by name.

Parameters
• inst – instance number
• name – lowercase-and-underscores register specifier name

Returns
address of the register block with the given name

DT_INST_REG_ADDR_BY_NAME_U64(inst, name)
64-bit version of DT_INST_REG_ADDR_BY_NAME()
This macro version adds the appropriate suffix for 64-bit unsigned integer literals.
Note that this macro is equivalent to DT_INST_REG_ADDR_BY_NAME() in linker/ASM context.

Parameters
• inst – instance number
DT INST_REG_SIZE_BY_NAME(inst, name)
Get a DT_DRV_COMPAT's register block size by name.

Parameters
- inst – instance number
- name – lowercase-and-underscores register specifier name

Returns
size of the register block with the given name

DT INST_REG_ADDR(inst)
Get a DT_DRV_COMPAT's (only) register block address.

Parameters
- inst – instance number

Returns
instance's register block address

DT INST_REG_ADDR_U64(inst)
64-bit version of DT INST_REG_ADDR()
This macro version adds the appropriate suffix for 64-bit unsigned integer literals.
Note that this macro is equivalent to DT INST_REG_ADDR() in linker/ASM context.

Parameters
- inst – instance number

Returns
instance's register block address

DT INST_REG_SIZE(inst)
Get a DT_DRV_COMPAT's (only) register block size.

Parameters
- inst – instance number

Returns
instance's register block size

DT INST_IRQ_LEVEL(inst)
Get a DT_DRV_COMPAT interrupt level.

Parameters
- inst – instance number

Returns
interrupt level

DT INST_IRQ_BY_IDX(inst, idx, cell)
Get a DT_DRV_COMPAT interrupt specifier value at an index.

Parameters
- inst – instance number
- idx – logical index into the interrupt specifier array
- cell – cell name specifier
Returns
the named value at the specifier given by the index

```
DT_INST_IRQ_INTC_BY_IDX(inst, idx)
```
Get a DT_DRV_COMPAT interrupt specifier's interrupt controller by index.

**Parameters**
- inst – instance number
- idx – interrupt specifier’s index

**Returns**
node_id of interrupt specifier's interrupt controller

```
DT_INST_IRQ_INTC_BY_NAME(inst, name)
```
Get a DT_DRV_COMPAT interrupt specifier's interrupt controller by name.

**Parameters**
- inst – instance number
- name – interrupt specifier's name

**Returns**
node_id of interrupt specifier's interrupt controller

```
DT_INST_IRQ_INTC(inst)
```
Get a DT_DRV_COMPAT interrupt specifier's interrupt controller.

See also:
```
DT_INST_IRQ_INTC_BY_IDX()
```

**Note:** Equivalent to `DT_INST_IRQ_INTC_BY_IDX(node_id, 0)`

```
DT_INST_IRQ_BY_NAME(inst, name, cell)
```
Get a DT_DRV_COMPAT interrupt specifier value by name.

**Parameters**
- inst – instance number
- name – lowercase-and-underscores interrupt specifier name
- cell – cell name specifier

**Returns**
the named value at the specifier given by the index

```
DT_INST_IRQ(inst, cell)
```
Get a DT_DRV_COMPAT interrupt specifier's value.

**Parameters**
- inst – instance number
- cell – cell name specifier
Returns
the named value at that index

DT_INST_IRQN(inst)
Get a DT_DRV_COMPAT’s (only) irq number.

Parameters
• inst – instance number

Returns
the interrupt number for the node’s only interrupt

DT_INST_IRQN_BY_IDX(inst, idx)
Get a DT_DRV_COMPAT’s irq number at index.

Parameters
• inst – instance number
• idx – logical index into the interrupt specifier array

Returns
the interrupt number for the node’s idx-th interrupt

DT_INST_BUS(inst)
Get a DT_DRV_COMPAT’s bus node identifier.

Parameters
• inst – instance number

Returns
node identifier for the instance’s bus node

DT_INST_ON_BUS(inst, bus)
Test if a DT_DRV_COMPAT’s bus type is a given type.

Parameters
• inst – instance number
• bus – a binding’s bus type as a C token, lowercased and without quotes

Returns
1 if the given instance is on a bus of the given type, 0 otherwise

DT_INST_STRING_TOKEN_OR(inst, name, default_value)
Like DT_INST_STRING_TOKEN(), but with a fallback to default_value.

Parameters
• inst – instance number
• name – lowercase-and-underscores property name
• default_value – a fallback value to expand to

Returns
if prop exists, its value as a token, i.e. without any quotes and with special characters converted to underscores. Otherwise default_value

DT_INST_STRING_UPPER_TOKEN_OR(inst, name, default_value)
Like DT_INST_STRING_UPPER_TOKEN(), but with a fallback to default_value.

Parameters
• inst – instance number
• name – lowercase-and-underscores property name
• default_value – a fallback value to expand to

**Returns**
the property's value as an uppercased token, or default_value

**DT_INST_STRING_UNQUOTED_OR**(inst, name, default_value)
Like **DT_INST_STRING_UNQUOTED()**, but with a fallback to default_value.

**Parameters**
• inst – instance number
• name – lowercase-and-underscores property name
• default_value – a fallback value to expand to

**Returns**
the property’s value as a sequence of tokens, with no quotes, or default_value

**DT_HAS_COMPAT_ON_BUS_STATUS_OKAY**(compat, bus)

**DT_ANY_INST_ON_BUS_STATUS_OKAY**(bus)
Test if any DT_DRV_COMPAT node is on a bus of a given type and has status okay.
This is a special-purpose macro which can be useful when writing drivers for devices which can appear on multiple buses. One example is a sensor device which may be wired on an I2C or SPI bus.

Example devicetree overlay:

```plaintext
&i2c0 {
  temp: temperature-sensor@76 {
    compatible = "vnd,some-sensor";
    reg = <0x76>;
  };
};
```

Example usage, assuming i2c0 is an I2C bus controller node, and therefore temp is on an I2C bus:

```plaintext
#define DT_DRV_COMPAT vnd_some_sensor
DT_ANY_INST_ON_BUS_STATUS_OKAY(i2c) // 1
```

**Parameters**
• bus – a binding’s bus type as a C token, lowercased and without quotes

**Returns**
1 if any enabled node with that compatible is on that bus type, 0 otherwise

**DT_ANY_INST_HAS_PROP_STATUS_OKAY**(prop)
Check if any DT_DRV_COMPAT node with status okay has a given property.

Example devicetree overlay:

```plaintext
&i2c0 {
  sensor0: sensor@0 {
    compatible = "vnd,some-sensor";
    status = "okay";
    reg = <0>;
    foo = <1>;
  };
};
```

(continues on next page)
bar = <2>;
};

sensor1: sensor@1 {
    compatible = "vnd,some-sensor";
    status = "okay";
    reg = <1>;
    foo = <2>;
};

sensor2: sensor@2 {
    compatible = "vnd,some-sensor";
    status = "disabled";
    reg = <2>;
    baz = <1>;
};

Example usage:

```c
#define DT_DRV_COMPAT vnd_some_sensor

DT_ANY_INST_HAS_PROP_STATUS_OKAY(foo) // 1
DT_ANY_INST_HAS_PROP_STATUS_OKAY(bar) // 1
DT_ANY_INST_HAS_PROP_STATUS_OKAY(baz) // 0
```

Parameters

- prop – lowercase-and-underscores property name

**DT_INST_FOREACH_STATUS_OKAY(fn)**

Call fn on all nodes with compatible DT_DRV_COMPAT and status okay

This macro calls fn(inst) on each inst number that refers to a node with status okay. Whitespace is added between invocations.

Example devicetree fragment:

```devicetree
a {
    compatible = "vnd,device";
    status = "okay";
    foobar = "DEV_A";
};

b {
    compatible = "vnd,device";
    status = "okay";
    foobar = "DEV_B";
};

c {
    compatible = "vnd,device";
    status = "disabled";
    foobar = "DEV_C";
};
```

Example usage:

```c
#define DT_DRV_COMPAT vnd_device
#define MY_FN(inst) DT_INST_PROP(inst, foobar),

DT_INST_FOREACH_STATUS_OKAY(MY_FN)
```
This expands to:

\[\text{MY\_FN(0)} \quad \text{MY\_FN(1)}\]

and from there, to either this:

\["\text{DEV\_A}, \text{DEV\_B},"\]

or this:

\["\text{DEV\_B}, \text{DEV\_A},"\]

No guarantees are made about the order that a and b appear in the expansion.

Note that \text{fn} is responsible for adding commas, semicolons, or other separators or terminators.

Device drivers should use this macro whenever possible to instantiate a struct device for each enabled node in the devicetree of the driver's compatible \text{DT\_DRV\_COMPAT}.

### Parameters

- \text{fn} – Macro to call for each enabled node. Must accept an instance number as its only parameter.

\text{DT\_INST\_FOREACH\_STATUS\_OKAY\_VARGS}(\text{fn}, \ldots)

Call \text{fn} on all nodes with compatible \text{DT\_DRV\_COMPAT} and status okay with multiple arguments.

### See also:

\text{DT\_INST\_FOREACH\_STATUS\_OKAY}

### Parameters

- \text{fn} – Macro to call for each enabled node. Must accept an instance number as its only parameter.
- \ldots – variable number of arguments to pass to \text{fn}

\text{DT\_INST\_FOREACH\_PROP\_ELEM}(\text{inst}, \text{prop}, \text{fn})

Invokes \text{fn} for each element of property \text{prop} for a \text{DT\_DRV\_COMPAT} instance.

Equivalent to \text{DT\_FOREACH\_PROP\_ELEM}(\text{DT\_DRV\_INST(\text{inst})}, \text{prop}, \text{fn}).

### Parameters

- \text{inst} – instance number
- \text{prop} – lowercase-and-underscores property name
- \text{fn} – macro to invoke

\text{DT\_INST\_FOREACH\_PROP\_ELEM\_SEP}(\text{inst}, \text{prop}, \text{fn}, \text{sep})

Invokes \text{fn} for each element of property \text{prop} for a \text{DT\_DRV\_COMPAT} instance with a separator.

Equivalent to \text{DT\_FOREACH\_PROP\_ELEM\_SEP}(\text{DT\_DRV\_INST(\text{inst})}, \text{prop}, \text{fn}, \text{sep}).

### Parameters

- \text{inst} – instance number
- \text{prop} – lowercase-and-underscores property name
- \text{fn} – macro to invoke
• `sep` – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

`DT_INST_FOREACH_PROP_ELEM_VARGS`(inst, prop, fn, ...)
Invokes `fn` for each element of property `prop` for a `DT_DRV_COMPAT` instance with multiple arguments.

Equivalent to `DT_FOREACH_PROP_ELEM_VARGS(DT_DRV_INST(inst), prop, fn, VA_ARGS)`

See also:
`DT_INST_FOREACH_PROP_ELEM`

Parameters
- `inst` – instance number
- `prop` – lowercase-and-underscores property name
- `fn` – macro to invoke
- `...` – variable number of arguments to pass to `fn`

`DT_INST_FOREACH_PROP_ELEM_SEP_VARGS`(inst, prop, fn, sep, ...)
Invokes `fn` for each element of property `prop` for a `DT_DRV_COMPAT` instance with multiple arguments and a separator.

Equivalent to `DT_FOREACH_PROP_ELEM_SEP_VARGS(DT_DRV_INST(inst), prop, fn, sep, VA_ARGS)`

See also:
`DT_INST_FOREACH_PROP_ELEM`

Parameters
- `inst` – instance number
- `prop` – lowercase-and-underscores property name
- `fn` – macro to invoke
- `sep` – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator:
- `...` – variable number of arguments to pass to `fn`

`DT_INST_NODE_HAS_PROP`(inst, prop)
Does a `DT_DRV_COMPAT` instance have a property?

Parameters
- `inst` – instance number
- `prop` – lowercase-and-underscores property name

Returns
1 if the instance has the property, 0 otherwise.

`DT_INST_PHA_HAS_CELL_AT_IDX`(inst, pha, idx, cell)
Does a phandle array have a named cell specifier at an index for a `DT_DRV_COMPAT` instance?

Parameters
5.2. Devicetree

- `inst` – instance number
- `pha` – lowercase-and-underscores property with type phandle-array
- `idx` – index to check
- `cell` – named cell value whose existence to check

**Returns**
1 if the named cell exists in the specifier at index `idx`, 0 otherwise.

**DT_INST_PHA_HAS_CELL** (`inst`, `pha`, `cell`)
Does a phandle array have a named cell specifier at index 0 for a DT_DRV_COMPAT instance?

**Parameters**
- `inst` – instance number
- `pha` – lowercase-and-underscores property with type phandle-array
- `cell` – named cell value whose existence to check

**Returns**
1 if the named cell exists in the specifier at index 0, 0 otherwise.

**DT_INST_IRQ_HAS_IDX** (`inst`, `idx`)
is index valid for interrupt property on a DT_DRV_COMPAT instance?

**Parameters**
- `inst` – instance number
- `idx` – logical index into the interrupt specifier array

**Returns**
1 if the `idx` is valid for the interrupt property, 0 otherwise.

**DT_INST_IRQ_HAS_CELL_AT_IDX** (`inst`, `idx`, `cell`)
Does a DT_DRV_COMPAT instance have an interrupt named cell specifier?

**Parameters**
- `inst` – instance number
- `idx` – index to check
- `cell` – named cell value whose existence to check

**Returns**
1 if the named cell exists in the interrupt specifier at index 0, 0 otherwise.

**DT_INST_IRQ_HAS_CELL** (`inst`, `cell`)
Does a DT_DRV_COMPAT instance have an interrupt value?

**Parameters**
- `inst` – instance number
- `cell` – named cell value whose existence to check

**Returns**
1 if the named cell exists in the interrupt specifier at index 0, 0 otherwise.

**DT_INST_IRQ_HAS_NAME** (`inst`, `name`)
Does a DT_DRV_COMPAT instance have an interrupt value?

**Parameters**
- `inst` – instance number
- `name` – lowercase-and-underscores interrupt specifier name
Returns

1 if `name` is a valid named specifier

Hardware specific APIs  The following APIs can also be used by including `<devicetree.h>`; no additional include is needed.

CAN  These conveniences may be used for nodes which describe CAN controllers/transceivers, and properties related to them.

group devicetree-can

Defines

`DT_CAN_TRANSCEIVER_MAX_BITRATE(node_id, max)`

Get the maximum transceiver bitrate for a CAN controller.

The bitrate will be limited to the maximum bitrate supported by the CAN controller. If no CAN transceiver is present in the devicetree, the maximum bitrate will be that of the CAN controller.

Example devicetree fragment:

```plaintext
transceiver0: can-phy0 {
    compatible = "vnd,can-transceiver";
    max-bitrate = <1000000>;
    #phy-cells = <0>;
};
can0: can@... {
    compatible = "vnd,can-controller";
    phys = <&transceiver0>;
};
can1: can@... {
    compatible = "vnd,can-controller";
    can-transceiver {
        max-bitrate = <2000000>;
    };
};
```

Example usage:

```plaintext
DT_CAN_TRANSCEIVER_MAX_BITRATE(DT_NODELABEL(can0), 5000000) // 1000000
DT_CAN_TRANSCEIVER_MAX_BITRATE(DT_NODELABEL(can1), 5000000) // 2000000
DT_CAN_TRANSCEIVER_MAX_BITRATE(DT_NODELABEL(can1), 1000000) // 1000000
```

Parameters

- `node_id` – node identifier
- `max` – maximum bitrate supported by the CAN controller

Returns

the maximum bitrate supported by the CAN controller/transceiver combination
**DT_INST_CAN_TRANSCEIVER_MAX_BITRATE**(inst, max)

Get the maximum transceiver bitrate for a DT_DRV_COMPAT CAN controller.

**See also:**

**DT_CAN_TRANSCEIVER_MAX_BITRATE()**

**Parameters**

- inst – DT_DRV_COMPAT instance number
- max – maximum bitrate supported by the CAN controller

**Returns**

the maximum bitrate supported by the CAN controller/transceiver combination

**Clocks**  These conveniences may be used for nodes which describe clock sources, and properties related to them.

group devicetree-clocks

**Defines**

**DT_CLOCKS_HAS_IDX**(node_id, idx)

Test if a node has a clocks phandle-array property at a given index.

This expands to 1 if the given index is valid clocks property phandle-array index. Otherwise, it expands to 0.

Example devicetree fragment:

```plaintext
n1: node-1 {
    clocks = <...>, <...>;
};
n2: node-2 {
    clocks = <...>;
};
```

Example usage:

```plaintext
DT_CLOCKS_HAS_IDX(DT_NODELABEL(n1), 0) // 1
DT_CLOCKS_HAS_IDX(DT_NODELABEL(n1), 1) // 1
DT_CLOCKS_HAS_IDX(DT_NODELABEL(n1), 2) // 0
DT_CLOCKS_HAS_IDX(DT_NODELABEL(n2), 1) // 0
```

**Parameters**

- node_id – node identifier; may or may not have any clocks property
- idx – index of a clocks property phandle-array whose existence to check

**Returns**

1 if the index exists, 0 otherwise
DT_CLOCKS_HAS_NAME(node_id, name)
Test if a node has a clock-names array property holds a given name.
This expands to 1 if the name is available as clocks-name array property cell. Otherwise, it expands to 0.
Example devicetree fragment:

```c
n1: node-1 {
    clocks = <...>, <...>;
    clock-names = "alpha", "beta";
};

n2: node-2 {
    clocks = <...>;
    clock-names = "alpha";
};
```

Example usage:

```
DT_CLOCKS_HAS_NAME(DT_NODELABEL(n1), alpha) // 1
DT_CLOCKS_HAS_NAME(DT_NODELABEL(n1), beta) // 1
DT_CLOCKS_HAS_NAME(DT_NODELABEL(n2), beta) // 0
```

**Parameters**
- node_id – node identifier; may or may not have any clock-names property.
- name – lowercase-and-underscores clock-names cell value name to check

**Returns**
1 if the clock name exists, 0 otherwise

DT_NUM_CLOCKS(node_id)
Get the number of elements in a clocks property.
Example devicetree fragment:

```c
n1: node-1 {
    clocks = &foo, &bar;
};

n2: node-2 {
    clocks = &foo;
};
```

Example usage:

```
DT_NUM_CLOCKS(DT_NODELABEL(n1)) // 2
DT_NUM_CLOCKS(DT_NODELABEL(n2)) // 1
```

**Parameters**
- node_id – node identifier with a clocks property

**Returns**
number of elements in the property

DT_CLOCKS_CTLR_BY_IDX(node_id, idx)
Get the node identifier for the controller phandle from a “clocks” phandle-array property at an index.
Example devicetree fragment:
Zephyr Project Documentation, Release 3.6.0-rc3

```
clk1: clock-controller@... { ... };  
clk2: clock-controller@... { ... };  
n: node {  
    clocks = <&clk1 10 20>, <&clk2 30 40>;  
};
```

Example usage:

```
DT_CLOCKS_CTLR_BY_IDX(DT_NODELABEL(n), 0)) // DT_NODELABEL(clk1)  
DT_CLOCKS_CTLR_BY_IDX(DT_NODELABEL(n), 1)) // DT_NODELABEL(clk2)
```

**See also:**

`DT_PHANDLE_BY_IDX()`

**Parameters**

- `node_id` – node identifier
- `idx` – logical index into “clocks”

**Returns**

the node identifier for the clock controller referenced at index “idx”

`DT_CLOCKS_CTLR(node_id)`

Equivalent to `DT_CLOCKS_CTLR_BY_IDX(node_id, 0)`

**See also:**

`DT_CLOCKS_CTLR_BY_IDX()`

**Parameters**

- `node_id` – node identifier

**Returns**

a node identifier for the clocks controller at index 0 in “clocks”

`DT_CLOCKS_CTLR_BY_NAME(node_id, name)`

Get the node identifier for the controller phandle from a clocks phandle-array property by name.

Example devicetree fragment:

```
clk1: clock-controller@... { ... };  
clk2: clock-controller@... { ... };  
n: node {  
    clocks = <&clk1 10 20>, <&clk2 30 40>;  
    clock-names = "alpha", "beta";  
};
```

Example usage:

```
DT_CLOCKS_CTLR_BY_NAME(DT_NODELABEL(n), beta) // DT_NODELABEL(clk2)
```

**See also:**

`DT_PHANDLE_BY_NAME()`

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Parameters

- `node_id` – node identifier
- `name` – lowercase-and-underscores name of a clocks element as defined by the node's clock-names property

Returns

the node identifier for the clock controller referenced by name

\texttt{DT\_CLOCKS\_CELL\_BY\_IDX}(\texttt{node\_id}, \texttt{idx}, \texttt{cell})

Get a clock specifier's cell value at an index.

Example devicetree fragment:

```
clk1: clock-controller@... {
    compatible = "vnd,clock";
    #clock-cells = < 2 >;
};

n: node {
    clocks = < &clk1 10 20 >, < &clk1 30 40 >;
};
```

Bindings fragment for the vnd,clock compatible:

```
clock-cells:
    - bus
    - bits
```

Example usage:

\texttt{DT\_CLOCKS\_CELL\_BY\_IDX(DT\_NODELABEL(n), 0, bus) // 10}
\texttt{DT\_CLOCKS\_CELL\_BY\_IDX(DT\_NODELABEL(n), 1, bits) // 40}

See also:

\texttt{DT\_PHA\_BY\_IDX()}

Parameters

- `node_id` – node identifier for a node with a clocks property
- `idx` – logical index into clocks property
- `cell` – lowercase-and-underscores cell name

Returns

the cell value at index “idx”

\texttt{DT\_CLOCKS\_CELL\_BY\_NAME}(\texttt{node\_id}, \texttt{name}, \texttt{cell})

Get a clock specifier's cell value by name.

Example devicetree fragment:

```
clk1: clock-controller@... {
    compatible = "vnd,clock";
    #clock-cells = < 2 >;
};

n: node {
    clocks = < &clk1 10 20 >, < &clk1 30 40 >;
    clocks-names = "alpha", "beta";
};
```

Bindings fragment for the vnd,clock compatible:
clock-cells:
- bus
- bits

Example usage:
```
DT_CLOCKS_CELL_BY_NAME(DT_NODELABEL(n), alpha, bus) // 10
DT_CLOCKS_CELL_BY_NAME(DT_NODELABEL(n), beta, bits) // 40
```

See also:

*DT_PHA_BY_NAME()*

**Parameters**

- **node_id** – node identifier for a node with a clocks property
- **name** – lowercase-and-underscores name of a clocks element as defined by the node’s clock-names property
- **cell** – lowercase-and-underscores cell name

**Returns**

the cell value in the specifier at the named element

```
DT_CLOCKS_CELL(node_id, cell)
```

Equivalent to
```
DT_CLOCKS_CELL_BY_IDX(node_id, 0, cell)
```

See also:

*DT_CLOCKS_CELL_BY_IDX()*

**Parameters**

- **node_id** – node identifier for a node with a clocks property
- **cell** – lowercase-and-underscores cell name

**Returns**

the cell value at index 0

```
DT_INST_CLOCKS_HAS_IDX(inst, idx)
```

Equivalent to
```
DT_CLOCKS_HAS_IDX(DT_DRV_INST(inst), idx)
```

**Parameters**

- **inst** – DT_DRV_COMPAT instance number; may or may not have any clocks property
- **idx** – index of a clocks property phandle-array whose existence to check

**Returns**

1 if the index exists, 0 otherwise

```
DT_INST_CLOCKS_HAS_NAME(inst, name)
```

Equivalent to
```
DT_CLOCK_HAS_NAME(DT_DRV_INST(inst), name)
```

**Parameters**

- **inst** – DT_DRV_COMPAT instance number; may or may not have any clock-names property.
- **name** – lowercase-and-underscores clock-names cell value name to check

**Returns**

1 if the clock name exists, 0 otherwise

---

5.2. Devicetree
DT_INST_NUM_CLOCKS(inst)
   Equivalent to \texttt{DT_NUM_CLOCKS(DT_DRV_INST(inst))}
   
   \textbf{Parameters}
   \begin{itemize}
   \item \texttt{inst} – instance number
   \end{itemize}
   
   \textbf{Returns}
   number of elements in the clocks property

DT_INST_CLOCKS_CTLR_BY_IDX(inst, idx)
   Get the node identifier for the controller phandle from a “clocks” phandle-array property at an index.

   \textbf{See also:}
   \texttt{DT_CLOCKS_CTLR_BY_IDX()}

   \textbf{Parameters}
   \begin{itemize}
   \item \texttt{inst} – instance number
   \item \texttt{idx} – logical index into “clocks”
   \end{itemize}
   
   \textbf{Returns}
   the node identifier for the clock controller referenced at index “idx”

DT_INST_CLOCKS_CTLR(inst)
   Equivalent to \texttt{DT_INST_CLOCKS_CTLR_BY_IDX(inst, 0)}

   \textbf{See also:}
   \texttt{DT_CLOCKS_CTLR()}

   \textbf{Parameters}
   \begin{itemize}
   \item \texttt{inst} – instance number
   \end{itemize}
   
   \textbf{Returns}
   a node identifier for the clocks controller at index 0 in “clocks”

DT_INST_CLOCKS_CTLR_BY_NAME(inst, name)
   Get the node identifier for the controller phandle from a clocks phandle-array property by name.

   \textbf{See also:}
   \texttt{DT_CLOCKS_CTLR_BY_NAME()}

   \textbf{Parameters}
   \begin{itemize}
   \item \texttt{inst} – instance number
   \item \texttt{name} – lowercase-and-underscores name of a clocks element as defined by the node’s clock-names property
   \end{itemize}
   
   \textbf{Returns}
   the node identifier for the clock controller referenced by the named element
DT_INST_CLOCKS_CELL_BY_IDX(inst, idx, cell)
Get a DT_DRV_COMPAT instance's clock specifier's cell value at an index.

See also:
DT_CLOCKS_CELL_BY_IDX()

Parameters
• inst – DT_DRV_COMPAT instance number
• idx – logical index into clocks property
• cell – lowercase-and-underscores cell name

Returns
the cell value at index “idx”

DT_INST_CLOCKS_CELL_BY_NAME(inst, name, cell)
Get a DT_DRV_COMPAT instance's clock specifier's cell value by name.

See also:
DT_CLOCKS_CELL_BY_NAME()

Parameters
• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a clocks element as defined
  by the node's clock-names property
• cell – lowercase-and-underscores cell name

Returns
the cell value in the specifier at the named element

DT_INST_CLOCKS_CELL (inst, cell)
Equivalent to DT_INST_CLOCKS_CELL_BY_IDX(inst, 0, cell)

Parameters
• inst – DT_DRV_COMPAT instance number
• cell – lowercase-and-underscores cell name

Returns
the value of the cell inside the specifier at index 0

DMA These conveniences may be used for nodes which describe direct memory access
controllers or channels, and properties related to them.

group devicetree-dmas

Defines

5.2. Devicetree
DT_DMAS_CTLR_BY_IDX(node_id, idx)
Get the node identifier for the DMA controller from a dmas property at an index.

Example devicetree fragment:

```plaintext
dma1: dma@... { ... };
dma2: dma@... { ... };
n: node {
    dmas = <&dma1 1 2 0x400 0x3>,
         <&dma2 6 3 0x404 0x5>;
};
```

Example usage:

```
DT_DMAS_CTLR_BY_IDX(DT_NODELABEL(n), 0) // DT_NODELABEL(dma1)
DT_DMAS_CTLR_BY_IDX(DT_NODELABEL(n), 1) // DT_NODELABEL(dma2)
```

See also:

```
DT_PROP_BY_PHANDLE_IDX()
```

Parameters

- `node_id` – node identifier for a node with a dmas property
- `idx` – logical index into dmas property

Returns

the node identifier for the DMA controller referenced at index “idx”

DT_DMAS_CTLR_BY_NAME(node_id, name)
Get the node identifier for the DMA controller from a dmas property by name.

Example devicetree fragment:

```plaintext
dma1: dma@... { ... };
dma2: dma@... { ... };
n: node {
    dmas = <&dma1 1 2 0x400 0x3>,
         <&dma2 6 3 0x404 0x5>;
    dma-names = "tx", "rx";
};
```

Example usage:

```
DT_DMAS_CTLR_BY_NAME(DT_NODELABEL(n), tx) // DT_NODELABEL(dma1)
DT_DMAS_CTLR_BY_NAME(DT_NODELABEL(n), rx) // DT_NODELABEL(dma2)
```

See also:

```
DT_PHANDLE_BY_NAME()
```

Parameters

- `node_id` – node identifier for a node with a dmas property
- `name` – lowercase-and-underscores name of a dmas element as defined by the node’s dma-names property

Returns

the node identifier for the DMA controller in the named element
DT_DMAS_CTLR(node_id)
Equivalent to \textit{DT_DMAS_CTLR\_BY\_IDX}(node_id, 0)

\textbf{See also:} \textit{DT_DMAS_CTLR\_BY\_IDX()}

\textbf{Parameters}
\begin{itemize}
  \item node\_id – node identifier for a node with a dmas property
\end{itemize}

\textbf{Returns}
the node identifier for the DMA controller at index 0 in the node's “dmas” property

\textbf{DT\_INST\_DMAS\_CTLR\_BY\_IDX}(inst, idx)
Get the node identifier for the DMA controller from a DT\_DRV\_COMPAT instance's dmas property at an index.

\textbf{See also:} \textit{DT_DMAS_CTLR\_BY\_IDX()}

\textbf{Parameters}
\begin{itemize}
  \item inst – DT\_DRV\_COMPAT instance number
  \item idx – logical index into dmas property
\end{itemize}

\textbf{Returns}
the node identifier for the DMA controller referenced at index “idx”

\textbf{DT\_INST\_DMAS\_CTLR\_BY\_NAME}(inst, name)
Get the node identifier for the DMA controller from a DT\_DRV\_COMPAT instance's dmas property by name.

\textbf{See also:} \textit{DT_DMAS_CTLR\_BY\_NAME()}

\textbf{Parameters}
\begin{itemize}
  \item inst – DT\_DRV\_COMPAT instance number
  \item name – lowercase-and-underscores name of a dmas element as defined by the node's dma\_names property
\end{itemize}

\textbf{Returns}
the node identifier for the DMA controller in the named element

\textbf{DT\_INST\_DMAS\_CTLR}(inst)
Equivalent to \textit{DT\_INST\_DMAS\_CTLR\_BY\_IDX}(inst, 0)

\textbf{See also:} \textit{DT_DMAS_CTLR\_BY\_IDX()}

\textbf{Parameters}
\begin{itemize}
  \item inst – DT\_DRV\_COMPAT instance number
\end{itemize}
Returns
the node identifier for the DMA controller at index 0 in the instance's “dmas” property

DT_DMAS_CELL_BY_IDX(node_id, idx, cell)
Get a DMA specifier's cell value at an index.

Example devicetree fragment:

dma1: dma@... {
    compatible = "vnd,dma";
    #dma-cells = <2>;
};

dma2: dma@... {
    compatible = "vnd,dma";
    #dma-cells = <2>;
};

n: node {
    dmas = <&dma1 1 0x400>,
          <&dma2 6 0x404>;
};

Bindings fragment for the vnd,dma compatible:

dma-cells:
    - channel
    - config

Example usage:

DT_DMAS_CELL_BY_IDX(DT_NODELABEL(n), 0, channel) // 1
DT_DMAS_CELL_BY_IDX(DT_NODELABEL(n), 1, channel) // 6
DT_DMAS_CELL_BY_IDX(DT_NODELABEL(n), 0, config) // 0x400
DT_DMAS_CELL_BY_IDX(DT_NODELABEL(n), 1, config) // 0x404

See also:
DT_PHA_BY_IDX()

Parameters

• node_id – node identifier for a node with a dmas property
• idx – logical index into dmas property
• cell – lowercase-and-underscores cell name

Returns
the cell value at index “idx”

DT_INST_DMAS_CELL_BY_IDX(inst, idx, cell)
Get a DT_DRV_COMPAT instance's DMA specifier's cell value at an index.

See also:
DT_DMAS_CELL_BY_IDX()
• **cell** – lowercase-and-underscores cell name

**Returns**

the cell value at index “idx”

**DT_DMAS_CELL_BY_NAME**(node_id, name, cell)

Get a DMA specifier’s cell value by name.

Example devicetree fragment:

```plaintext
dma1: dma@... {
    compatible = "vnd,dma";
    #dma-cells = <2>;
};

dma2: dma@... {
    compatible = "vnd,dma";
    #dma-cells = <2>;
};

n: node {
    dmas = <&dma1 1 0x400>,
           <&dma2 6 0x404>;
    dma-names = "tx", "rx";
};
```

Bindings fragment for the vnd,dma compatible:

```plaintext
dma-cells:
    - channel
    - config
```

Example usage:

```plaintext
DT_DMAS_CELL_BY_NAME(DT_NODELABEL(n), tx, channel) // 1
DT_DMAS_CELL_BY_NAME(DT_NODELABEL(n), rx, channel) // 6
DT_DMAS_CELL_BY_NAME(DT_NODELABEL(n), tx, config) // 0x400
DT_DMAS_CELL_BY_NAME(DT_NODELABEL(n), rx, config) // 0x404
```

**See also:**

**DT_PHA_BY_NAME**

**Parameters**

• **node_id** – node identifier for a node with a dmas property

• **name** – lowercase-and-underscores name of a dmas element as defined by the node's dma-names property

• **cell** – lowercase-and-underscores cell name

**Returns**

the cell value in the specifier at the named element

**DT_INST_DMAS_CELL_BY_NAME**(inst, name, cell)

Get a DT_DRV_COMPAT instance's DMA specifier's cell value by name.

**See also:**

**DT_DMAS_CELL_BY_NAME**

**Parameters**
• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a dmas element as defined by the node's dma-names property
• cell – lowercase-and-underscores cell name

Returns
the cell value in the specifier at the named element

DT_DMAS_HAS_IDX(node_id, idx)
Is index “idx” valid for a dmas property?

Parameters
• node_id – node identifier for a node with a dmas property
• idx – logical index into dmas property

Returns
1 if the “dmas” property has index “idx”, 0 otherwise

DT_INST_DMAS_HAS_IDX(inst, idx)
Is index “idx” valid for a DT_DRV_COMPAT instance's dmas property?

Parameters
• inst – DT_DRV_COMPAT instance number
• idx – logical index into dmas property

Returns
1 if the “dmas” property has a specifier at index “idx”, 0 otherwise

DT_DMAS_HAS_NAME(node_id, name)
Does a dmas property have a named element?

Parameters
• node_id – node identifier for a node with a dmas property
• name – lowercase-and-underscores name of a dmas element as defined by the node's dma-names property

Returns
1 if the dmas property has the named element, 0 otherwise

DT_INST_DMAS_HAS_NAME(inst, name)
Does a DT_DRV_COMPAT instance's dmas property have a named element?

Parameters
• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a dmas element as defined by the node's dma-names property

Returns
1 if the dmas property has the named element, 0 otherwise

Fixed flash partitions These conveniences may be used for the special-purpose fixed-partitions compatible used to encode information about flash memory partitions in the device tree. See See fixed-partition for more details.

group devicetree-fixed-partition
Defines

**DT_NODE_BY_FIXED_PARTITION_LABEL**(label)
Get a node identifier for a fixed partition with a given label property.

Example devicetree fragment:

```markdown
flash@... {
  partitions {
    compatible = "fixed-partitions";
    boot_partition: partition@0 {
      label = "mcuboot";
    }; 
    slot0_partition: partition@c000 {
      label = "image-0";
    };
    ...
  };
}
```

Example usage:

- `DT_NODE_BY_FIXED_PARTITION_LABEL(mcuboot)` // node identifier for boot_partition
- `DT_NODE_BY_FIXED_PARTITION_LABEL(image_0)` // node identifier for slot0_partition

**Parameters**

- **label** – lowercase-and-underscores label property value

**Returns**

a node identifier for the partition with that label property

**DT_HAS_FIXED_PARTITION_LABEL**(label)
Test if a fixed partition with a given label property exists.

**Parameters**

- **label** – lowercase-and-underscores label property value

**Returns**

1 if any “fixed-partitions” child node has the given label, 0 otherwise.

**DT_FIXED_PARTITION_EXISTS**(node_id)
Test if fixed-partition compatible node exists.

**Parameters**

- **node_id** – DTS node to test

**Returns**

1 if node exists and is fixed-partition compatible, 0 otherwise.

**DT_FIXED_PARTITION_ID**(node_id)
Get a numeric identifier for a fixed partition.

**Parameters**

- **node_id** – node identifier for a fixed-partitions child node

**Returns**

the partition's ID, a unique zero-based index number

**DT_MEM_FROM_FIXED_PARTITION**(node_id)
Get the node identifier of the flash memory for a partition.

**Parameters**

---

5.2. Devicetree
• node_id – node identifier for a fixed-partitions child node

Returns
the node identifier of the internal memory that contains the fixed-partitions node, or DT_INVALID_NODE if it doesn’t exist.

DT_MTD_FROM_FIXED_PARTITION(node_id)
Get the node identifier of the flash controller for a partition.

Parameters
• node_id – node identifier for a fixed-partitions child node

Returns
the node identifier of the memory technology device that contains the fixed-partitions node.

DT_FIXED_PARTITION_ADDR(node_id)
Get the absolute address of a fixed partition.

Example devicetree fragment:

```
&flash_controller {
    flash@1000000 {
        compatible = "soc-nv-flash";
        partitions {
            compatible = "fixed-partitions";
            storage_partition: partition@3a000 {
                label = "storage";
            };
        };
    };
}
```

Here, the “storage” partition is seen to belong to flash memory starting at address 0x1000000. The partition’s unit address of 0x3a000 represents an offset inside that flash memory.

Example usage:

```
DT_FIXED_PARTITION_ADDR(DT_NODELABEL(storage_partition)) // 0x103a000
```

This macro can only be used with partitions of internal memory addressable by the CPU. Otherwise, it may produce a compile-time error, such as: __REG_IDX_0_VAL_ADDRESS’ undeclared’.

Parameters
• node_id – node identifier for a fixed-partitions child node

Returns
the partition’s offset plus the base address of the flash node containing it.

GPIO These conveniences may be used for nodes which describe GPIO controllers/pins, and properties related to them.

```
group devicetree-gpio
```

Defines
DT_GPIO_CTLR_BY_IDX(node_id, gpio_pha, idx)

Get the node identifier for the controller phandle from a gpio phandle-array property at an index.

Example devicetree fragment:

```markdown
| gpio1: gpio@... { };
| gpio2: gpio@... { };
| n: node {
|    gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
|            <&gpio2 30 GPIO_ACTIVE_HIGH>;
|};
```

Example usage:

```markdown
DT_GPIO_CTLR_BY_IDX(DT_NODELABEL(n), gpios, 1) // DT_NODELABEL(gpio2)
```

See also:

*DT_PHANDLE_BY_IDX()*

Parameters

- `node_id` – node identifier
- `gpio_pha` – lowercase-and-underscores GPIO property with type “phandle-array”
- `idx` – logical index into “gpio_pha”

Returns

the node identifier for the gpio controller referenced at index “idx”

DT_GPIO_CTLR(node_id, gpio_pha)

Equivalent to `DT_GPIO_CTLR_BY_IDX(node_id, gpio_pha, 0)`

See also:

*DT_GPIO_CTLR_BY_IDX()*

Parameters

- `node_id` – node identifier
- `gpio_pha` – lowercase-and-underscores GPIO property with type “phandle-array”

Returns

a node identifier for the gpio controller at index 0 in “gpio_pha”

DT_GPIO_PIN_BY_IDX(node_id, gpio_pha, idx)

Get a GPIO specifier's pin cell at an index.

This macro only works for GPIO specifiers with cells named “pin”. Refer to the node's binding to check if necessary.

Example devicetree fragment:

```markdown
| gpio1: gpio@... {
|    compatible = "vnd,gpio";
|    #gpio-cells = <2>;
|};
```
gpio2: gpio@... {
    compatible = "vnd,gpio";
    gpio-cells = <2>;
};

n: node {
    gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
           <&gpio2 30 GPIO_ACTIVE_HIGH>;
};

Bindings fragment for the vnd,gpio compatible:

gpio-cells:
    - pin
    - flags

Example usage:

```
DT_GPIO_PIN_BY_IDX(DT_NODELABEL(n), gpios, 0) // 10
DT_GPIO_PIN_BY_IDX(DT_NODELABEL(n), gpios, 1) // 30
```

See also:

`DT_PHA_BY_IDX()`

**Parameters**

- `node_id` – node identifier
- `gpio_pha` – lowercase-and-underscores GPIO property with type “phandle-array”
- `idx` – logical index into “gpio_pha”

**Returns**

the pin cell value at index “idx”

`DT_GPIO_PIN(node_id, gpio_pha)`

Equivalent to `DT_GPIO_PIN_BY_IDX(node_id, gpio_pha, 0)`

See also:

`DT_GPIO_PIN_BY_IDX()`

**Parameters**

- `node_id` – node identifier
- `gpio_pha` – lowercase-and-underscores GPIO property with type “phandle-array”

**Returns**

the pin cell value at index 0

`DT_GPIO_FLAGS_BY_IDX(node_id, gpio_pha, idx)`

Get a GPIO specifier's flags cell at an index.

This macro expects GPIO specifiers with cells named “flags”. If there is no “flags” cell in the GPIO specifier, zero is returned. Refer to the node’s binding to check specifier cell names if necessary.
Example devicetree fragment:

```plaintext
gpio1: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;
};

gpio2: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;
};

n: node {
    gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
             <&gpio2 30 GPIO_ACTIVE_HIGH>;
};
```

Bindings fragment for the vnd,gpio compatible:

```plaintext
gpio-cells:
- pin
- flags
```

Example usage:

```plaintext
DT_GPIO_FLAGS_BY_IDX(DT_NODELABEL(n), gpios, 0) // GPIO_ACTIVE_LOW
DT_GPIO_FLAGS_BY_IDX(DT_NODELABEL(n), gpios, 1) // GPIO_ACTIVE_HIGH
```

See also:

DT_PHA_BY_IDX()

Parameters

- node_id – node identifier
  - gpio_pha – lowercase-and-underscores GPIO property with type
    “phandle-array”
  - idx – logical index into “gpio_pha”

Returns

the flags cell value at index “idx”, or zero if there is none

DT_GPIO_FLAGS(node_id, gpio_pha)

Equivalent to DT_GPIO_FLAGS_BY_IDX(node_id, gpio_pha, 0)

See also:

DT_GPIO_FLAGS_BY_IDX()

Parameters

- node_id – node identifier
  - gpio_pha – lowercase-and-underscores GPIO property with type
    “phandle-array”

Returns

the flags cell value at index 0, or zero if there is none
DT_NUM_GPIO_HOGS(node_id)

Get the number of GPIO hogs in a node.

This expands to the number of hogged GPIOs, or zero if there are none.

Example devicetree fragment:

```
gpio1: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;

    n1: node-1 {
        gpio-hog;
        gpios = <0 GPIO_ACTIVE_HIGH>, <1 GPIO_ACTIVE_LOW>;
        output-high;
    };

    n2: node-2 {
        gpio-hog;
        gpios = <3 GPIO_ACTIVE_HIGH>;
        output-low;
    };
};
```

Bindings fragment for the vnd,gpio compatible:

```
gpio-cells:
    - pin
    - flags
```

Example usage:

```
DT_NUM_GPIO_HOGS(DT_NODELABEL(n1)) // 2
DT_NUM_GPIO_HOGS(DT_NODELABEL(n2)) // 1
```

**Parameters**

- node_id – node identifier; may or may not be a GPIO hog node.

**Returns**

number of hogged GPIOs in the node

DT_GPIO_HOG_PIN_BY_IDX(node_id, idx)

Get a GPIO hog specifier's pin cell at an index.

This macro only works for GPIO specifiers with cells named “pin”. Refer to the node’s binding to check if necessary.

Example devicetree fragment:

```
 gpio1: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;

    n1: node-1 {
        gpio-hog;
        gpios = <0 GPIO_ACTIVE_HIGH>, <1 GPIO_ACTIVE_LOW>;
        output-high;
    };

    n2: node-2 {
        gpio-hog;
        gpios = <3 GPIO_ACTIVE_HIGH>;
    };
};
```

(continues on next page)
Bindings fragment for the vnd,gpio compatible:

gpio-cells:
  - pin
  - flags

Example usage:

```
DT_GPIO_HOG_PIN_BY_IDX(DT_NODELABEL(n1), 0) // 0
DT_GPIO_HOG_PIN_BY_IDX(DT_NODELABEL(n1), 1) // 1
DT_GPIO_HOG_PIN_BY_IDX(DT_NODELABEL(n2), 0) // 3
```

**Parameters**

- `node_id` – node identifier
- `idx` – logical index into “gpios”

**Returns**

the pin cell value at index “idx”

`DT_GPIO_HOG_FLAGS_BY_IDX(node_id, idx)`

Get a GPIO hog specifier's flags cell at an index.

This macro expects GPIO specifiers with cells named “flags”. If there is no “flags” cell in the GPIO specifier, zero is returned. Refer to the node's binding to check specifier cell names if necessary.

Example devicetree fragment:

```plaintext
gpio@... {
  compatible = "vnd,gpio";
  #gpio-cells = <2>;
  
  n1: node-1 {
    gpio-hog;
    gpios = <0 GPIO_ACTIVE_HIGH>, <1 GPIO_ACTIVE_LOW>;
    output-high;
  };

  n2: node-2 {
    gpio-hog;
    gpios = <3 GPIO_ACTIVE_HIGH>;
    output-low;
  };
}
```

Bindings fragment for the vnd,gpio compatible:

gpio-cells:
  - pin
  - flags

Example usage:

```
DT_GPIO_HOG_FLAGS_BY_IDX(DT_NODELABEL(n1), 0) // GPIO_ACTIVE_HIGH
DT_GPIO_HOG_FLAGS_BY_IDX(DT_NODELABEL(n1), 1) // GPIO_ACTIVE_LOW
DT_GPIO_HOG_FLAGS_BY_IDX(DT_NODELABEL(n2), 0) // GPIO_ACTIVE_HIGH
```
**Parameters**

- `node_id` – node identifier
- `idx` – logical index into “gpios”

**Returns**

the flags cell value at index “idx”, or zero if there is none

```c
DT_INST_GPIO_PIN_BY_IDX(inst, gpio_pha, idx)
```

Get a DT_DRV_COMPAT instance's GPIO specifier's pin cell value at an index.

**See also:**

`DT_GPIO_PIN_BY_IDX()`

**Parameters**

- `inst` – DT_DRV_COMPAT instance number
- `gpio_pha` – lowercase-and-underscores GPIO property with type “phandle-array”
- `idx` – logical index into “gpio_pha”

**Returns**

the pin cell value at index “idx”

```c
DT_INST_GPIO_PIN(inst, gpio_pha)
```

Equivalent to `DT_INST_GPIO_PIN_BY_IDX(inst, gpio_pha, 0)`

**See also:**

`DT_INST_GPIO_PIN_BY_IDX()`

**Parameters**

- `inst` – DT_DRV_COMPAT instance number
- `gpio_pha` – lowercase-and-underscores GPIO property with type “phandle-array”

**Returns**

the pin cell value at index 0

```c
DT_INST_GPIO_FLAGS_BY_IDX(inst, gpio_pha, idx)
```

Get a DT_DRV_COMPAT instance's GPIO specifier's flags cell at an index.

**See also:**

`DT_GPIO_FLAGS_BY_IDX()`

**Parameters**

- `inst` – DT_DRV_COMPAT instance number
- `gpio_pha` – lowercase-and-underscores GPIO property with type “phandle-array”
- `idx` – logical index into “gpio_pha”

**Returns**

the flags cell value at index “idx”, or zero if there is none
DT_INST_GPIO_FLAGS(inst, gpio_pha)
   Equivalent to DT_INST_GPIO_FLAGS_BY_IDX(inst, gpio_pha, 0)

See also:
DT_INST_GPIO_FLAGS_BY_IDX()

Parameters
- inst – DT_DRV_COMPAT instance number
- gpio_pha – lowercase-and-underscores GPIO property with type
  “phandle-array”

Returns
the flags cell value at index 0, or zero if there is none

IO channels These are commonly used by device drivers which need to use IO channels (e.g.
ADC or DAC channels) for conversion.

    group devicetree-io-channels

Defines

DT_IO_CHANNELS_CTLR_BY_IDX(node_id, idx)
Get the node identifier for the node referenced by an io-channels property at an index.
Example devicetree fragment:
adc1: adc@... { ... ;
adc2: adc@... { ... ;
    n: node {
       io-channels = <&adc1 10>, <&adc2 20>;
    };

Example usage:
DT_IO_CHANNELS_CTLR_BY_IDX(DT_NODELABEL(n), 0) // DT_NODELABEL(adc1)
DT_IO_CHANNELS_CTLR_BY_IDX(DT_NODELABEL(n), 1) // DT_NODELABEL(adc2)

See also:
DT_PROP_BY_PHANDLE_IDX()

Parameters
- node_id – node identifier for a node with an io-channels property
- idx – logical index into io-channels property

Returns
the node identifier for the node referenced at index “idx”

DT_IO_CHANNELS_CTLR_BY_NAME(node_id, name)
Get the node identifier for the node referenced by an io-channels property by name.
Example devicetree fragment:
adc1: adc@... { ... };
adc2: adc@... { ... };

n: node {
    io-channels = <&adc1 10>, <&adc2 20>;
    io-channel-names = "SENSOR", "BANDGAP";
};

Example usage:

```
DT_IO_CHANNELS_CTLR_BY_NAME(DT_NODELABEL(n), sensor) //
DT_NODELABEL(adc1) DT_IO_CHANNELS_CTLR_BY_NAME(DT_NODELABEL(n), bandgap) // DT_NODELABEL(adc2)
```

See also:

```
DT_PHANDLE_BY_NAME()
```

**Parameters**

- **node_id** – node identifier for a node with an io-channels property
- **name** – lowercase-and-underscores name of an io-channels element as defined by the node's io-channel-names property

**Returns**

the node identifier for the node referenced at the named element

```
DT_IO_CHANNELS_CTLR(node_id)
```

Equivalent to `DT_IO_CHANNELS_CTLR_BYIDX(node_id, 0)`

See also:

```
DT_IO_CHANNELS_CTLR_BYIDX()
```

**Parameters**

- **node_id** – node identifier for a node with an io-channels property

**Returns**

the node identifier for the node referenced at index 0 in the node's “io-channels” property

```
DT_INST_IO_CHANNELS_CTLR_BYIDX(inst, idx)
```

Get the node identifier from a DT_DRV_COMPAT instance's io-channels property at an index.

See also:

```
DT_IO_CHANNELS_CTLR_BYIDX()
```

**Parameters**

- **inst** – DT_DRV_COMPAT instance number
- **idx** – logical index into io-channels property

**Returns**

the node identifier for the node referenced at index “idx”
DT_INST_IO_CHANNELS_CTLR_BY_NAME(inst, name)
Get the node identifier from a DT_DRV_COMPAT instance's io-channels property by name.

See also:
DT_IOS_CHANNELS_CTLR_BY_NAME()

Parameters
- inst – DT_DRV_COMPAT instance number
- name – lowercase-and-underscores name of an io-channels element as defined by the node's io-channel-names property

Returns
the node identifier for the node referenced at the named element

DT_INST_IO_CHANNELS_CTLR(inst)
Equivalent to DT_INST_IO_CHANNELS_CTLR_BY_IDX(inst, 0)

See also:
DT_IOS_CHANNELS_CTLR_BY_IDX()

Parameters
- inst – DT_DRV_COMPAT instance number

Returns
the node identifier for the node referenced at index 0 in the node's “io-channels” property

DT_IOS_CHANNELS_INPUT_BY_IDX(node_id, idx)
Get an io-channels specifier input cell at an index.

This macro only works for io-channels specifiers with cells named “input”. Refer to the node's binding to check if necessary.

Example devicetree fragment:

```
adc1: adc0... {
    compatible = "vnd,adc";
    #io-channel-cells = <1>;
};
adc2: adc0... {
    compatible = "vnd,adc";
    #io-channel-cells = <1>;
};
n: node {
    io-channels = <adc1 10>, <adc2 20>;
};
```

Bindings fragment for the vnd,adc compatible:
io-channel-cells:
- input

Example usage:
DT_IO_CHANNELS_INPUT_BY_IDX(DT_NODELABEL(n), 0) // 10
DT_IO_CHANNELS_INPUT_BY_IDX(DT_NODELABEL(n), 1) // 20

See also:
DT_PHA_BY_IDX()

Parameters

• node_id – node identifier for a node with an io-channels property
• idx – logical index into io-channels property

Returns

the input cell in the specifier at index “idx”

DT_IO_CHANNELS_INPUT_BY_NAME(node_id, name)

Get an io-channels specifier input cell by name.

This macro only works for io-channels specifiers with cells named “input”. Refer to
the node’s binding to check if necessary.

Example devicetree fragment:

adc1: adc@... {
    compatible = "vnd,adc";
    #io-channel-cells = <1>;
};
adc2: adc@... {
    compatible = "vnd,adc";
    #io-channel-cells = <1>;
};
n: node {
    io-channels = <&adc1 10>, <&adc2 20>;
    io-channel-names = "SENSOR", "BANDGAP";
};

Bindings fragment for the vnd,adc compatible:

io-channel-cells:
• input

Example usage:

DT_IO_CHANNELS_INPUT_BY_NAME(DT_NODELABEL(n), sensor) // 10
DT_IO_CHANNELS_INPUT_BY_NAME(DT_NODELABEL(n), bandgap) // 20

See also:
DT_PHA_BY_NAME()

Parameters

• node_id – node identifier for a node with an io-channels property
• name – lowercase-and-underscores name of an io-channels element as defined by the node’s io-channel-names property

Returns

the input cell in the specifier at the named element
DT_IO_CHANNELS_INPUT(node_id)
   Equivalent to DT_IO_CHANNELS_INPUT_BY_IDX(node_id, 0)

   See also:
   DT_IO_CHANNELS_INPUT_BY_IDX()

   Parameters
   • node_id – node identifier for a node with an io-channels property

   Returns
   the input cell in the specifier at index 0

DT_INST_IO_CHANNELS_INPUT_BY_IDX(inst, idx)
   Get an input cell from the “DT_DRV_INST(inst)” io-channels property at an index.

   See also:
   DT_IO_CHANNELS_INPUT_BY_IDX()

   Parameters
   • inst – DT_DRV_COMPAT instance number
   • idx – logical index into io-channels property

   Returns
   the input cell in the specifier at index “idx”

DT_INST_IO_CHANNELS_INPUT_BY_NAME(inst, name)
   Get an input cell from the “DT_DRV_INST(inst)” io-channels property by name.

   See also:
   DT_IO_CHANNELS_INPUT_BY_NAME()

   Parameters
   • inst – DT_DRV_COMPAT instance number
   • name – lowercase-and-underscores name of an io-channels element as defined by the instance's io-channel-names property

   Returns
   the input cell in the specifier at the named element

DT_INST_IO_CHANNELS_INPUT(inst)
   Equivalent to DT_INST_IO_CHANNELS_INPUT_BY_IDX(inst, 0)

   Parameters
   • inst – DT_DRV_COMPAT instance number

   Returns
   the input cell in the specifier at index 0
MBOX These conveniences may be used for nodes which describe MBOX controllers/users, and properties related to them.

group devicetree-mbox

Defines

**DT_MBOX_CTLR_BY_NAME(node_id, name)**
Get the node identifier for the MBOX controller from a mboxes property by name.

Example devicetree fragment:

```plaintext
mbox1: mbox-controller@... { ... ;
    n: node {
        mboxes = <&mbox1 8>,
            <&mbox1 9>;
        mbox-names = "tx", "rx";
    }
};
```

Example usage:

```plaintext
DT_MBOX_CTLR_BY_NAME(DT_NODELABEL(n), tx) // DT_NODELABEL(mbox1)
DT_MBOX_CTLR_BY_NAME(DT_NODELABEL(n), rx) // DT_NODELABEL(mbox1)
```

See also:

**DT_PHANDLE_BY_NAME()**

Parameters

- **node_id** – node identifier for a node with a mboxes property
- **name** – lowercase-and-underscores name of a mboxes element as defined by the node’s mbox-names property

Returns

the node identifier for the MBOX controller in the named element

**DT_MBOX_CHANNEL_BY_NAME(node_id, name)**
Get a MBOX channel value by name.

Example devicetree fragment:

```plaintext
mbox1: mbox@... { 
    #mbox-cells = <1>;
};

n: node {
    mboxes = <&mbox1 1>,
            <&mbox1 6>;
    mbox-names = "tx", "rx";
};
```

Bindings fragment for the mbox compatible:

```plaintext
mbox-cells:
    - channel
```

Example usage:
DT_MBOX_CHANNEL_BY_NAME(DT_NODELABEL(n), tx) // 1
DT_MBOX_CHANNEL_BY_NAME(DT_NODELABEL(n), rx) // 6

See also:
DT_PHA_BY_NAME_OR()

Parameters
• node_id – node identifier for a node with a mbox property
• name – lowercase-and-underscores name of a mbox element as defined by the node’s mbox-names property

Returns
the channel value in the specifier at the named element or 0 if no channels are supported

Pinctrl (pin control) These are used to access pin control properties by name or index.
Devicetree nodes may have properties which specify pin control (sometimes known as pin mux) settings. These are expressed using pinctrl-<index> properties within the node, where the <index> values are contiguous integers starting from 0. These may also be named using the pinctrl-names property.

Here is an example:

node {
  ...
  pinctrl-0 = <&foo &bar ...>;
  pinctrl-1 = <&baz ...>;
  pinctrl-names = "default", "sleep";
};

Above, pinctrl-0 has name "default", and pinctrl-1 has name "sleep". The pinctrl-<index> property values contain phandles. The &foo, &bar, etc. phandles within the properties point to nodes whose contents vary by platform, and which describe a pin configuration for the node.

group devicetree-pinctrl

Defines

DT_PINCTRL_BY_IDX(node_id, pc_idx, idx)
Get a node identifier for a phandle in a pinctrl property by index.

Example devicetree fragment:

n: node {
  pinctrl-0 = <&foo &bar>;
  pinctrl-1 = <&baz &blub>;
}

Example usage:

DT_PINCTRL_BY_IDX(DT_NODELABEL(n), 0, 1) // DT_NODELABEL(bar)
DT_PINCTRL_BY_IDX(DT_NODELABEL(n), 1, 0) // DT_NODELABEL(baz)

Parameters
• node_id – node with a pinctrl-‘pc_idx’ property
- pc_idx – index of the pinctrl property itself
- idx – index into the value of the pinctrl property

**Returns**
node identifier for the phandle at index ‘idx’ in ‘pinctrl-‘pc_idx’"

**DT_PINCTRL_0(node_id, idx)**
Get a node identifier from a pinctrl-0 property.
This is equivalent to:

```
DT_PINCTRL_BY_IDX(node_id, 0, idx)
```

It is provided for convenience since pinctrl-0 is commonly used.

**Parameters**
- node_id – node with a pinctrl-0 property
- idx – index into the pinctrl-0 property

**Returns**
node identifier for the phandle at index idx in the pinctrl-0 property of that node

**DT_PINCTRL_BY_NAME(node_id, name, idx)**
Get a node identifier for a phandle inside a pinctrl node by name.

Example devicetree fragment:

```
n: node {
    pinctrl-0 = <&foo &bar>;
    pinctrl-1 = <&baz &blub>;
    pinctrl-names = "default", "sleep";
};
```

Example usage:

```
DT_PINCTRL_BY_NAME(DT_NODELABEL(n), default, 1) // DT_NODELABEL(bar)
DT_PINCTRL_BY_NAME(DT_NODELABEL(n), sleep, 0) // DT_NODELABEL(baz)
```

**Parameters**
- node_id – node with a named pinctrl property
- name – lowercase-and-underscores pinctrl property name
- idx – index into the value of the named pinctrl property

**Returns**
node identifier for the phandle at that index in the pinctrl property

**DT_PINCTRL_NAME_TO_IDX(node_id, name)**
Convert a pinctrl name to its corresponding index.

Example devicetree fragment:

```
n: node {
    pinctrl-0 = <&foo &bar>;
    pinctrl-1 = <&baz &blub>;
    pinctrl-names = "default", "sleep";
};
```

Example usage:
Parameters

- `node_id` – node identifier with a named pinctrl property
- `name` – lowercase-and-underscores name of the pinctrl whose index to get

Returns

integer literal for the index of the pinctrl property with that name

\[\text{DT_PINCTRL_IDX_TO_NAME_TOKEN}(\text{node_id, pc_idx})\]

Convert a pinctrl property index to its name as a token.

This allows you to get a pinctrl property's name, and “remove the quotes” from it.

\[\text{DT_PINCTRL_IDX_TO_NAME_TOKEN}()\]

can only be used if the node has a pinctrl-`pc_idx` property and a pinctrl-names property element for that index. It is an error to use it in other circumstances.

Example devicetree fragment:

```plaintext
n: node {
    pinctrl-0 = <...>;
    pinctrl-1 = <...>;
    pinctrl-names = "default", "f.o.o2";
};
```

Example usage:

```plaintext
DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_NODELABEL(n), 0) // default
DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_NODELABEL(n), 1) // f_o_o2
```

The same caveats and restrictions that apply to \[\text{DT_STRING_TOKEN()}\]’s return value also apply here.

Parameters

- `node_id` – node identifier
- `pc_idx` – index of a pinctrl property in that node

Returns

name of the pinctrl property, as a token, without any quotes and with non-alphanumeric characters converted to underscores

\[\text{DT_PINCTRL_IDX_TO_NAME_UPPER_TOKEN}(\text{node_id, pc_idx})\]

Like \[\text{DT_PINCTRL_IDX_TO_NAME_TOKEN}()\], but with an uppercased result.

This does the a similar conversion as \[\text{DT_PINCTRL_IDX_TO_NAME_TOKEN}(\text{node_id, pc_idx})\]. The only difference is that alphabetical characters in the result are uppercased.

Example devicetree fragment:

```plaintext
n: node {
    pinctrl-0 = <...>;
    pinctrl-1 = <...>;
    pinctrl-names = "default", "f.o.o2";
};
```
Example usage:

```
DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_NODELABEL(n), 0) // DEFAULT
DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_NODELABEL(n), 1) // F_O_O2
```

The same caveats and restrictions that apply to `DT_STRING_UPPER_TOKEN()`’s return value also apply here.

**DT_NUM_PINCTRLS_BY_IDX(node_id, pc_idx)**

Get the number of phandles in a pinctrl property.

Example devicetree fragment:

```plaintext
n1: node-1 {
    pinctrl-0 = <&foo &bar>;
};

n2: node-2 {
    pinctrl-0 = <&baz>;
};
```

Example usage:

```
DT_NUM_PINCTRLS_BY_IDX(DT_NODELABEL(n1), 0) // 2
DT_NUM_PINCTRLS_BY_IDX(DT_NODELABEL(n2), 0) // 1
```

**Parameters**

- `node_id` – node identifier with a pinctrl property
- `pc_idx` – index of the pinctrl property itself

**Returns**

number of phandles in the property with that index

**DT_NUM_PINCTRLS_BY_NAME(node_id, name)**

Like `DT_NUM_PINCTRLS_BY_IDX()`, but by name instead.

Example devicetree fragment:

```plaintext
n: node {
    pinctrl-0 = <&foo &bar>;
    pinctrl-1 = <&baz>
    pinctrl-names = "default", "sleep";
};
```

Example usage:

```
DT_NUM_PINCTRLS_BY_NAME(DT_NODELABEL(n), default) // 2
DT_NUM_PINCTRLS_BY_NAME(DT_NODELABEL(n), sleep) // 1
```

**Parameters**

- `node_id` – node identifier with a pinctrl property
- `name` – lowercase-and-underscores name name of the pinctrl property

**Returns**

number of phandles in the property with that name

**DT_NUM_PINCTRL_STATES(node_id)**

Get the number of pinctrl properties in a node.
This expands to 0 if there are no pinctrl-i properties. Otherwise, it expands to the number of such properties.

Example devicetree fragment:

```plaintext
n1: node-1 {
    pinctrl-0 = <...>;
    pinctrl-1 = <...>;
};

n2: node-2 {
};
```

Example usage:

```plaintext
DT_NUM_PINCTRL_STATES(DT_NODELABEL(n1)) // 2
DT_NUM_PINCTRL_STATES(DT_NODELABEL(n2)) // 0
```

**Parameters**

- `node_id` – node identifier; may or may not have any pinctrl properties

**Returns**

number of pinctrl properties in the node

**DT_PINCTRL_HAS_IDX** (`node_id`, `pc_idx`)

Test if a node has a pinctrl property with an index.

This expands to 1 if the pinctrl-`idx` property exists. Otherwise, it expands to 0.

Example devicetree fragment:

```plaintext
n1: node-1 {
    pinctrl-0 = <...>;
    pinctrl-1 = <...>;
};

n2: node-2 {
};
```

Example usage:

```plaintext
DT_PINCTRL_HAS_IDX(DT_NODELABEL(n1), 0) // 1
DT_PINCTRL_HAS_IDX(DT_NODELABEL(n1), 1) // 1
DT_PINCTRL_HAS_IDX(DT_NODELABEL(n1), 2) // 0
DT_PINCTRL_HAS_IDX(DT_NODELABEL(n2), 0) // 0
```

**Parameters**

- `node_id` – node identifier; may or may not have any pinctrl properties
- `pc_idx` – index of a pinctrl property whose existence to check

**Returns**

1 if the property exists, 0 otherwise

**DT_PINCTRL_HAS_NAME** (`node_id`, `name`)

Test if a node has a pinctrl property with a name.

This expands to 1 if the named pinctrl property exists. Otherwise, it expands to 0.

Example devicetree fragment: 

```plaintext
```

5.2. Devicetree
n1: node-1 {
    pinctrl-0 = <...>;
    pinctrl-names = "default";
};
n2: node-2 {
};

Example usage:

DT_PINCTRL_HAS_NAME(DT_NODELABEL(n1), default) // 1
DT_PINCTRL_HAS_NAME(DT_NODELABEL(n1), sleep) // 0
DT_PINCTRL_HAS_NAME(DT_NODELABEL(n2), default) // 0

Parameters

• node_id – node identifier; may or may not have any pinctrl properties
• name – lowercase-and-underscores pinctrl property name to check

Returns

1 if the property exists, 0 otherwise

DT_INST_PINCTRL_BY_IDX(inst, pc_idx, idx)
Get a node identifier for a phandle in a pinctrl property by index for a
DT_DRV_COMPAT instance.
This is equivalent to DT_PINCTRL_BY_IDX(DT_DRV_INST(inst), pc_idx, idx).

Parameters

• inst – instance number
• pc_idx – index of the pinctrl property itself
• idx – index into the value of the pinctrl property

Returns
	node identifier for the phandle at index ‘idx’ in ‘pinctrl-‘pc_idx’”

DT_INST_PINCTRL_0(inst, idx)
Get a node identifier from a pinctrl-0 property for a DT_DRV_COMPAT instance.
This is equivalent to:

DT_PINCTRL_BY_IDX(DT_DRV_INST(inst), 0, idx)

It is provided for convenience since pinctrl-0 is commonly used.

Parameters

• inst – instance number
• idx – index into the pinctrl-0 property

Returns
	node identifier for the phandle at index idx in the pinctrl-0 property of that
instance

DT_INST_PINCTRL_BY_NAME(inst, name, idx)
Get a node identifier for a phandle inside a pinctrl node for a DT_DRV_COMPAT in-
stance.

This is equivalent to DT_PINCTRL_BY_NAME(DT_DRV_INST(inst), name, idx).

Parameters
• inst – instance number
• name – lowercase-and-underscores pinctrl property name
• idx – index into the value of the named pinctrl property

Returns
node identifier for the phandle at that index in the pinctrl property

\texttt{DT_INST_PINCTRL_NAME_TO_IDX}(\texttt{inst, name})
Convert a pinctrl name to its corresponding index for a DT_DRV_COMPAT instance.
This is equivalent to \texttt{DT_PINCTRL_NAME_TO_IDX(DT_DRV_INST(inst), name)}.

Parameters
• inst – instance number
• name – lowercase-and-underscores name of the pinctrl whose index to get

Returns
integer literal for the index of the pinctrl property with that name

\texttt{DT_INST_PINCTRL_IDX_TO_NAME_TOKEN}(\texttt{inst, pc_idx})
Convert a pinctrl index to its name as an uppercased token.
This is equivalent to \texttt{DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_DRV_INST(inst), pc_idx)}.

Parameters
• inst – instance number
• pc_idx – index of the pinctrl property itself

Returns
name of the pin control property as a token

\texttt{DT_INST_PINCTRL_IDX_TO_NAME_UPPER_TOKEN}(\texttt{inst, pc_idx})
Convert a pinctrl index to its name as an uppercased token.
This is equivalent to \texttt{DT_PINCTRL_IDX_TO_NAME_UPPER_TOKEN(DT_DRV_INST(inst), idx)}.

Parameters
• inst – instance number
• pc_idx – index of the pinctrl property itself

Returns
name of the pin control property as an uppercase token

\texttt{DT_INST_NUM_PINCTRLS_BY_IDX}(\texttt{inst, pc_idx})
Get the number of phandles in a pinctrl property for a DT_DRV_COMPAT instance.
This is equivalent to \texttt{DT_NUM_PINCTRLS_BY_IDX(DT_DRV_INST(inst), pc_idx)}.

Parameters
• inst – instance number
• pc_idx – index of the pinctrl property itself

Returns
number of phandles in the property with that index

\texttt{DT_INST_NUM_PINCTRLS_BY_NAME}(\texttt{inst, name})
Like \texttt{DT_INST_NUM_PINCTRLS_BY_IDX()}, but by name instead.
This is equivalent to \texttt{DT_NUM_PINCTRLS_BY_NAME(DT_DRV_INST(inst), name)}.

Parameters
• inst – instance number
• name – lowercase-and-underscores name of the pinctrl property

Returns
number of phandles in the property with that name

DT_INST_NUM_PINCTRL_STATES(inst)
Get the number of pinctrl properties in a DT_DRV_COMPAT instance.
This is equivalent to DT_NUM_PINCTRL_STATES(DT_DRV_INST(inst)).

Parameters
• inst – instance number

Returns
number of pinctrl properties in the instance

DT_INST_PINCTRL_HAS_IDX(inst, pc_idx)
Test if a DT_DRV_COMPAT instance has a pinctrl property with an index.
This is equivalent to DT_PINCTRL_HAS_IDX(DT_DRV_INST(inst), pc_idx).

Parameters
• inst – instance number
• pc_idx – index of a pinctrl property whose existence to check

Returns
1 if the property exists, 0 otherwise

DT_INST_PINCTRL_HAS_NAME(inst, name)
Test if a DT_DRV_COMPAT instance has a pinctrl property with a name.
This is equivalent to DT_PINCTRL_HAS_NAME(DT_DRV_INST(inst), name).

Parameters
• inst – instance number
• name – lowercase-and-underscores pinctrl property name to check

Returns
1 if the property exists, 0 otherwise

**PWM** These conveniences may be used for nodes which describe PWM controllers and properties related to them.

*group devicetree-pwms*

**Defines**

DT_PWMS_CTLR_BY_IDX(node_id, idx)
Get the node identifier for the PWM controller from a pwms property at an index.

Example devicetree fragment:

```plaintext
pwm1: pwm-controller@... { ... };
pwm2: pwm-controller@... { ... };
n: node {
```
pwms = <&pwm1 1 PWM_POLARITY_NORMAL>, <&pwm2 3 PWM_POLARITY_INVERTED>;
}

Example usage:
DT_PWMS_CTRLR_BY_IDX(DT_NODELABEL(n), 0) // DT_NODELABEL(pwm1)
DT_PWMS_CTRLR_BY_IDX(DT_NODELABEL(n), 1) // DT_NODELABEL(pwm2)

See also:
DT_PROP_BY_PHANDLE_IDX()

Parameters
• node_id – node identifier for a node with a pwms property
• idx – logical index into pwms property

Returns
the node identifier for the PWM controller referenced at index “idx”

DT_PWMS_CTRLR_BY_NAME(node_id, name)
Get the node identifier for the PWM controller from a pwms property by name.
Example devicetre fragment:

Example usage:
DT_PWMS_CTRLR_BY_NAME(DT_NODELABEL(n), alpha) // DT_NODELABEL(pwm1)
DT_PWMS_CTRLR_BY_NAME(DT_NODELABEL(n), beta) // DT_NODELABEL(pwm2)

See also:
DT_PHANDLE_BY_NAME()

Parameters
• node_id – node identifier for a node with a pwms property
• name – lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property

Returns
the node identifier for the PWM controller in the named element

DT_PWMS_CTRLR(node_id)
Equivalent to DT_PWMS_CTRLR_BY_IDX(node_id, 0)

See also:
DT_PWMS_CTRLR_BY_IDX()
Returns

the node identifier for the PWM controller at index 0 in the node’s “pwms” property

`DT_PWMS_CELL_BY_IDX(node_id, idx, cell)`

Get PWM specifier's cell value at an index.

Example devicetree fragment:

```dtb
pwm1: pwm-controller@... {
    compatible = "vnd,pwm";
    #pwm-cells = <2>;
};

pwm2: pwm-controller@... {
    compatible = "vnd,pwm";
    #pwm-cells = <2>;
};

n: node {
    pwms = <&pwm1 1 200000 PWM_POLARITY_NORMAL>,
           <&pwm2 3 100000 PWM_POLARITY_INVERTED>;
};
```

Bindings fragment for the “vnd,pwm” compatible:

```dtb
pwm-cells:
- channel
- period
- flags
```

Example usage:

```c
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 0, channel) // 1
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 1, channel) // 3
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 0, period) // 200000
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 1, period) // 100000
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 0, flags) // PWM_POLARITY_NORMAL
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 1, flags) // PWM_POLARITY_INVERTED
```

See also:

`DT_PHA_BY_IDX()`

Parameters

- **node_id** – node identifier for a node with a pwms property
- **idx** – logical index into pwms property
- **cell** – lowercase-and-underscores cell name

Returns

the cell value at index “idx”

`DT_PWMS_CELL_BY_NAME(node_id, name, cell)`

Get a PWM specifier's cell value by name.

Example devicetree fragment:

```dtb
pwm1: pwm-controller@... {
    compatible = "vnd,pwm";
    #pwm-cells = <2>;
};
```
Bindings fragment for the “vnd,pwm” compatible:

```
pwm-cells:
  - channel
  - period
  - flags
```

Example usage:

```
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), alpha, channel) // 1
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), beta, channel) // 3
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), alpha, period) // 200000
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), beta, period) // 100000
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), alpha, flags) // PWM_POLARITY_NORMAL
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), beta, flags) // PWM_POLARITY_INVERTED
```

See also:

`DT_PHA_BY_NAME()`

**Parameters**

- `node_id` – node identifier for a node with a pwms property
- `name` – lowercase-and-underscores name of a pwms element as defined by the node's pwm-names property
- `cell` – lowercase-and-underscores cell name

**Returns**

the cell value in the specifier at the named element

`DT_PWMS_CELL(node_id, cell)`

Equivalent to `DT_PWMS_CELL_BY_IDX(node_id, 0, cell)`

See also:

`DT_PWMS_CELL_BY_IDX()`

**Parameters**

- `node_id` – node identifier for a node with a pwms property
- `cell` – lowercase-and-underscores cell name

**Returns**

the cell value at index 0
DT_PWMS_CHANNEL_BY_IDX(node_id, idx)
Get a PWM specifier's channel cell value at an index.
This macro only works for PWM specifiers with cells named “channel”. Refer to the
node's binding to check if necessary.
This is equivalent to DT_PWMS_CELL_BY_IDX(node_id, idx, channel).

See also:
DT_PWMS_CELL_BY_IDX()

Parameters
• node_id – node identifier for a node with a pwms property
• idx – logical index into pwms property

Returns
the channel cell value at index “idx”

DT_PWMS_CHANNEL_BY_NAME(node_id, name)
Get a PWM specifier's channel cell value by name.
This macro only works for PWM specifiers with cells named “channel”. Refer to the
node's binding to check if necessary.
This is equivalent to DT_PWMS_CELL_BY_NAME(node_id, name, channel).

See also:
DT_PWMS_CELL_BY_NAME()

Parameters
• node_id – node identifier for a node with a pwms property
• name – lowercase-and-underscores name of a pwms element as defined
  by the node's pwm-names property

Returns
the channel cell value in the specifier at the named element

DT_PWMS_CHANNEL(node_id)
Equivalent to DT_PWMS_CHANNEL_BY_IDX(node_id, 0)

See also:
DT_PWMS_CHANNEL_BY_IDX()
DT_PWMS_PERIOD_BY_IDX(node_id, idx)
Get PWM specifier's period cell value at an index.
This macro only works for PWM specifiers with cells named “period”. Refer to the node's binding to check if necessary.
This is equivalent to DT_PWMS_CELL_BY_IDX(node_id, idx, period).

See also:
DT_PWMS_CELL_BY_IDX()

Parameters
- node_id – node identifier for a node with a pwms property
- idx – logical index into pwms property

Returns
the period cell value at index “idx”

DT_PWMS_PERIOD_BY_NAME(node_id, name)
Get a PWM specifier's period cell value by name.
This macro only works for PWM specifiers with cells named “period”. Refer to the node's binding to check if necessary.
This is equivalent to DT_PWMS_CELL_BY_NAME(node_id, name, period).

See also:
DT_PWMS_CELL_BY_NAME()

Parameters
- node_id – node identifier for a node with a pwms property
- name – lowercase-and-underscores name of a pwms element as defined by the node's pwm-names property

Returns
the period cell value in the specifier at the named element

DT_PWMS_PERIOD(node_id)
Equivalent to DT_PWMS_PERIOD_BY_IDX(node_id, 0)

See also:
DT_PWMS_PERIOD_BY_IDX()
DT_PWMS_FLAGS_BY_IDX(node_id, idx)

Get a PWM specifier’s flags cell value at an index.

This macro expects PWM specifiers with cells named “flags”. If there is no “flags” cell
in the PWM specifier, zero is returned. Refer to the node’s binding to check specifier
cell names if necessary.

This is equivalent to DT_PWMS_CELL_BY_IDX(node_id, idx, flags).

See also:

DT_PWMS_CELL_BY_IDX()

Parameters

- node_id – node identifier for a node with a pwms property
- idx – logical index into pwms property

Returns

the flags cell value at index “idx”, or zero if there is none

DT_PWMS_FLAGS_BY_NAME(node_id, name)

Get a PWM specifier’s flags cell value by name.

This macro expects PWM specifiers with cells named “flags”. If there is no “flags” cell
in the PWM specifier, zero is returned. Refer to the node’s binding to check specifier
cell names if necessary.

This is equivalent to DT_PWMS_CELL_BY_NAME(node_id, name, flags) if there is a flags
cell, but expands to zero if there is none.

See also:

DT_PWMS_CELL_BY_NAME()

Parameters

- node_id – node identifier for a node with a pwms property
- name – lowercase-and-underscores name of a pwms element as defined
  by the node’s pwm-names property

Returns

the flags cell value in the specifier at the named element, or zero if there is
none

DT_PWMS_FLAGS(node_id)

Equivalent to DT_PWMS_FLAGS_BY_IDX(node_id, 0)

See also:

DT_PWMS_FLAGS_BY_IDX()
DT_INST_PWMS_CTLR_BY_INDEX(inst, idx)
Get the node identifier for the PWM controller from a DT_DRV_COMPAT instance’s pwms property at an index.

See also:
DT_PWMS_CTLR_BY_INDEX()

Parameters
• inst – DT_DRV_COMPAT instance number
• idx – logical index into pwms property

Returns
the node identifier for the PWM controller referenced at index “idx”

DT_INST_PWMS_CTLR_BY_NAME(inst, name)
Get the node identifier for the PWM controller from a DT_DRV_COMPAT instance’s pwms property by name.

See also:
DT_PWMS_CTLR_BY_NAME()

Parameters
• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property

Returns
the node identifier for the PWM controller in the named element

DT_INST_PWMS_CTLR(inst)
Equivalent to DT_INST_PWMS_CTLR_BY_INDEX(inst, 0)

See also:
DT_PWMS_CTLR_BY_INDEX()

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
the node identifier for the PWM controller at index 0 in the instance’s “pwms” property

DT_INST_PWMS_CELL_BY_INDEX(inst, idx, cell)
Get a DT_DRV_COMPAT instance’s PWM specifier’s cell value at an index.

Parameters
• inst – DT_DRV_COMPAT instance number
• idx – logical index into pwms property
• cell – lowercase-and-underscores cell name
Returns
the cell value at index “idx”

DT_INST_PWMS_CELL_BY_NAME(inst, name, cell)
Get a DT_DRV_COMPAT instance's PWM specifier's cell value by name.

See also:

   DT_PWMS_CELL_BY_NAME()

Parameters

• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a pwms element as defined
  by the node's pwm-names property
• cell – lowercase-and-underscores cell name

Returns
the cell value in the specifier at the named element

DT_INST_PWMS_CELL(inst, cell)
Equivalent to DT_INST_PWMS_CELL_BY_IDX(inst, 0, cell)

Parameters

• inst – DT_DRV_COMPAT instance number
• cell – lowercase-and-underscores cell name

Returns
the cell value at index 0

DT_INST_PWMS_CHANNEL_BY_IDX(inst, idx)
Equivalent to DT_INST_PWMS_CELL_BY_IDX(inst, idx, channel)

See also:

   DT_INST_PWMS_CELL_BY_IDX()

Parameters

• inst – DT_DRV_COMPAT instance number
• idx – logical index into pwms property

Returns
the channel cell value at index “idx”

DT_INST_PWMS_CHANNEL_BY_NAME(inst, name)
Equivalent to DT_INST_PWMS_CELL_BY_NAME(inst, name, channel)

See also:

   DT_INST_PWMS_CELL_BY_NAME()

Parameters

• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a pwms element as defined
  by the node's pwm-names property
Returns
the channel cell value in the specifier at the named element

DT_INST_PWMS_CHANNEL(inst)
Equivalent to DT_INST_PWMS_CHANNEL_BY_IDX(inst, 0)

See also:
DT_INST_PWMS_CHANNEL_BY_IDX()

Parameters
  • inst – DT_DRV_COMPAT instance number

Returns
the channel cell value at index 0

DT_INST_PWMS_PERIOD_BY_IDX(inst, idx)
Equivalent to DT_INST_PWMS_CELL_BY_IDX(inst, idx, period)

See also:
DT_INST_PWMS_CELL_BY_IDX()

Parameters
  • inst – DT_DRV_COMPAT instance number
  • idx – logical index into pwms property

Returns
the period cell value at index “idx”

DT_INST_PWMS_PERIOD_BY_NAME(inst, name)
Equivalent to DT_INST_PWMS_CELL_BY_NAME(inst, name, period)

See also:
DT_INST_PWMS_CELL_BY_NAME()

Parameters
  • inst – DT_DRV_COMPAT instance number
  • name – lowercase-and-underscores name of a pwms element as defined
    by the node’s pwm-names property

Returns
the period cell value in the specifier at the named element

DT_INST_PWMS_PERIOD(inst)
Equivalent to DT_INST_PWMS_PERIOD_BY_IDX(inst, 0)

See also:
DT_INST_PWMS_PERIOD_BY_IDX()
Returns

- the period cell value at index 0

**DT_INST_PWMS_FLAGS_BY_IDX**(inst, idx)

Equivalent to **DT_INST_PWMS_CELL_BY_IDX**(inst, idx, flags)

See also:

**DT_INST_PWMS_CELL_BY_IDX()**

Parameters

- inst – DT_DRV_COMPAT instance number
- idx – logical index into pwms property

Returns

- the flags cell value at index “idx”, or zero if there is none

**DT_INST_PWMS_FLAGS_BY_NAME**(inst, name)

Equivalent to **DT_INST_PWMS_CELL_BY_NAME**(inst, name, flags)

See also:

**DT_INST_PWMS_CELL_BY_NAME()**

Parameters

- inst – DT_DRV_COMPAT instance number
- name – lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property

Returns

- the flags cell value in the specifier at the named element, or zero if there is none

**DT_INST_PWMS_FLAGS**(inst)

Equivalent to **DT_INST_PWMS_FLAGS_BY_IDX**(inst, 0)

See also:

**DT_INST_PWMS_FLAGS_BY_IDX()**

Parameters

- inst – DT_DRV_COMPAT instance number

Returns

- the flags cell value at index 0, or zero if there is none

**Reset Controller** These conveniences may be used for nodes which describe reset controllers and properties related to them.

**group devicetree-reset-controller**
Defines

**DT_RESET_CTLR_BY_IDX(node_id, idx)**

Get the node identifier for the controller phandle from a “resets” phandle-array property at an index.

Example devicetree fragment:

```
reset1: reset-controller@... { ... }
reset2: reset-controller@... { ... }

n: node {
    resets = <&reset1 10>, <&reset2 20>;
}
```

Example usage:

```
DT_RESET_CTLR_BY_IDX(DT_NODELABEL(n), 0)) // DT_NODELABEL(reset1)
DT_RESET_CTLR_BY_IDX(DT_NODELABEL(n), 1)) // DT_NODELABEL(reset2)
```

See also:

**DT_PHANDLE_BY_IDX()**

Parameters

- *node_id* – node identifier
- *idx* – logical index into “resets”

Returns

the node identifier for the reset controller referenced at index “idx”

**DT_RESET_CTLR(node_id)**

Equivalent to *DT_RESET_CTLR_BY_IDX(node_id, 0)*

See also:

**DT_RESET_CTLR_BY_IDX()**

Parameters

- *node_id* – node identifier

Returns

a node identifier for the reset controller at index 0 in “resets”

**DT_RESET_CTLR_BY_NAME(node_id, name)**

Get the node identifier for the controller phandle from a resets phandle-array property by name.

Example devicetree fragment:

```
reset1: reset-controller@... { ... }
reset2: reset-controller@... { ... }

n: node {
    resets = <&reset1 10>, <&reset2 20>;
    reset-names = "alpha", "beta";
}
```
Example usage:

```
DT_RESET_CTLR_BY_NAME(DT_NODELABEL(n), alpha) // DT_NODELABEL(reset1)
DT_RESET_CTLR_BY_NAME(DT_NODELABEL(n), beta) // DT_NODELABEL(reset2)
```

See also:

`DT_PHANDLE_BY_NAME()`

**Parameters**

- `node_id` – node identifier
- `name` – lowercase-and-underscores name of a resets element as defined by the node’s reset-names property

**Returns**

the node identifier for the reset controller referenced by name

**DT_RESET_CELL_BY_IDX** (node_id, idx, cell)

Get a reset specifier’s cell value at an index.

Example devicetree fragment:

```
reset: reset-controller@... {
    compatible = "vnd,reset";
    #reset-cells = <1>;
};

n: node {
    resets = <&reset 10>;
};
```

Bindings fragment for the vnd,reset compatible:

```
reset-cells:
 - id
```

Example usage:

```
DT_RESET_CELL_BY_IDX(DT_NODELABEL(n), 0, id) // 10
```

See also:

`DT_PHA_BY_IDX()`

**Parameters**

- `node_id` – node identifier for a node with a resets property
- `idx` – logical index into resets property
- `cell` – lowercase-and-underscores cell name

**Returns**

the cell value at index “idx”

**DT_RESET_CELL_BY_NAME** (node_id, name, cell)

Get a reset specifier’s cell value by name.

Example devicetree fragment:
reset: reset-controller@... {
    compatible = "vnd,reset";
    #reset-cells = <1>;
};

n: node {
    resets = <&reset 10>;
    reset-names = "alpha";
};

Bindings fragment for the vnd,reset compatible:
reset-cells:
  - id

Example usage:
DT_RESET_CELL_BY_NAME(DT_NODELABEL(n), alpha, id) // 10

See also:

DT_PHA_BY_NAME()

Parameters

• node_id – node identifier for a node with a resets property
• name – lowercase-and-underscores name of a resets element as defined by the node's reset-names property
• cell – lowercase-and-underscores cell name

Returns

the cell value in the specifier at the named element

DT_RESET_CELL(node_id, cell)
Equivalent to DT_RESET_CELL_BY_IDX(node_id, 0, cell)

See also:

DT_RESET_CELL_BY_IDX()

Parameters

• node_id – node identifier for a node with a resets property
• cell – lowercase-and-underscores cell name

Returns

the cell value at index 0

DT_INST_RESET_CTLR_BY_IDX(inst, idx)
Get the node identifier for the controller phandle from a “resets” phandle-array property at an index.

See also:

DT_RESET_CTLR_BY_IDX()

Parameters

• inst – instance number
• idx – logical index into “resets”

**Returns**
the node identifier for the reset controller referenced at index “idx”

`DT_INST_RESET_CTLR(inst)`
Equivalent to `DT_INST_RESET_CTLR_BY_IDX(inst, 0)`

**See also:**

`DT_RESET_CTLR()`

**Parameters**
• inst – instance number

**Returns**
a node identifier for the reset controller at index 0 in “resets”

`DT_INST_RESET_CTLR_BY_NAME(inst, name)`
Get the node identifier for the controller phandle from a resets phandle-array property by name.

**See also:**

`DT_RESET_CTLR_BY_NAME()`

**Parameters**
• inst – instance number
• name – lowercase-and-underscores name of a resets element as defined by the node’s reset-names property

**Returns**
the node identifier for the reset controller referenced by the named element

`DT_INST_RESET_CELL_BY_IDX(inst, idx, cell)`
Get a DT_DRV_COMPAT instance’s reset specifier’s cell value at an index.

**See also:**

`DT_RESET_CELL_BY_IDX()`

**Parameters**
• inst – DT_DRV_COMPAT instance number
• idx – logical index into resets property
• cell – lowercase-and-underscores cell name

**Returns**
the cell value at index “idx”
DT_INST_RESET_CELL_BY_NAME(inst, name, cell)
Get a DT_DRV_COMPAT instance's reset specifier's cell value by name.

See also:

*DT_RESET_CELL_BY_NAME()*

Parameters

- inst – DT_DRV_COMPAT instance number
- name – lowercase-and-underscores name of a resets element as defined by the node's reset-names property
- cell – lowercase-and-underscores cell name

Returns
the cell value in the specifier at the named element

DT_INST_RESET_CELL(inst, cell)
Equivalent to DT_INST_RESET_CELL_BY_IDX(inst, 0, cell)

Parameters

- inst – DT_DRV_COMPAT instance number
- cell – lowercase-and-underscores cell name

Returns
the value of the cell inside the specifier at index 0

DT_RESET_ID_BY_IDX(node_id, idx)
Get a Reset Controller specifier's id cell at an index.

This macro only works for Reset Controller specifiers with cells named “id”. Refer to the node's binding to check if necessary.

Example devicetree fragment:

```plaintext
reset: reset-controller@... {
    compatible = "vnd,reset";
    #reset-cells = <1>;
};

n: node {
    resets = <&reset 10>;
};
```

Bindings fragment for the vnd,reset compatible:

```plaintext
reset-cells:
- id
```

Example usage:

```plaintext
DT_RESET_ID_BY_IDX(DT_NODELABEL(n), 0) // 10
```

See also:

*DT_PHA_BY_IDX()*

Parameters

- node_id – node identifier
- idx – logical index into “resets”
Returns
the id cell value at index “idx”

`DT_RESET_ID(node_id)`
Equivalent to `DT_RESET_ID_BY_IDX(node_id, 0)`

See also:
`DT_RESET_ID_BY_IDX()`

Parameters
• `node_id` – node identifier

Returns
the id cell value at index 0

`DT_INST_RESET_ID_BY_IDX(inst, idx)`
Get a DT_DRV_COMPAT instance's Reset Controller specifier's id cell value at an index.

See also:
`DT_RESET_ID_BY_IDX()`

Parameters
• `inst` – DT_DRV_COMPAT instance number
  • `idx` – logical index into “resets”

Returns
the id cell value at index “idx”

`DT_INST_RESET_ID(inst)`
Equivalent to `DT_INST_RESET_ID_BY_IDX(inst, 0)`

See also:
`DT_INST_RESET_ID_BY_IDX()`

Parameters
• `inst` – DT_DRV_COMPAT instance number

Returns
the id cell value at index 0

**SPI** These conveniences may be used for nodes which describe either SPI controllers or devices, depending on the case.

`group devicetree-spi`
Defines

**DT_SPI_HAS_CS_GPIOS**(spi)

Does a SPI controller node have chip select GPIOs configured?

SPI bus controllers use the “cs-gpios” property for configuring chip select GPIOs. Its value is a phandle-array which specifies the chip select lines.

Example devicetree fragment:

```plaintext
spi1: spi@... {
    compatible = "vnd_spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
              <&gpio2 20 GPIO_ACTIVE_LOW>;
};
spi2: spi@... {
    compatible = "vnd_spi";
};
```

Example usage:

```plaintext
DT_SPI_HAS_CS_GPIOS(DT_NODELABEL(spi1)) // 1
DT_SPI_HAS_CS_GPIOS(DT_NODELABEL(spi2)) // 0
```

**Parameters**

- **spi** – a SPI bus controller node identifier

**Returns**

1 if “spi” has a cs-gpios property, 0 otherwise

---

**DT_SPI_NUM_CS_GPIOS**(spi)

Number of chip select GPIOs in a SPI controller's cs-gpios property.

Example devicetree fragment:

```plaintext
spi1: spi@... {
    compatible = "vnd_spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
              <&gpio2 20 GPIO_ACTIVE_LOW>;
};
spi2: spi@... {
    compatible = "vnd_spi";
};
```

Example usage:

```plaintext
DT_SPI_NUM_CS_GPIOS(DT_NODELABEL(spi1)) // 2
DT_SPI_NUM_CS_GPIOS(DT_NODELABEL(spi2)) // 0
```

**Parameters**

- **spi** – a SPI bus controller node identifier

**Returns**

Logical length of spi's cs-gpios property, or 0 if “spi” doesn't have a cs-gpios property
DT_SPI_DEV_HAS_CS_GPIOS(spi_dev)

Does a SPI device have a chip select line configured? Example devicetree fragment:

```
spi1: spi@... {
    compatible = "vnd,spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>, <&gpio2 20 GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };

    b: spi-dev-b@1 {
        reg = <1>;
    };
};
spi2: spi@... {
    compatible = "vnd,spi";
    c: spi-dev-c@0 {
        reg = <0>;
    };
};
```

Example usage:

```
DT_SPI_DEV_HAS_CS_GPIOS(DT_NODELABEL(a)) // 1
DT_SPI_DEV_HAS_CS_GPIOS(DT_NODELABEL(b)) // 1
DT_SPI_DEV_HAS_CS_GPIOS(DT_NODELABEL(c)) // 0
```

Parameters

- `spi_dev` – a SPI device node identifier

Returns

1 if `spi_dev`'s bus node `DT_BUS(spi_dev)` has a chip select pin at index `DT_REG_ADDR(spi_dev)`, 0 otherwise

DT_SPI_DEV_CS_GPIOS_CTRLR(spi_dev)

Get a SPI device's chip select GPIO controller's node identifier.

Example devicetree fragment:

```
gpio1: gpio@... { ... };
gpio2: gpio@... { ... };
spi@... {
    compatible = "vnd,spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>, <&gpio2 20 GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };

    b: spi-dev-b@1 {
        reg = <1>;
    };
};
```
Example usage:

```
DT_SPI_DEV_CS_GPIOS_CTLR(DT_NODELABEL(a)) // DT_NODELABEL(gpio1)
DT_SPI_DEV_CS_GPIOS_CTLR(DT_NODELABEL(b)) // DT_NODELABEL(gpio2)
```

**Parameters**

- `spi_dev` – a SPI device node identifier

**Returns**

node identifier for `spi_dev`'s chip select GPIO controller

**DT_SPI_DEV_CS_GPIOS_PIN(spi_dev)**

Get a SPI device's chip select GPIO pin number.

It's an error if the GPIO specifier for `spi_dev`'s entry in its bus node's cs-gpios property has no pin cell.

Example devicetree fragment:

```
spi1: spi@... {
    compatible = "vnd,spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
              <&gpio2 20 GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };

    b: spi-dev-b@1 {
        reg = <1>;
    };
};
```

Example usage:

```
DT_SPI_DEV_CS_GPIOS_PIN(DT_NODELABEL(a)) // 10
DT_SPI_DEV_CS_GPIOS_PIN(DT_NODELABEL(b)) // 20
```

**Parameters**

- `spi_dev` – a SPI device node identifier

**Returns**

pin number of `spi_dev`'s chip select GPIO

**DT_SPI_DEV_CS_GPIOS_FLAGS(spi_dev)**

Get a SPI device's chip select GPIO flags.

Example devicetree fragment:

```
spi1: spi@... {
    compatible = "vnd,spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };

};
```

Example usage:
If the GPIO specifier for spi_dev's entry in its bus node's cs-gpios property has no flags cell, this expands to zero.

**Parameters**
- spi_dev – a SPI device node identifier

**Returns**
flags value of spi_dev's chip select GPIO specifier, or zero if there is none

`DT_INST_SPI_DEV_HAS_CS_GPIOS(inst)`
Equivalent to `DT_SPI_DEV_HAS_CS_GPIOS(DT_DRV_INST(inst))`.

**See also:**
`DT_SPI_DEV_HAS_CS_GPIOS()`

**Parameters**
- inst – DT_DRV_COMPAT instance number

**Returns**
1 if the instance's bus has a CS pin at index `DT_INST_REG_ADDR(inst)`, 0 otherwise

`DT_INST_SPI_DEV_CS_GPIOS_CTLR(inst)`
Get GPIO controller node identifier for a SPI device instance This is equivalent to `DT_SPI_DEV_CS_GPIOS_CTLR(DT_DRV_INST(inst))`.

**See also:**
`DT_SPI_DEV_CS_GPIOS_CTLR()`

**Parameters**
- inst – DT_DRV_COMPAT instance number

**Returns**
node identifier for instance's chip select GPIO controller

`DT_INST_SPI_DEV_CS_GPIOS_PIN(inst)`
Equivalent to `DT_SPI_DEV_CS_GPIOS_PIN(DT_DRV_INST(inst))`.

**See also:**
`DT_SPI_DEV_CS_GPIOS_PIN()`

**Parameters**
- inst – DT_DRV_COMPAT instance number

**Returns**
pin number of the instance's chip select GPIO
DT_INST_SPI_DEV_CS_GPIOS_FLAGS(inst)

\[ DT_SPI_DEV_CS_GPIOS_FLAGS(DT_DRV_INST(inst)) \].

See also:

\[ DT_SPI_DEV_CS_GPIOS_FLAGS() \]

Parameters

- \( \text{inst} \) – DT_DRV_COMPAT instance number

Returns

flags value of the instance's chip select GPIO specifier, or zero if there is none

**Chosen nodes**  The special /chosen node contains properties whose values describe system-wide settings. The \( \text{DT_CHOSEN()} \) macro can be used to get a node identifier for a chosen node.

**group devicetree-generic-chosen**

**Defines**

**DT_CHOSEN(prop)**

Get a node identifier for a /chosen node property.

This is only valid to call if \( \text{DT_HAS_CHOSEN(prop)} \) is 1.

Parameters

- \( \text{prop} \) – lowercase-and-underscores property name for the /chosen node

Returns

a node identifier for the chosen node property

**DT_HAS_CHOSEN(prop)**

Test if the devicetree has a /chosen node.

Parameters

- \( \text{prop} \) – lowercase-and-underscores devicetree property

Returns

1 if the chosen property exists and refers to a node, 0 otherwise

**Zephyr-specific chosen nodes**  The following table documents some commonly used Zephyr-specific chosen nodes.

Sometimes, a chosen node's label property will be used to set the default value of a Kconfig option which in turn configures a hardware-specific device. This is usually for backwards compatibility in cases when the Kconfig option predates devicetree support in Zephyr. In other cases, there is no Kconfig option, and the devicetree node is used directly in the source code to select a device.

<table>
<thead>
<tr>
<th>Property</th>
<th>Purpose</th>
</tr>
</thead>
<tbody>
<tr>
<td>zephyr,bt-c2h-uart</td>
<td>Selects the UART used for host communication in the bluetooth-hci-uart-sample</td>
</tr>
<tr>
<td>zephyr,bt-mon-uart</td>
<td>Sets UART device used for the Bluetooth monitor logging</td>
</tr>
</tbody>
</table>

continues on next page
<table>
<thead>
<tr>
<th>Property</th>
<th>Purpose</th>
</tr>
</thead>
<tbody>
<tr>
<td>zephyr,bt_uart</td>
<td>Sets UART device used by Bluetooth</td>
</tr>
<tr>
<td>zephyr,canbus</td>
<td>Sets the default CAN controller</td>
</tr>
<tr>
<td>zephyr,ccm</td>
<td>Core-Coupled Memory node on some STM32 SoCs</td>
</tr>
<tr>
<td>zephyr,code-partition</td>
<td>Flash partition that the Zephyr image's text section should be linked into</td>
</tr>
<tr>
<td>zephyr,console</td>
<td>Sets UART device used by console driver</td>
</tr>
<tr>
<td>zephyr,display</td>
<td>Sets the default display controller</td>
</tr>
<tr>
<td>zephyr,keyboard-scan</td>
<td>Sets the default keyboard scan controller</td>
</tr>
<tr>
<td>zephyr,dtcm</td>
<td>Data Tightly Coupled Memory node on some Arm SoCs</td>
</tr>
<tr>
<td>zephyr,entropy</td>
<td>A device which can be used as a system-wide entropy source</td>
</tr>
<tr>
<td>zephyr,flash</td>
<td>A node whose reg is sometimes used to set the defaults for CONFIG_FLASH_BASE_ADDRESS and CONFIG_FLASH_SIZE</td>
</tr>
<tr>
<td>zephyr,flash-controller</td>
<td>The node corresponding to the flash controller device for the zephyr, flash node</td>
</tr>
<tr>
<td>zephyr,gdbstub-uart</td>
<td>Sets UART device used by the GDB stub subsystem</td>
</tr>
<tr>
<td>zephyr,ieee802154</td>
<td>Used by the networking subsystem to set the IEEE 802.15.4 device</td>
</tr>
<tr>
<td>zephyr,ipc</td>
<td>Used by the OpenAMP subsystem to specify the inter-process communication (IPC) device</td>
</tr>
<tr>
<td>zephyr,ipc_shm</td>
<td>A node whose reg is used by the OpenAMP subsystem to determine the base address and size of the shared memory (SHM) usable for interprocess-communication (IPC)</td>
</tr>
<tr>
<td>zephyr,itmcm</td>
<td>Instruction Tightly Coupled Memory node on some Arm SoCs</td>
</tr>
<tr>
<td>zephyr,log-uart</td>
<td>Sets the UART device(s) used by the logging subsystem's UART backend. If defined, the UART log backend would output to the devices listed in this node.</td>
</tr>
<tr>
<td>zephyr,ocm</td>
<td>On-chip memory node on Xilinx Zynq-7000 and ZynqMP SoCs</td>
</tr>
<tr>
<td>zephyr,osdp-uart</td>
<td>Sets UART device used by OSDP subsystem</td>
</tr>
<tr>
<td>zephyr,ot-uart</td>
<td>Used by the OpenThread to specify UART device for Spinel protocol</td>
</tr>
<tr>
<td>zephyr,pcie-controller</td>
<td>The node corresponding to the PCIe Controller</td>
</tr>
<tr>
<td>zephyr,ppp-uart</td>
<td>Sets UART device used by PPP</td>
</tr>
<tr>
<td>zephyr,settings-partition</td>
<td>Fixed partition node. If defined this selects the partition used by the NVS and FCB settings backends.</td>
</tr>
<tr>
<td>zephyr,shell-uart</td>
<td>Sets UART device used by serial shell backend</td>
</tr>
<tr>
<td>zephyr,sram</td>
<td>A node whose reg sets the base address and size of SRAM memory available to the Zephyr image, used during linking</td>
</tr>
<tr>
<td>zephyr,tracing-uart</td>
<td>Sets UART device used by tracing subsystem</td>
</tr>
<tr>
<td>zephyr,uart-mcumgr</td>
<td>UART used for Device Management</td>
</tr>
<tr>
<td>zephyr,uart-pipe</td>
<td>Sets UART device used by serial pipe driver</td>
</tr>
<tr>
<td>zephyr,usb-device</td>
<td>USB device node. If defined and has a vbus–gpios property, these will be used by the USB subsystem to enable/disable VBUS</td>
</tr>
</tbody>
</table>

**Bindings index**

This page documents the available devicetree bindings. See *Devicetree bindings* for an introduction to the Zephyr bindings file format.

**Vendor index**  This section contains an index of hardware vendors. Click on a vendor's name to go to the list of bindings for that vendor.

- Generic or vendor-independent
- Advanced Micro Devices (AMD), Inc. (amd)
5.2. Devicetree
• Himax Technologies, Inc. (himax)
• Hitachi Ltd. (hit)
• Holtek Semiconductor, Inc. (holtek)
• Honeywell (honeywell)
• HOPERF Microelectronics Co. Ltd (hoperf)
• Hynitron (hynitron)
• ILI Technology Corporation (ILITEK) (ilitek)
• Imagination Technologies Ltd. (formerly MIPS Technologies Inc.) (mti)
• Infineon Technologies (infineon)
• Integrated Silicon Solutions Inc. (issi)
• Intel Corporation (intel)
• Intersil (isil)
• InvenSense Inc. (invensense)
• Inventek Systems (inventek)
• Isentek Inc. (isentek)
• ITE Tech. Inc. (ite)
• JEDEC Solid State Technology Association (jedec)
• Kvaser (kvaser)
• Lattice Semiconductor (lattice)
• Linaro Limited (linaro)
• Linear Technology Corporation (lltc)
• LiteOn OptoElectronics (ltr)
• LiteX SoC builder (litex)
• lowRISC Community Interest Company (lowrisc)
• M5Stack (m5stack)
• Maxim Integrated Products (maxim)
• Measurement Specialties (meas)
• MEMSIC Inc. (memsic)
• Micro:bit Educational Foundation (microbit)
• Microchip Technology Inc. (microchip)
• Micron Technology Inc. (micron)
• Motorola, Inc. (motorola)
• Murata Manufacturing Co., Ltd. (murata)
• Nordic Semiconductor (nordic)
• Noritake Co., Inc. Electronics Division (noritake)
• Nuclei System Technology (nuclei)
• Nuvoton Technology Corporation (nuvoton)
• NXP Semiconductors (nxp)
• OmniVision Technologies (ovti)
5.2. Devicetree
• Standard Microsystems Corporation (smsc)
• StarFive Technology Co. Ltd. (starfive)
• STMicroelectronics (st)
• Synopsys, Inc. (snps)
• Synopsys, Inc. (formerly ARC International PLC) (arc)
• TDK Corporation. (tdk)
• Telink Semiconductor (telink)
• Telit Cinterion (telit)
• Texas Instruments (ti)
• u-blox (u-blox)
• UltraChip Inc. (ultrachip)
• Vishay Intertechnology, Inc (vishay)
• Wistron NeWeb Corporation (wnc)
• WIZnet Co., Ltd. (wiznet)
• Worldsemi Co., Limited (worldsemi)
• Würth Elektronik GmbH. (we)
• X-Powers (x-powers)
• Xen Hypervisor (xen)
• Xilinx (xlnx)
• Zephyr-specific binding (zephyr)
• Zhengzhou Winsen Electronics Technology Co., Ltd. (winsen)
• Unknown vendor

Bindings by vendor  This section contains available bindings, grouped by vendor. Within each group, bindings are listed by the “compatible” property they apply to, like this:

Vendor name (vendor prefix)

• <compatible-A>
• <compatible-B> (on <bus-name> bus)
• <compatible-C>
• ...

The text “(on <bus-name> bus)” appears when bindings may behave differently depending on the bus the node appears on. For example, this applies to some sensor device nodes, which may appear as children of either I2C or SPI bus nodes.

Generic or vendor-independent

• dtbinding_adafruit_feather_header
• dtbinding_ambiq_header
• dtbinding_analog_axis
• dtbinding_arduino_header_r3
• dtbinding_arduino_mkr_header
5.2. Devicetree
• dtbinding_power_domain_gpio
• dtbinding_power_domain_gpio_monitor
• dtbinding_pwm_clock
• dtbinding_pwm_leds
• dtbinding_raspberrypi_40pins_header
• dtbinding_regulator_fixed
• dtbinding_regulator_gpio
• dtbinding_sample_controller
• dtbinding_shared_irq
• dtbinding_soc_nv_flash
• dtbinding_st_morpho_header
• dtbinding_swj_connector
• dtbinding_syscon
• dtbinding_vnd_gpio_enable_disable_interrupt
• dtbinding_usb_audio
• dtbinding_usb_audio_feature_volume
• dtbinding_usb_audio_hp
• dtbinding_usb_audio_hs
• dtbinding_usb_audio_mic
• dtbinding_usb_c_connector
• dtbinding_usb_nop_xceiv
• dtbinding_usb_ulpi_phy
• dtbinding_vexriscv_intc0
• dtbinding_voltage_divider

Advanced Micro Devices (AMD), Inc. (amd)
• dtbinding_amd_sb_tsi

Altera Corp. (altr)
• dtbinding_altr_jtag_uart
• dtbinding_altr_msgdma
• dtbinding_altr_nios2_i2c
• dtbinding_altr_nios2_qspi
• dtbinding_altr_nios2_qspi_nor
• dtbinding_altr_nios2f
• dtbinding_altr_pio_1.0
• dtbinding_altr_uart
Ambiq Micro, Inc. (ambiq)
- dtbinding_ambiq_am1805
- dtbinding_ambiq_apollo4_pinctrl
- dtbinding_ambiq_bt_hci_spi
- dtbinding_ambiq_clkctrl
- dtbinding_ambiq_counter
- dtbinding_ambiq_flash_controller
- dtbinding_ambiq_gpio
- dtbinding_ambiq_gpio_bank
- dtbinding_ambiq_i2c
- dtbinding_ambiq_mspi
- dtbinding_ambiq_pwrctrl
- dtbinding_ambiq_spi
- dtbinding_ambiq_stimer
- dtbinding_ambiq_uart
- dtbinding_ambiq_watchdog

AMS AG (ams)
- dtbinding_ams_as5600
- dtbinding_ams_as6212
- dtbinding_ams_ccs811
- dtbinding_ams_ens210
- dtbinding_ams_iaqcore
- dtbinding_ams_tcs3400
- dtbinding_ams_tmd2620
- dtbinding_ams tsl2540
- dtbinding_ams tsl2561

Analog Devices, Inc. (adi)
- dtbinding_adi ad5592
- dtbinding_adi ad5592_adc
- dtbinding_adi ad5592_dac
- dtbinding_adi ad5592_gpio
- dtbinding_adi ad5628
- dtbinding_adi ad5648
- dtbinding_adi ad5668
- dtbinding_adi ad5672
- dtbinding_adi ad5674
- dtbinding_adi ad5676
• dtbinding_adi_ad5679
• dtbinding_adi_ad5684
• dtbinding_adi_ad5686
• dtbinding_adi_ad5687
• dtbinding_adi_ad5689
• dtbinding_adi_adin1110
• dtbinding_adi_adin2111
• dtbinding_adi_adin2111_mdio
• dtbinding_adi_adin2111_phy
• dtbinding_adi_adltc2990
• dtbinding_adi_adp5360
• dtbinding_adi_adp5360_regulator
• dtbinding_adi_adt7310
• dtbinding_adi_adt7420
• dtbinding_adi_adxl345_i2c
• dtbinding_adi_adxl345_spi
• dtbinding_adi_adxl362
• dtbinding_adi_adxl367_i2c
• dtbinding_adi_adxl367_spi
• dtbinding_adi_adxl372_i2c
• dtbinding_adi_adxl372_spi

Andes Technology Corporation (andestech)
• dtbinding_andes_andescore_v5
• dtbinding_andestech_atcdmac300
• dtbinding_andestech_atcgpio100
• dtbinding_andestech_atciic100
• dtbinding_andestech_atcpit100
• dtbinding_andestech.atcspi200
• dtbinding_andestech_atcwdt200
• dtbinding_andestech_machine_timer
• dtbinding_andestech_plic_sw
• dtbinding_andestech_qspi_nor

Apa Electronic Co., Ltd (apa)
• dtbinding_apa_apa102

Aptina Imaging (aptina)
• dtbinding_aptina_mt9m114
Arduino (arduino)
  - dtbinding_arduino_uno_adc

ARM Ltd. (arm)
  - dtbinding_arm_armv6m_mpu
  - dtbinding_arm_armv6m_systick
  - dtbinding_arm_armv7m_itm
  - dtbinding_arm_armv7m_mpu
  - dtbinding_arm_armv7m_systick
  - dtbinding_arm_armv8_timer
  - dtbinding_arm_armv8.1m_mpu
  - dtbinding_arm_armv8.1m_systick
  - dtbinding_arm_armv8m_itm
  - dtbinding_arm_armv8m_mpu
  - dtbinding_arm_armv8m_systick
  - dtbinding_arm_beetle_syscon
  - dtbinding_arm_cmsdk_dtimer
  - dtbinding_arm_cmsdk_gpio
  - dtbinding_arm_cmsdk_timer
  - dtbinding_arm_cmsdk_uart
  - dtbinding_arm_cmsdk_watchdog
  - dtbinding_arm_cortex_a53
  - dtbinding_arm_cortex_a55
  - dtbinding_arm_cortex_a72
  - dtbinding_arm_cortex_a76
  - dtbinding_arm_cortex_m0
  - dtbinding_arm_cortex_m0+
  - dtbinding_arm_cortex_m1
  - dtbinding_arm_cortex_m23
  - dtbinding_arm_cortex_m3
  - dtbinding_arm_cortex_m33
  - dtbinding_arm_cortex_m33f
  - dtbinding_arm_cortex_m4
  - dtbinding_arm_cortex_m4f
  - dtbinding_arm_cortex_m7
  - dtbinding_arm_cortex_r4
  - dtbinding_arm_cortex_r4f
  - dtbinding_arm_cortex_r5
  - dtbinding_arm_cortex_r52

5.2. Devicetree
• dtbinding_arm_cortex_r5f
• dtbinding_arm_cortex_r7
• dtbinding_arm_cortex_r82
• dtbinding_arm_cryptocell_310
• dtbinding_arm_cryptocell_312
• dtbinding_arm_dma_pl330
• dtbinding_arm_dtcmap
• dtbinding_arm_ethos_u
• dtbinding_arm_gic
• dtbinding_arm_gic_v1
• dtbinding_arm_gic_v2
• dtbinding_arm_gic_v3
• dtbinding_arm_gic_v3_its
• dtbinding_arm_itcmap
• dtbinding_arm_mhup
• dtbinding_arm_mps2_fpgaio_gpio
• dtbinding_arm_mps3_fpgaio_gpio
• dtbinding_arm_pl011
• dtbinding_arm_pl022
• dtbinding_arm_psci_0.2
• dtbinding_arm_psci_1.1
• dtbinding_arm_sbsa_uart
• dtbinding_arm_scc
• dtbinding_arm_v6m_nvic
• dtbinding_arm_v7m_nvic
• dtbinding_arm_v8.1m_nvic
• dtbinding_arm_v8m_nvic
• dtbinding_arm_versatile_i2c

Asahi Kasei Corp. (asahi-kasei)
• dtbinding_asahi_kasei_ak8975
• dtbinding_asahi_kasei_akm09918c

ASMedia Technology Inc. (asmedia)
• dtbinding_asmedia_asm2364

ASPEED Technology Inc. (aspeed)
• dtbinding_aspeed_ast10x0_clock
• dtbinding_aspeed_ast10x0_reset
Atmel Corporation (atmel)
- dtbinding_atmel_at24
- dtbinding_atmel_24mac402
- dtbinding_atmel_at25
- dtbinding_atmel_at45
- dtbinding_atmel_ataes132a
- dtbinding_atmel_rf2xx
- dtbinding_atmel_sam_adc
- dtbinding_atmel_sam_afec
- dtbinding_atmel_sam_can
- dtbinding_atmel_sam_dac
- dtbinding_atmel_sam_flash
- dtbinding_atmel_sam_flash_controller
- dtbinding_atmel_sam_gmac
- dtbinding_atmel_sam_gpio
- dtbinding_atmel_sam_hsmci
- dtbinding_atmel_sam_i2c_twi
- dtbinding_atmel_sam_i2c_twihs
- dtbinding_atmel_sam_i2c_twim
- dtbinding_atmel_sam_mdio
- dtbinding_atmel_sam_pinctrl
- dtbinding_atmel_sam_pmc
- dtbinding_atmel_sam_pwm
- dtbinding_atmel_sam_rstc
- dtbinding_atmel_sam_rtc
- dtbinding_atmel_sam_smc
- dtbinding_atmel_sam_spi
- dtbinding_atmel_sam_ssc
- dtbinding_atmel_sam_supc
- dtbinding_atmel_sam_tc
- dtbinding_atmel_sam_tc_qdec
- dtbinding_atmel_sam_trng
- dtbinding_atmel_sam_uart
- dtbinding_atmel_sam_usart
- dtbinding_atmel_sam_usbc
- dtbinding_atmel_sam_usbhs
- dtbinding_atmel_sam_watchdog
- dtbinding_atmel_sam_xdmac
- dtbinding_atmel_sam0_adc
• dtbinding_atmel_sam0_can
• dtbinding_atmel_sam0_dac
• dtbinding_atmel_sam0_dmac
• dtbinding_atmel_sam0_eic
• dtbinding_atmel_sam0_gmac
• dtbinding_atmel_sam0_gpio
• dtbinding_atmel_sam0_i2c
• dtbinding_atmel_sam0_id
• dtbinding_atmel_sam0_nvmctrl
• dtbinding_atmel_sam0_pinctrl
• dtbinding_atmel_sam0_pinmux
• dtbinding_atmel_sam0_RTC
• dtbinding_atmel_sam0_sercom
• dtbinding_atmel_sam0_spi
• dtbinding_atmel_sam0_tc32
• dtbinding_atmel_sam0_tcc_pwm
• dtbinding_atmel_sam0_uart
• dtbinding_atmel_sam0_usb
• dtbinding_atmel_sam0_watchdog
• dtbinding_atmel_sam4l_flashcalw_controller
• dtbinding_atmel_sam4l_gpio
• dtbinding_atmel_sam4l_uid
• dtbinding_atmel_samc2x_gclk
• dtbinding_atmel_samc2x_mclk
• dtbinding_atmel_samd2x_gclk
• dtbinding_atmel_samd2x_pm
• dtbinding_atmel_samd5x_gclk
• dtbinding_atmel_samd5x_mclk
• dtbinding_atmel_saml2x_gclk
• dtbinding_atmel_saml2x_mclk
• dtbinding_atmel_winc1500

Avago Technologies (avago)
• dtbinding_avago_apds9960

Bosch Sensortec GmbH (bosch)
• dtbinding_bosch_bma280
• dtbinding_bosch_bma4xx_i2c
• dtbinding_bosch_bma4xx_spi
• dtbinding_bosch_bmc150_magn
• dtbinding_bosch_bme280_i2c
• dtbinding_bosch_bme280_spi
• dtbinding_bosch_bme680_i2c
• dtbinding_bosch_bme680_spi
• dtbinding_bosch_bmg160
• dtbinding_bosch_bmi08x_accel_i2c
• dtbinding_bosch_bmi08x_accel_spi
• dtbinding_bosch_bmi08x_gyro_i2c
• dtbinding_bosch_bmi08x_gyro_spi
• dtbinding_bosch_bmi160_i2c
• dtbinding_bosch_bmi160_spi
• dtbinding_bosch_bmi270_i2c
• dtbinding_bosch_bmi270_spi
• dtbinding_bosch_bmi270
• dtbinding_bosch_bmi323
• dtbinding_bosch_bmm150_i2c
• dtbinding_bosch_bmm150_spi
• dtbinding_bosch_bmp388_i2c
• dtbinding_bosch_bmp388_spi
• dtbinding_bosch_bmp581

**Broadcom Corporation (brcm)**
• dtbinding_brcm_bcm2711_aux_uart
• dtbinding_brcm_bcm2711_gpio
• dtbinding_brcm_iproc_pax_dma_v1
• dtbinding_brcm_iproc_pax_dma_v2
• dtbinding_brcm_iproc_pcie_ep

**Cadence Design Systems Inc. (cdns)**
• dtbinding_cdns_i3c
• dtbinding_cdns_nand
• dtbinding_cdns_qspi_nor
• dtbinding_cdns_sdhc
• dtbinding_cdns_tensilica_xtensa_lx3
• dtbinding_cdns_tensilica_xtensa_lx4
• dtbinding_cdns_tensilica_xtensa_lx6
• dtbinding_cdns_tensilica_xtensa_lx7
• dtbinding_cdns_uart
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- dtbinding_cdns_xtensa_core_intc

**Cirrus Logic, Inc. (cirrus)**
- dtbinding_cirrus_cs47l63

**Cypress Semiconductor Corporation (cypress)**
- dtbinding_cypress_cy8c95xx_gpio
- dtbinding_cypress_cy8c95xx_gpio_port
- dtbinding_cypress_psoc6_flash_controller
- dtbinding_cypress_psoc6_gpio
- dtbinding_cypress_psoc6_hsiom
- dtbinding_cypress_psoc6_intmux
- dtbinding_cypress_psoc6_intmux_ch
- dtbinding_cypress_psoc6_pinctrl
- dtbinding_cypress_psoc6_spi
- dtbinding_cypress_psoc6_uart
- dtbinding_cypress_psoc6_uid

**DFRobot (dfrobot)**
- dtbinding_dfrobot_a01nyub

**Digilent, Inc. (digilent)**
- dtbinding_digilent_pmod

**Diodes Incorporated (diodes)**
- dtbinding_diodes_pi3usb9201

**Efinix Inc (efinix)**
- dtbinding_efinix_sapphire_gpio
- dtbinding_efinix_sapphire_timer0
- dtbinding_efinix_sapphire_uart0
- dtbinding_efinix_vexriscv_sapphire

**EPCOS AG (epcos)**
- dtbinding_epcos_b57861s0103a039
Espressif Systems (espressif)
  • dtbinding_espressif_esp_at
  • dtbinding_espressif_esp32_adc
  • dtbinding_espressif_esp32_dac
  • dtbinding_espressif_esp32_eth
  • dtbinding_espressif_esp32_flash_controller
  • dtbinding_espressif_esp32_gdma
  • dtbinding_espressif_esp32_gpio
  • dtbinding_espressif_esp32_i2c
  • dtbinding_espressif_esp32_intc
  • dtbinding_espressif_esp32_ipm
  • dtbinding_espressif_esp32_ledc
  • dtbinding_espressif_esp32_mcpwm
  • dtbinding_espressif_esp32_mdio
  • dtbinding_espressif_esp32_pcnt
  • dtbinding_espressif_esp32_pinctrl
  • dtbinding_espressif_esp32_RTC
  • dtbinding_espressif_esp32_RTC_timer
  • dtbinding_espressif_esp32_spi
  • dtbinding_espressif_esp32_systick
  • dtbinding_espressif_esp32_temp
  • dtbinding_espressif_esp32_timer
  • dtbinding_espressif_esp32_touch_sensor
  • dtbinding_espressif_esp32_trng
  • dtbinding_espressif_esp32_twai
  • dtbinding_espressif_esp32_uart
  • dtbinding_espressif_esp32_usb_serial
  • dtbinding_espressif_esp32_watchdog
  • dtbinding_espressif_esp32_wifi
  • dtbinding_espressif_riscv

Fairchild Semiconductor (fcs)
  • dtbinding_fcs_fxl6408

Feature Integration Technology Inc. (fintek)
  • dtbinding_fintek_f75303

FocalTech Systems Co.,Ltd (focaltech)
  • dtbinding_focaltech_ft5336

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Freescale Semiconductor (fsl)
  • dtbinding_fsl_imx21_i2c
  • dtbinding_fsl_imx27_pwm

Fujitsu Ltd. (fujitsu)
  • dtbinding_fujitsu_mb85rcxx

Future Technology Devices International Ltd. (ftdi)
  • dtbinding_ftdi_ft800

Gaisler (gaisler)
  • dtbinding_gaisler_apbuart
  • dtbinding_gaisler_gptimer
  • dtbinding_gaisler_irqmp
  • dtbinding_gaisler_leon3
  • dtbinding_gaisler_spimctrl

Galaxycore, Inc. (galaxycore)
  • dtbinding_galaxycore_gc9x01x

Gas Sensing Solutions Ltd. (gss)
  • dtbinding_gss_explorerir_m

GigaDevice Semiconductor (gd)
  • dtbinding_gd_gd32_adc
  • dtbinding_gd_gd32_afio
  • dtbinding_gd_gd32_cctl
  • dtbinding_gd_gd32_dac
  • dtbinding_gd_gd32_dma
  • dtbinding_gd_gd32_dma_v1
  • dtbinding_gd_gd32_exti
  • dtbinding_gd_gd32_flash_controller
  • dtbinding_gd_gd32_fwdgt
  • dtbinding_gd_gd32_gpio
  • dtbinding_gd_gd32_i2c
  • dtbinding_gd_gd32_nv_flash_v1
  • dtbinding_gd_gd32_nv_flash_v2
  • dtbinding_gd_gd32_nv_flash_v3
  • dtbinding_gd_gd32_pinctrl_af
• dtbinding_gd_gd32_pinctrl_afio
• dtbinding_gd_gd32_pwm
• dtbinding_gd_gd32_rctl
• dtbinding_gd_gd32_rcu
• dtbinding_gd_gd32_spi
• dtbinding_gd_gd32_syscfg
• dtbinding_gd_gd32_timer
• dtbinding_gd_gd32_usart
• dtbinding_gd_gd32_wwdgt

GreeLed Electronic Ltd. (greeled)
• dtbinding_greeled_lpd8803
• dtbinding_greeled_lpd8806

Guangzhou Aosong Electronic Co., Ltd. (aosong)
• dtbinding_aosong_agss10
• dtbinding_aosong_dht

Hamamatsu Photonics K.K. (hamamatsu)
• dtbinding_hamamatsu_s11059

Hangzhou Grow Technology Co., Ltd. (hzgrow)
• dtbinding_hzgrow_r502a

Himax Technologies, Inc. (himax)
• dtbinding_himax_hx8394

Hitachi Ltd. (hit)
• dtbinding_hit_hd44780

Holtek Semiconductor, Inc. (holtek)
• dtbinding_holtek_ht16k33
• dtbinding_holtek_ht16k33_keysan

Honeywell (honeywell)
• dtbinding_honeywell_hmc5883l
• dtbinding_honeywell_mpr
• dtbinding_honeywell_sm351lt
HOPERF Microelectronics Co. Ltd (hoperf)
  • dtbinding_hoperf_hp206c
  • dtbinding_hoperf_th02

Hynitron (hynitron)
  • dtbinding_hynitron_cst816s

ILI Technology Corporation (ILITEK) (ilitek)
  • dtbinding_ilitek_ili9340
  • dtbinding_ilitek_ili9341
  • dtbinding_ilitek_ili9342c
  • dtbinding_ilitek_ili9488

Imagination Technologies Ltd. (formerly MIPS Technologies Inc.) (mti)
  • dtbinding_mti_cpu_intc

Infineon Technologies (infineon)
  • dtbinding_infineon_airoc_wifi
  • dtbinding_infineon_cat1_scb
  • dtbinding_infineon_cat1_sdhc_sdio
  • dtbinding_infineon_cat1_spi
  • dtbinding_infineon_cat1_uart
  • dtbinding_infineon_cat1_watchdog
  • dtbinding_infineon_cyw43xxx_bt_hci
  • dtbinding_infineon_dps310
  • dtbinding_infineon_tle9104
  • dtbinding_infineon_xmc4xxx_adc
  • dtbinding_infineon_xmc4xxx_can
  • dtbinding_infineon_xmc4xxx_can_node
  • dtbinding_infineon_xmc4xxx_ccu4_pwm
  • dtbinding_infineon_xmc4xxx_ccu8_pwm
  • dtbinding_infineon_xmc4xxx_dma
• dtbinding_infineon_xmc4xxx_ethernet
• dtbinding_infineon_xmc4xxx_flash_controller
• dtbinding_infineon_xmc4xxx_gpio
• dtbinding_infineon_xmc4xxx_i2c
• dtbinding_infineon_xmc4xxx_intc
• dtbinding_infineon_xmc4xxx_mdio
• dtbinding_infineon_xmc4xxx_nv_flash
• dtbinding_infineon_xmc4xxx_pinctrl
• dtbinding_infineon_xmc4xxx_spi
• dtbinding_infineon_xmc4xxx_temp
• dtbinding_infineon_xmc4xxx_uart
• dtbinding_infineon_xmc4xxx_watchdog

Integrated Silicon Solutions Inc. (issi)
• dtbinding_issi_is31fl3216a
• dtbinding_issi_is31fl3733

Intel Corporation (intel)
• dtbinding_intel_ace_art_counter
• dtbinding_intel_ace_intc
• dtbinding_intel_ace_rtc_counter
• dtbinding_intel_ace_timestamp
• dtbinding_intel_adsp_communication_widget
• dtbinding_intel_adsp_dfpmcch
• dtbinding_intel_adsp_dfpmccu
• dtbinding_intel_adsp_dmic_vss
• dtbinding_intel_adsp_gpdma
• dtbinding_intel_adsp_hda_dmic_cap
• dtbinding_intel_adsp_hda_host_in
• dtbinding_intel_adsp_hda_host_out
• dtbinding_intel_adsp_hda_link_in
• dtbinding_intel_adsp_hda_link_out
• dtbinding_intel_adsp_hda_ssp_cap
• dtbinding_intel_adsp_host_ipc
• dtbinding_intel_adsp_idc
• dtbinding_intel_adsp_imr
• dtbinding_intel_adsp_mailbox
• dtbinding_intel_adsp_mem_window
• dtbinding_intel_adsp_mtl_tlb
- dtbinding_intel_adsp_power_domain
- dtbinding_intel_adsp_sha
- dtbinding_intel_adsp_shim_clkctl
- dtbinding_intel_adsp_timer
- dtbinding_intel_adsp_tlb
- dtbinding_intel_adsp_watchdog
- dtbinding_intel_agilex_clock
- dtbinding_intel_agilex5_clock
- dtbinding_intel_alder_lake
- dtbinding_intel_alh_dai
- dtbinding_intel_apollo_lake
- dtbinding_intel_blinky_pwm
- dtbinding_intel_cavs_i2s
- dtbinding_intel_cavs_intc
- dtbinding_intel_dai_dmic
- dtbinding_intel_e1000
- dtbinding_intel_elkhart_lake
- dtbinding_intel_emmc_host
- dtbinding_intel_gpio
- dtbinding_intel_hda_dai
- dtbinding_intel_hpet
- dtbinding_intel_ibecc
- dtbinding_intel_ioapic
- dtbinding_intel_ish
- dtbinding_intel_lakemont
- dtbinding_intel_loapic
- dtbinding_intel_LPSS
- dtbinding_intel_IW_UART
- dtbinding_intel_multiboot_framebuffer
- dtbinding_intel_niosv
- dtbinding_intel_pch_smbus
- dtbinding_intel_penwell_spi
- dtbinding_intel_raptor_lake
- dtbinding_intel_sedi_gpio
- dtbinding_intel_sedi_i2c
- dtbinding_intel_sedi_ipm
- dtbinding_intel_sedi_spi
- dtbinding_intel_sedi_UART
- dtbinding_intel_sedi_dma
• dtbinding_intel_agilex_socfpga_sip_smc
• dtbinding_intel_socfpga_reset
• dtbinding_intel_ssp_dai
• dtbinding_intel_ssp_sspbase
• dtbinding_intel_tco_wdt
• dtbinding_intel_timeaware_gpio
• dtbinding_intel_vt_d
• dtbinding_intel_x86

Intersil (isil)
• dtbinding_isil_isl29035

InvenSense Inc. (invensense)
• dtbinding_invensense_icm42605
• dtbinding_invensense_icm42670
• dtbinding_invensense_icm42688
• dtbinding_invensense_icp10125
• dtbinding_invensense_mpu6050
• dtbinding_invensense_mpu9250

Inventek Systems (inventek)
• dtbinding_inventek_eswifi
• dtbinding_inventek_eswifi_uart

Isentek Inc. (isentek)
• dtbinding_isentek_ist8310

ITE Tech. Inc. (ite)
• dtbinding_ite_enhance_i2c
• dtbinding_ite_it82xx2_usb
• dtbinding_ite_it8xxx2_adc
• dtbinding_ite_it8xxx2_bbram
• dtbinding_ite_it8xxx2_espi
• dtbinding_ite_it8xxx2_flash_controller
• dtbinding_ite_it8xxx2_gpio
• dtbinding_ite_it8xxx2_gpio_v2
• dtbinding_ite_it8xxx2_gpiokscan
• dtbinding_ite_it8xxx2_i2c
• dtbinding_ite_it8xxx2ilinx
• dtbinding_ite_it8xxx2_intc
• dtbinding_ite_it8xxx2_intc_v2
• dtbinding_ite_it8xxx2_kbd
• dtbinding_ite_it8xxx2_peci
• dtbinding_ite_it8xxx2_pinctrl
• dtbinding_ite_it8xxx2_pinctrl_func
• dtbinding_ite_it8xxx2_pwm
• dtbinding_ite_it8xxx2_pwmprs
• dtbinding_ite_it8xxx2_sha
• dtbinding_ite_it8xxx2_sspi
• dtbinding_ite_it8xxx2_tach
• dtbinding_ite_it8xxx2_timer
• dtbinding_ite_it8xxx2_uart
• dtbinding_ite_it8xxx2_usbpd
• dtbinding_ite_it8xxx2_vcmp
• dtbinding_ite_it8xxx2_watchdog
• dtbinding_ite_it8xxx2_wuc
• dtbinding_ite_it8xxx2_wuc_map
• dtbinding_ite_riscv_ite

JEDEC Solid State Technology Association (jedec)
  • dtbinding_jedec_spi_nor

Kvaser (kvaser)
  • dtbinding_kvaser_pcican

Lattice Semiconductor (lattice)
  • dtbinding_lattice_ice40_fpga

Linaro Limited (linaro)
  • dtbinding_linaro_96b_lscon_1v8
  • dtbinding_linaro_96b_lscon_3v3
  • dtbinding_linaro_ivshmem_ipm

Linear Technology Corporation (lltc)
  • dtbinding_lltc_ltc1660
  • dtbinding_lltc_ltc1665
  • dtbinding_lltc_ltc2451
LiteOn OptoElectronics (ltr)
  - dtbinding_ltrf216a

LiteX SoC builder (litex)
  - dtbinding_litex_clk
  - dtbinding_litex_clkout
  - dtbinding_litex_dna0
  - dtbinding_litex_eth0
  - dtbinding_litex_gpio
  - dtbinding_litex_i2c
  - dtbinding_litex_i2s
  - dtbinding_litex_prbs
  - dtbinding_litex_pwm
  - dtbinding_litex_spi
  - dtbinding_litex_timer0
  - dtbinding_litex_uart0
  - dtbinding_litex_vexriscv_standard

lowRISC Community Interest Company (lowrisc)
  - dtbinding_lowrisc_ibex
  - dtbinding_lowrisc_machine_timer
  - dtbinding_lowrisc_opentitan_aontimer
  - dtbinding_lowrisc_opentitan_pwrmgr
  - dtbinding_lowrisc_opentitan_spi
  - dtbinding_lowrisc_opentitan_uart

M5Stack (m5stack)
  - dtbinding_m5stack_atom_header
  - dtbinding_m5stack_mbus_header
  - dtbinding_m5stack_stamps3_header

Maxim Integrated Products (maxim)
  - dtbinding_maxim_ds1307
  - dtbinding_maxim_ds18b20
  - dtbinding_maxim_ds2482_800
  - dtbinding_maxim_ds2482_800_channel
  - dtbinding_maxim_ds2484
  - dtbinding_maxim_ds2485
  - dtbinding_maxim_ds3231

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- dtbinding_maxim_max11102
- dtbinding_maxim_max11103
- dtbinding_maxim_max11105
- dtbinding_maxim_max11106
- dtbinding_maxim_max11110
- dtbinding_maxim_max11111
- dtbinding_maxim_max11115
- dtbinding_maxim_max11116
- dtbinding_maxim_max11117
- dtbinding_maxim_max11253
- dtbinding_maxim_max11254
- dtbinding_maxim_max17048
- dtbinding_maxim_max17055
- dtbinding_maxim_max17262
- dtbinding_maxim_max20335
- dtbinding_maxim_max20335_charger
- dtbinding_maxim_max20335_regulator
- dtbinding_maxim_max30101
- dtbinding_maxim_max31790
- dtbinding_maxim_max31855_spi
- dtbinding_maxim_max31865
- dtbinding_maxim_max31875
- dtbinding_maxim_max3421e_spi
- dtbinding_maxim_max44009
- dtbinding_maxim_max6675
- dtbinding_maxim_max7219

Measurement Specialties (meas)
- dtbinding_meas_ms5607_i2c
- dtbinding_meas_ms5607_spi
- dtbinding_meas_ms5837

MEMSIC Inc. (memsic)
- dtbinding_memsic_mc3419

Micro:bit Educational Foundation (microbit)
- dtbinding_microbit_edge_connector
Microchip Technology Inc. (microchip)
  • dtbinding_microchip_cap1203
  • dtbinding_microchip_coreuart
  • dtbinding_microchip_enc28j60
  • dtbinding_microchip_enc424j600
  • dtbinding_microchip_ksz8081
  • dtbinding_microchip_ksz8794
  • dtbinding_microchip_ksz8863
  • dtbinding_microchip_lan865x
  • dtbinding_microchip_mcp230xx
  • dtbinding_microchip_mcp23s17
  • dtbinding_microchip_mcp23sxx
  • dtbinding_microchip_mcp2515
  • dtbinding_microchip_mcp251xfd
  • dtbinding_microchip_mcp3204
  • dtbinding_microchip_mcp3208
  • dtbinding_microchip_mcp4725
  • dtbinding_microchip_mcp4728
  • dtbinding_microchip_mcp940n
  • dtbinding_microchip_mcp9600
  • dtbinding_microchip_mcp970x
  • dtbinding_microchip_mcp9808
  • dtbinding_microchip_mpfs_gpio
  • dtbinding_microchip_mpfs_i2c
  • dtbinding_microchip_mpfs_qspi
  • dtbinding_microchip_mpfs_spi
  • dtbinding_microchip_tcn75a
  • dtbinding_microchip_xec_adc
  • dtbinding_microchip_xec_bbled
  • dtbinding_microchip_xec_bbram
  • dtbinding_microchip_xec_dmac
  • dtbinding_microchip_xec_ecia
  • dtbinding_microchip_xec_ecia_girq
  • dtbinding_microchip_xec_ecs
  • dtbinding_microchip_xec_eeprom
  • dtbinding_microchip_xec_espi
  • dtbinding_microchip_xec_espi_host_dev
  • dtbinding_microchip_xec_espi_saf
  • dtbinding_microchip_xec_espi_saf_v2
• dtbinding_microchip_xec_espi_v2
• dtbinding_microchip_xec_espi_vw_routing
• dtbinding_microchip_xec_gpio
• dtbinding_microchip_xec_gpio_v2
• dtbinding_microchip_xec_i2c
• dtbinding_microchip_xec_i2c_v2
• dtbinding_microchip_xec_kscan
• dtbinding_microchip_xec_pcr
• dtbinding_microchip_xec_peci
• dtbinding_microchip_xec_pinctrl
• dtbinding_microchip_xec_ps2
• dtbinding_microchip_xec_pwm
• dtbinding_microchip_xec_pwmbled
• dtbinding_microchip_xec_qmspi
• dtbinding_microchip_xec_qmspi_ldma
• dtbinding_microchip_xec_rtos_timer
• dtbinding_microchip_xec_symcr
• dtbinding_microchip_xec_tach
• dtbinding_microchip_xec_timer
• dtbinding_microchip_xec_uart
• dtbinding_microchip_xec_watchdog

Micron Technology Inc. (micron)
• dtbinding_micron_mt25qu02g

Motorola, Inc. (motorola)
• dtbinding_motorola_mc146818

Murata Manufacturing Co., Ltd. (murata)
• dtbinding_murata_ncp15wb473

Nordic Semiconductor (nordic)
• dtbinding_nordic_mbox_nrf_ipc
• dtbinding_nordic_mram
• dtbinding_nordic_npm1100
• dtbinding_nordic_npm1300
• dtbinding_nordic_npm1300_charger
• dtbinding_nordic_npm1300_gpio
• dtbinding_nordic_npm1300_led
• dtbinding_nordic_npm1300_regulator
• dtbinding_nordic_npm1300_wdt
• dtbinding_nordic_npm6001
• dtbinding_nordic_npm6001_gpio
• dtbinding_nordic_npm6001_regulator
• dtbinding_nordic_npm6001_wdt
• dtbinding_nordic_nrf_acl
• dtbinding_nordic_nrf_adc
• dtbinding_nordic_nrf_bprot
• dtbinding_nordic_nrf_ccm
• dtbinding_nordic_nrf_clic
• dtbinding_nordic_nrf_clock
• dtbinding_nordic_nrf_comp
• dtbinding_nordic_nrf_ctrlapperi
• dtbinding_nordic_nrf_dcnf
• dtbinding_nordic_nrf_dppic
• dtbinding_nordic_nrf_ecb
• dtbinding_nordic_nrf_egu
• dtbinding_nordic_nrf_ficr
• dtbinding_nordic_nrf_gpio
• dtbinding_nordic_nrf_gpio_forwarder
• dtbinding_nordic_nrf_gpiote
• dtbinding_nordic_nrf_gpreget
• dtbinding_nordic_nrf_grtc
• dtbinding_nordic_nrf_hfxo
• dtbinding_nordic_nrf_hsfll
• dtbinding_nordic_nrf_i2s
• dtbinding_nordic_nrf_ieee802154
• dtbinding_nordic_nrf_ipc
• dtbinding_nordic_nrf_kmu
• dtbinding_nordic_nrf_led_matrix
• dtbinding_nordic_nrf_lfxo
• dtbinding_nordic_nrf_lpcmp
• dtbinding_nordic_nrf_mpu
• dtbinding_nordic_nrf_mutex
• dtbinding_nordic_nrf_mwu
• dtbinding_nordic_nrf_nfct
• dtbinding_nordic_nrf_oscillators
• dtbinding_nordic_nrf_pdm

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• dtbinding_nordic_nrf_pinctrl
• dtbinding_nordic_nrf_power
• dtbinding_nordic_nrf_ppi
• dtbinding_nordic_nrf_pwm
• dtbinding_nordic_nrf_qdec
• dtbinding_nordic_nrf_qspi
• dtbinding_nordic_nrf_radio
• dtbinding_nordic_nrf_regulators
• dtbinding_nordic_nrf_reset
• dtbinding_nordic_nrf_rng
• dtbinding_nordic_nrf_rtc
• dtbinding_nordic_nrf_saadc
• dtbinding_nordic_nrf_spi
• dtbinding_nordic_nrf_spim
• dtbinding_nordic_nrf_spis
• dtbinding_nordic_nrf_spu
• dtbinding_nordic_nrf_sw_pwm
• dtbinding_nordic_nrf_swi
• dtbinding_nordic_nrf_temp
• dtbinding_nordic_nrf_timer
• dtbinding_nordic_nrf_tw1
• dtbinding_nordic_nrf_twim
• dtbinding_nordic_nrf_twis
• dtbinding_nordic_nrf_uart
• dtbinding_nordic_nrf_uarte
• dtbinding_nordic_nrf_uicr
• dtbinding_nordic_nrf_uicr_v2
• dtbinding_nordic_nrf_usb
• dtbinding_nordic_nrf_usbreg
• dtbinding_nordic_nrf_vmc
• dtbinding_nordic_nrf_vpr_coprocessor
• dtbinding_nordic_nrf_wdt
• dtbinding_nordic_nrf21540_fem
• dtbinding_nordic_nrf21540_fem_spi
• dtbinding_nordic_nrf51_flash_controller
• dtbinding_nordic_nrf52_flash_controller
• dtbinding_nordic_nrf53_flash_controller
• dtbinding_nordic_nrf91_flash_controller
• dtbinding_nordic_owned_memory
• dtbinding_nordic_owned_partitions
• dtbinding_nordic_qspi_nor
• dtbinding_nordic_vpr

Noritake Co., Inc. Electronics Division (noritake)
• dtbinding_noritake_itron

Nuclei System Technology (nuclei)
• dtbinding_nuclei_bumblebee
• dtbinding_nuclei_eclic
• dtbinding_nuclei_systimer

Nuvoton Technology Corporation (nuvoton)
• dtbinding_nuvoton_adc_cmp
• dtbinding_nuvoton_nct38xx
• dtbinding_nuvoton_nct38xx_gpio
• dtbinding_nuvoton_nct38xx_gpio_alert
• dtbinding_nuvoton_nct38xx_gpio_port
• dtbinding_nuvoton_npcx_adc
• dtbinding_nuvoton_npcx_bbram
• dtbinding_nuvoton_npcx_booter_variant
• dtbinding_nuvoton_npcx_espi
• dtbinding_nuvoton_npcx_espi_taf
• dtbinding_nuvoton_npcx_espi_vw_conf
• dtbinding_nuvoton_npcx_fiu_nor
• dtbinding_nuvoton_npcx_fiu_qspi
• dtbinding_nuvoton_npcx_gpio
• dtbinding_nuvoton_npcx_host_sub
• dtbinding_nuvoton_npcx_host_uart
• dtbinding_nuvoton_npcx_i2c_ctrl
• dtbinding_nuvoton_npcx_i2c_port
• dtbinding_nuvoton_npcx_itim_timer
• dtbinding_nuvoton_npcx_kbd
• dtbinding_nuvoton_npcx_leakage_io
• dtbinding_nuvoton_npcx_lvolctrl_conf
• dtbinding_nuvoton_npcx_miwu
• dtbinding_nuvoton_npcx_miwu_int_map
• dtbinding_nuvoton_npcx_miwu_wui_map
• dtbinding_nuvoton_npcx_pcc
• dtbinding_nuvoton_npcx_peci
• dtbinding_nuvoton_npcx_pinctrl
• dtbinding_nuvoton_npcx_pinctrl_conf
• dtbinding_nuvoton_npcx_pinctrl_def
• dtbinding_nuvoton_npcx_power_psl
• dtbinding_nuvoton_npcx_ps2_channel
• dtbinding_nuvoton_npcx_ps2_ctrl
• dtbinding_nuvoton_npcx_pwm
• dtbinding_nuvoton_npcx_scfg
• dtbinding_nuvoton_npcx_sha
• dtbinding_nuvoton_npcx_shi
• dtbinding_nuvoton_npcx_shi_enhanced
• dtbinding_nuvoton_npcx_soc_id
• dtbinding_nuvoton_npcx_spip
• dtbinding_nuvoton_npcx_tach
• dtbinding_nuvoton_npcx_uart
• dtbinding_nuvoton_npcx_watchdog
• dtbinding_nuvoton_numaker_adc
• dtbinding_nuvoton_numaker_canfd
• dtbinding_nuvoton_numaker_ethernet
• dtbinding_nuvoton_numaker_fmc
• dtbinding_nuvoton_numaker_gpio
• dtbinding_nuvoton_numaker_i2c
• dtbinding_nuvoton_numaker_pcc
• dtbinding_nuvoton_numaker_pinctrl
• dtbinding_nuvoton_numaker_pwm
• dtbinding_nuvoton_numaker_rst
• dtbinding_nuvoton_numaker_scc
• dtbinding_nuvoton_numaker_spi
• dtbinding_nuvoton_numaker_uart
• dtbinding_nuvoton_numicro_gpio
• dtbinding_nuvoton_numicro_pinctrl
• dtbinding_nuvoton_numicro_uart

**NXP Semiconductors (nxp)**
• dtbinding_nxp_css_v2
• dtbinding_nxp_ctimer_pwm
• dtbinding_nxp_dai_sai
• dtbinding_nxp_dcnano_lcdif
• dtbinding_nxp_dmic
• dtbinding_nxp_edma
• dtbinding_nxp_edci
• dtbinding_nxp_enet
• dtbinding_nxp_enet_mac
• dtbinding_nxp_enet_mdio
• dtbinding_nxp_enet_ptp_clock
• dtbinding_nxp_flexcan
• dtbinding_nxp_flexcan_fd
• dtbinding_nxp_flexpwm
• dtbinding_nxp_flexram
• dtbinding_nxp_fs26_wdog
• dtbinding_nxp_fxas21002_i2c
• dtbinding_nxp_fxas21002_spi
• dtbinding_nxp_fxs8700_i2c
• dtbinding_nxp_fxs8700_spi
• dtbinding_nxp_gpt_hw_timer
• dtbinding_nxp_iap_fmc11
• dtbinding_nxp_iap_fmc54
• dtbinding_nxp_iap_fmc55
• dtbinding_nxp_iap_fmc553
• dtbinding_nxp_imx_anatop
• dtbinding_nxp_imx_caam
• dtbinding_nxp_imx_ccm
• dtbinding_nxp_imx_ccm_rev2
• dtbinding_nxp_imxcsi
• dtbinding_nxp_imx_dtcms
• dtbinding_nxp_imx_elcdif
• dtbinding_nxp_imx_epit
• dtbinding_nxp_imx_flexspi
• dtbinding_nxp_imx_flexspi_aps6408l
• dtbinding_nxp_imx_flexspi_hyperflash
• dtbinding_nxp_imx_flexspi_mx25um51345g
• dtbinding_nxp_imx_flexspi_nor
• dtbinding_nxp_imx_flexspi_s27ks0641
• dtbinding_nxp_imx_flexspi_w956a8mbya
• dtbinding_nxp_imx_gpio
• dtbinding_nxp_imx_gpr

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• dtbinding_nxp_imx_gpt
• dtbinding_nxp_imx_iomuxc
• dtbinding_nxp_imx_iomuxc_scu
• dtbinding_nxp_imx_itcm
• dtbinding_nxp_imx_iuart
• dtbinding_nxp_imx_lpi2c
• dtbinding_nxp_imx_lpspi
• dtbinding_nxp_imx_mipi_dsi
• dtbinding_nxp_imx_mu
• dtbinding_nxp_imx_pwm
• dtbinding_nxp_imx_qtmr
• dtbinding_nxp_imx_rgpio
• dtbinding_nxp_imx_semc
• dtbinding_nxp_imx_snvs_rtc
• dtbinding_nxp_imx_tmr
• dtbinding_nxp_imx_uart
• dtbinding_nxp_imx_usdhc
• dtbinding_nxp_imx_wdog
• dtbinding_nxp_imx7d_pinctrl
• dtbinding_nxp_imx8_pinctrl
• dtbinding_nxp_imx8m_pinctrl
• dtbinding_nxp_imx8mp_pinctrl
• dtbinding_nxp_imx93_pinctrl
• dtbinding_nxp_irqsteer_intc
• dtbinding_nxp_irqsteer_master
• dtbinding_nxp_kinetis_acmp
• dtbinding_nxp_kinetis_adc12
• dtbinding_nxp_kinetis_adc16
• dtbinding_nxp_kinetis_dac
• dtbinding_nxp_kinetis_dac32
• dtbinding_nxp_kinetis_dspi
• dtbinding_nxp_kinetis_ethernet
• dtbinding_nxp_kinetis_ftfa
• dtbinding_nxp_kinetis_ftfe
• dtbinding_nxp_kinetis_ftfl
• dtbinding_nxp_kinetis_ftm
• dtbinding_nxp_kinetis_ftm_pwm
• dtbinding_nxp_kinetis_gpio
• dtbinding_nxp_kinetis_i2c
• dtbinding_nxp_kinetis_ke1xf_sim
• dtbinding_nxp_kinetis_lpsci
• dtbinding_nxp_kinetis_lptmr
• dtbinding_nxp_kinetis_lpuart
• dtbinding_nxp_kinetis_mcg
• dtbinding_nxp_kinetis_pcc
• dtbinding_nxp_kinetis_pinctrl
• dtbinding_nxp_kinetis_pinmux
• dtbinding_nxp_kinetis_pit
• dtbinding_nxp_kinetis_ptp
• dtbinding_nxp_kinetis_pwt
• dtbinding_nxp_kinetis_rng
• dtbinding_nxp_kinetis_RTC
• dtbinding_nxp_kinetis_scg
• dtbinding_nxp_kinetis_sim
• dtbinding_nxp_kinetis_temperature
• dtbinding_nxp_kinetis_tpm
• dtbinding_nxp_kinetis_trng
• dtbinding_nxp_kinetis_uart
• dtbinding_nxp_kinetis_usbd
• dtbinding_nxp_kinetis_wdog
• dtbinding_nxp_kinetis_wdog32
• dtbinding_nxp_kw41z_ieee802154
• dtbinding_nxp_lpc_ctimer
• dtbinding_nxp_lpc_dma
• dtbinding_nxp_lpc_flexcomm
• dtbinding_nxp_lpc_gpio
• dtbinding_nxp_lpc_i2c
• dtbinding_nxp_lpc_i2s
• dtbinding_nxp_lpc_iocon
• dtbinding_nxp_lpc_iocon_pinctrl
• dtbinding_nxp_lpc_iocon_pio
• dtbinding_nxp_lpc_vpadc
• dtbinding_nxp_lpc_mailbox
• dtbinding_nxp_lpc_mcan
• dtbinding_nxp_lpc_rng
• dtbinding_nxp_lpc_rtc
• dtbinding_nxp_lpc_rtc_highres
• dtbinding_nxp_lpc_sdif
• dtbinding_nxp_lpc_spi
• dtbinding_nxp_lpc_syscon
• dtbinding_nxp_lpc_uid
• dtbinding_nxp_lpc_usart
• dtbinding_nxp_lpc_wvdt
• dtbinding_nxp_lpc11u6x_eeprom
• dtbinding_nxp_lpc11u6x_gpio
• dtbinding_nxp_lpc11u6x_i2c
• dtbinding_nxp_lpc11u6x_pinctrl
• dtbinding_nxp_lpc11u6x_syscon
• dtbinding_nxp_lpc11u6x_uart
• dtbinding_nxp_lpcip3511
• dtbinding_nxp_lpdac
• dtbinding_nxp_mbox_imx_mu
• dtbinding_nxp_mbox_mailbox
• dtbinding_nxp_mcr20a
• dtbinding_nxp_mcux_12b1msps_sar
• dtbinding_nxp_mcux_dcp
• dtbinding_nxp_mcux_edma
• dtbinding_nxp_mcux_edma_v3
• dtbinding_nxp_mcux_i2s
• dtbinding_nxp_mcux_i3c
• dtbinding_nxp_mcux_qdec
• dtbinding_nxp_mcux_rt_pinctrl
• dtbinding_nxp_mcux_rt11xx_pinctrl
• dtbinding_nxp_mcux_xbar
• dtbinding_nxp_mipi_dsi_2l
• dtbinding_nxp_mrt
• dtbinding_nxp_mrt_channel
• dtbinding_nxp_nx20p3483
• dtbinding_nxp_os_timer
• dtbinding_nxp_pca9420
• dtbinding_nxp_pca95xx
• dtbinding_nxp_pca9633
• dtbinding_nxp_pca9685
• dtbinding_nxp_pcal6408a
• dtbinding_nxp_pcal6416a
• dtbinding_nxp_pcf8523
• dtbinding_nxp_pcf8563
• dtbinding_nxp_pcf857x
• dtbinding_nxp_pdcfg_power
• dtbinding_nxp_pint
• dtbinding_nxp_pxp
• dtbinding_nxp_s32_qdec
• dtbinding_nxp_rt_iocon_pinctrl
• dtbinding_nxp_s32_adc_sar
• dtbinding_nxp_s32_canxl
• dtbinding_nxp_s32_clock
• dtbinding_nxp_s32_emios
• dtbinding_nxp_s32_emios_pwm
• dtbinding_nxp_s32_gmac
• dtbinding_nxp_s32_gmac_mdio
• dtbinding_nxp_s32_gpio
• dtbinding_nxp_s32_lcu
• dtbinding_nxp_s32_linflexd
• dtbinding_nxp_s32_mru
• dtbinding_nxp_s32_netc_emdio
• dtbinding_nxp_s32_netc_psi
• dtbinding_nxp_s32_netc_vsi
• dtbinding_nxp_s32_qspi
• dtbinding_nxp_s32_qspi_device
• dtbinding_nxp_s32_qspi_nor
• dtbinding_nxp_s32_siul2_eirq
• dtbinding_nxp_s32_spi
• dtbinding_nxp_s32.swt
• dtbinding_nxp_s32_sys_timer
• dtbinding_nxp_s32_trgmux
• dtbinding_nxp_s32_wkpu
• dtbinding_nxp_s32k3_pinctrl
• dtbinding_nxp_s32ze_pinctrl
• dtbinding_nxp_sc18im704
• dtbinding_nxp_sc18im704_gpio
• dtbinding_nxp_sc18im704_i2c
• dtbinding_nxp_sctimer_pwm
• dtbinding_nxp_smartdma
• dtbinding_nxp_sof_host_dma
• dtbinding_nxp_tempmon
• dtbinding_nxp_tja1103
dtbinding_nxp_vf610_adc
dtbinding_nxp_vref

OmniVision Technologies (ovti)
  dtbinding_ovti_ov2640
  dtbinding_ovti_ov7725

ON Semiconductor Corp. (onnn)
  dtbinding_onnn_ncp5623

open-isa.org (openisa)
  dtbinding_openisa_ri5cy
  dtbinding_openisa_rv32m1_event_unit
  dtbinding_openisa_rv32m1_ftfe
  dtbinding_openisa_rv32m1_genfsk
  dtbinding_openisa_rv32m1_gpio
  dtbinding_openisa_rv32m1_intmux
  dtbinding_openisa_rv32m1_intmux_ch
  dtbinding_openisa_rv32m1_lpi2c
  dtbinding_openisa_rv32m1_lpspi
  dtbinding_openisa_rv32m1_lptmr
  dtbinding_openisa_rv32m1_lpuart
  dtbinding_openisa_rv32m1_pcc
  dtbinding_openisa_rv32m1_pinctrl
  dtbinding_openisa_rv32m1_pinmux
  dtbinding_openisa_rv32m1_tpm
  dtbinding_openisa_rv32m1_trng
  dtbinding_openisa_zero_ri5cy

OpenCores.org (opencores)
  dtbinding_opencores_spi_simple

OpenThread.io (openthread)
  dtbinding_openthread_config

Orise Technology (orisetech)
  dtbinding_orisetech_otm8009a
Panasonic Corporation (panasonic)
  • dtbinding_panasonic_amg88xx
  • dtbinding_panasonic_reduced_arduino_header

Plantower Co., Ltd (plantower)
  • dtbinding_plantower_pms7003

Princeton Technology Corp. (ptc)
  • dtbinding_ptc_pt6314

QEMU, a generic and open source machine emulator and virtualizer (qemu)
  • dtbinding_qemu_ivshmem
  • dtbinding_qemu_nios2_zephyr

Qorvo, Inc (formerly Decawave) (decawave)
  • dtbinding_decawave_dw1000

Quectel Wireless Solutions Co., Ltd. (quectel)
  • dtbinding_quectel_bg95
  • dtbinding_quectel_bg9x
  • dtbinding_quectel_eg25_g
  • dtbinding_quectel_lc26g
  • dtbinding_quectel_lc76g
  • dtbinding_quectel_lc86g

QuickLogic Corp. (quicklogic)
  • dtbinding_quicklogic_eos_s3_gpio
  • dtbinding_quicklogic_eos_s3_pinctrl
  • dtbinding_quicklogic_usbserialport_s3b

Raspberry Pi Foundation (raspberrypi)
  • dtbinding_raspberrypi_core_supply_regulator
  • dtbinding_raspberrypi_pico_adc
  • dtbinding_raspberrypi_pico_clock
  • dtbinding_raspberrypi_pico_clock_controller
  • dtbinding_raspberrypi_pico_dma
  • dtbinding_raspberrypi_pico_flash_controller
  • dtbinding_raspberrypi_pico_gpio
  • dtbinding_raspberrypi_pico_header

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- dtbinding_raspberrypi_pico_i2c
- dtbinding_raspberrypi_pico_pinctrl
- dtbinding_raspberrypi_pico_pio
- dtbinding_raspberrypi_pico_pio_device
- dtbinding_raspberrypi_pico_pll
- dtbinding_raspberrypi_pico_pwm
- dtbinding_raspberrypi_pico_reset
- dtbinding_raspberrypi_pico_rosc
- dtbinding_raspberrypi_pico_spi
- dtbinding_raspberrypi_pico_spi_pio
- dtbinding_raspberrypi_pico_temp
- dtbinding_raspberrypi_pico_timer
- dtbinding_raspberrypi_pico_uart
- dtbinding_raspberrypi_pico_uart_pio
- dtbinding_raspberrypi_pico_usbd
- dtbinding_raspberrypi_pico_watchdog

Raydium Semiconductor Corp. (raydium)
- dtbinding_raydium_rm67162
- dtbinding_raydium_rm68200

Renesas Electronics Corporation (renesas)
- dtbinding_renesas_hs300x
- dtbinding_renesas_pwm_rcar
- dtbinding_renesas_r8a7795_cpg_mssr
- dtbinding_renesas_r8a779f0_cpg_mssr
- dtbinding_renesas_ra_clock_generation_circuit
- dtbinding_renesas_ra_gpio
- dtbinding_renesas_ra_interrupt_controller_unit
- dtbinding_renesas_ra_pinctrl
- dtbinding_renesas_ra_sci
- dtbinding_renesas_ra_uart_sci
- dtbinding_renesas_rcar_can
- dtbinding_renesas_rcar_cmt
- dtbinding_renesas_rcar_gpio
- dtbinding_renesas_rcar_i2c
- dtbinding_renesas_rcar_pfc
- dtbinding_renesas_rcar_scif
- dtbinding_renesas_rzt2m_gpio
- dtbinding_renesas_rzt2m_pinctrl
- dtbinding_renesas_rzt2m_uart
- dtbinding_renesas_smartbond_gpadc
- dtbinding_renesas_smartbond_crypto
- dtbinding_renesas_smartbond_dma
- dtbinding_renesas_smartbond_flash_controller
- dtbinding_renesas_smartbond_gpio
- dtbinding_renesas_smartbond_i2c
- dtbinding_renesas_smartbond_lp_clock
- dtbinding_renesas_smartbond_lp_osc
- dtbinding_renesas_smartbond_pinctrl
- dtbinding_renesas_da1469x_regulator
- dtbinding_renesas_smartbond_RTC
- dtbinding_renesas_smartbond_sdadc
- dtbinding_renesas_smartbond_spi
- dtbinding_renesas_smartbond_sys_clock
- dtbinding_renesas_smartbond_timer
- dtbinding_renesas_smartbond_trng
- dtbinding_renesas_smartbond_uart
- dtbinding_renesas_smartbond_usbd
- dtbinding_renesas_smartbond_watchdog

**Richtek Technology Corporation (richtek)**
- dtbinding_richtek_rt1718s
- dtbinding_richtek_rt1718s_gpio_port

**RISC-V Foundation (riscv)**
- dtbinding_riscv_cpu_intc

**ROCKTECH DISPLAYS LIMITED (rocktech)**
- dtbinding_rocktech_rk043fn02h_ct

**ROHM Semiconductor Co., Ltd (rohm)**
- dtbinding_rohm_bd8lb600fs
- dtbinding_rohm_bh1750

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Seeed Technology Co., Ltd (seeed)
  • dtbinding_seeed_grove_lcd_rgb
  • dtbinding_seeed_grove_light
  • dtbinding_seeed_grove_temperature
  • dtbinding_seeed_hm330x
  • dtbinding_seeed_xiao_header

SEGGER Microcontroller GmbH (segger)
  • dtbinding_segger_rtt_uart

Semtech Corporation (semtech)
  • dtbinding_semtech_sx1261
  • dtbinding_semtech_sx1262
  • dtbinding_semtech_sx1272
  • dtbinding_semtech_sx1276
  • dtbinding_semtech_sx1509b
  • dtbinding_semtech_sx9500

Sensirion AG (sensirion)
  • dtbinding_sensirion_sgp40
  • dtbinding_sensirion_sht3xd
  • dtbinding_sensirion_sht4x
  • dtbinding_sensirion_shtcx

Sequans Communications (sqn)
  • dtbinding_sqn_hwspinlock

Sharp Corporation (sharp)
  • dtbinding_sharp_ls0xx

Shenzhen Huiding Technology Co., Ltd. (goodix)
  • dtbinding_goodix_gt911

Shenzhen Jinghua Displays Electronics Co., Ltd. (jhd)
  • dtbinding_jhd_jhd1313

Shenzhen Xptek Technology Co., Ltd (xptek)
  • dtbinding_xptek_xpt2046
Siemens AG (siemens)
  • dtbinding_siemens_ivshmem_eth

Sierra Wireless (swir)
  • dtbinding_swir_hl7800

SiFive, Inc. (sifive)
  • dtbinding_sifive_clint0
  • dtbinding_sifive_dtim0
  • dtbinding_sifive_e24
  • dtbinding_sifive_e31
  • dtbinding_sifive_e51
  • dtbinding_sifive_fu740_c000_ddr
  • dtbinding_sifive_gpio0
  • dtbinding_sifive_i2c0
  • dtbinding_sifive_pinctrl
  • dtbinding_sifive_plic_1.0.0
  • dtbinding_sifive_pwm0
  • dtbinding_sifive_s7
  • dtbinding_sifive_spi0
  • dtbinding_sifive_u54
  • dtbinding_sifive_uart0
  • dtbinding_sifive_wdt

Silicon Laboratories (silabs)
  • dtbinding_silabs_gecko_adc
  • dtbinding_silabs_gecko_burtc
  • dtbinding_silabs_gecko_ethernet
  • dtbinding_silabs_gecko_flash_controller
  • dtbinding_silabs_gecko_gpio
  • dtbinding_silabs_gecko_gpio_port
  • dtbinding_silabs_gecko_i2c
  • dtbinding_silabs_gecko_iadc
  • dtbinding_silabs_gecko_leuart
  • dtbinding_silabs_gecko_pinctrl
  • dtbinding_silabs_gecko_pwm
  • dtbinding_silabs_gecko_rtcc
  • dtbinding_silabs_gecko_semailbox
  • dtbinding_silabs_gecko_spi_usart
• dtbinding_silabs_gecko_stimer
• dtbinding_silabs_gecko_timer
• dtbinding_silabs_gecko_trng
• dtbinding_silabs_gecko_uart
• dtbinding_silabs_gecko_usart
• dtbinding_silabs_gecko_wdog
• dtbinding_silabs_hfxo
• dtbinding_silabs_si7006
• dtbinding_silabs_si7055
• dtbinding_silabs_si7060
• dtbinding_silabs_si7210

SIMCom Wireless Solutions Co., LTD (simcom)
• dtbinding_simcom_sim7080

Sino Wealth Electronic Ltd (sinowealth)
• dtbinding_sinowealth_sh1106_i2c
• dtbinding_sinowealth_sh1106_spi

Sitronix Technology Corporation (sitronix)
• dtbinding_sitronix_st7735r
• dtbinding_sitronix_st7789v

Skyworks Solutions, Inc. (skyworks)
• dtbinding_skyworks_sky13351

Smart Battery System (sbs)
• dtbinding_sbs_default_sbs_gauge
• dtbinding_sbs_sbs_charger
• dtbinding_sbs_sbs_gauge
• dtbinding_sbs_sbs_gauge_new_api

Solomon Systech Limited (solomon)
• dtbinding_solomon_ssd1306fb_i2c
• dtbinding_solomon_ssd1306fb_spi
• dtbinding_solomon_ssd1608
• dtbinding_solomon_ssd1673
• dtbinding_solomon_ssd1675a
• dtbinding_solomon_ssd1680
• dtbinding_solomon_ssd1681

**SparkFun Electronics (sparkfun)**
• dtbinding_sparkfun_pro_micro_header
• dtbinding_sparkfun_serlcd

**Standard Microsystems Corporation (smsc)**
• dtbinding_smc_lan91c111
• dtbinding_smc_lan91c111_mdio
• dtbinding_smc_lan9220

**StarFive Technology Co. Ltd. (starfive)**
• dtbinding_starfive_jh7100_clint

**STMicroelectronics (st)**
• dtbinding_st_dsi_lcd_qsh_030
• dtbinding_st_hci_spi_v1
• dtbinding_st_hci_spi_v2
• dtbinding_st_hts221_i2c
• dtbinding_st_hts221_spi
• dtbinding_st_i3g4250d
• dtbinding_st_iis2dh_i2c
• dtbinding_st_iis2dh_spi
• dtbinding_st_iis2dlpc_i2c
• dtbinding_st_iis2dlpc_spi
• dtbinding_st_iis2iclx_i2c
• dtbinding_st_iis2iclx_spi
• dtbinding_st_iis2mdc_i2c
• dtbinding_st_iis2mdc_spi
• dtbinding_st_iis3dhhc_spi
• dtbinding_st_ism330dhcx_i2c
• dtbinding_st_ism330dhcx_spi
• dtbinding_st_lis2de12_i2c
• dtbinding_st_lis2de12_spi
• dtbinding_st_lis2dh_i2c
• dtbinding_st_lis2dh_spi
• dtbinding_st_lis2dh12_i2c
• dtbinding_st_lis2ds12_i2c
• dtbinding_st_lis2ds12_spi
- dtbinding_st_lis2du12_i2c
- dtbinding_st_lis2du12_spi
- dtbinding_st_lis2dw12_i2c
- dtbinding_st_lis2dw12_spi
- dtbinding_st_lis2mdl_i2c
- dtbinding_st_lis2mdl_spi
- dtbinding_st_lis3dh_i2c
- dtbinding_st_lis3mdl_magn
- dtbinding_st_lps22df_i2c
- dtbinding_st_lps22df_i3c
- dtbinding_st_lps22df_spi
- dtbinding_st_lps22hb_press
- dtbinding_st_lps22hh_i2c
- dtbinding_st_lps22hh_i3c
- dtbinding_st_lps22hh_spi
- dtbinding_st_lps25hb_press
- dtbinding_st_lps28dfw_i2c
- dtbinding_st_lps28dfw_i3c
- dtbinding_st_lsm303agr_accel_i2c
- dtbinding_st_lsm303agr_accel_spi
- dtbinding_st_lsm303dlhc_accel
- dtbinding_st_lsm303dlhc_magn
- dtbinding_st_lsm6ds0
- dtbinding_st_lsm6dsl_i2c
- dtbinding_st_lsm6dsl_spi
- dtbinding_st_lsm6dso_i2c
- dtbinding_st_lsm6dso_spi
- dtbinding_st_lsm6dso16is_i2c
- dtbinding_st_lsm6dso16is_spi
- dtbinding_st_lsm6ds032_i2c
- dtbinding_st_lsm6ds032_spi
- dtbinding_st_lsm6ds16x_i2c
- dtbinding_st_lsm6ds16x_spi
- dtbinding_st_lsm9ds0_gyro_i2c
- dtbinding_st_lsm9ds0_mfd_i2c
- dtbinding_st_mpxxdttyy_i2s
- dtbinding_st_stm32_adc
- dtbinding_st_stm32_aes
- dtbinding_st_stm32_backup_sram
• dtbinding_st_stm32_bbram
• dtbinding_st_stm32_bdma
• dtbinding_st_stm32_bxcan
• dtbinding_st_stm32_ccm
• dtbinding_st_stm32_clock_mux
• dtbinding_st_stm32_counter
• dtbinding_st_stm32_cryp
• dtbinding_st_stm32_dac
• dtbinding_st_stm32_dma
• dtbinding_st_stm32_dma_v1
• dtbinding_st_stm32_dma_v2
• dtbinding_st_stm32_dma_v2bis
• dtbinding_st_stm32_dmamux
• dtbinding_st_stm32_eeprom
• dtbinding_st_stm32_ethernet
• dtbinding_st_stm32_exti
• dtbinding_st_stm32_fdcan
• dtbinding_st_stm32_flash_controller
• dtbinding_st_stm32_fmc
• dtbinding_st_stm32_fmc_nor_psram
• dtbinding_st_stm32_fmc_sdram
• dtbinding_st_stm32_gpio
• dtbinding_st_stm32_hse_clock
• dtbinding_st_stm32_hsem_mailbox
• dtbinding_st_stm32_hsi48_clock
• dtbinding_st_stm32_i2c_v1
• dtbinding_st_stm32_i2c_v2
• dtbinding_st_stm32_i2s
• dtbinding_st_stm32_ipcc_mailbox
• dtbinding_st_stm32_lptim
• dtbinding_st_stm32_lpuart
• dtbinding_st_stm32_lse_clock
• dtbinding_st_stm32_ltdc
• dtbinding_st_stm32_mipi_dsi
• dtbinding_st_stm32_msi_clock
• dtbinding_st_stm32_nv_flash
• dtbinding_st_stm32_ospi
• dtbinding_st_stm32_ospi_nor
• dtbinding_st_stm32_otgfs

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• dtbinding_st stm32 otghs
• dtbinding_st stm32 pinctrl
• dtbinding_st stm32 pwm
• dtbinding_st stm32 qdec
• dtbinding_st stm32 qs pi
• dtbinding_st stm32 qs pi nor
• dtbinding_st stm32 rcc
• dtbinding_st stm32 rcc rctl
• dtbinding_st stm32 rng
• dtbinding_st stm32 rtc
• dtbinding_st stm32 sdmmc
• dtbinding_st stm32 smbus
• dtbinding_st stm32 spi
• dtbinding_st stm32 spi fifo
• dtbinding_st stm32 spi host cmd
• dtbinding_st stm32 spi subghz
• dtbinding_st stm32 temp
• dtbinding_st stm32 temp cal
• dtbinding_st stm32 timers
• dtbinding_st stm32 uart
• dtbinding_st stm32 ucpd
• dtbinding_st stm32 usart
• dtbinding_st stm32 usb
• dtbinding_st stm32 usbphyc
• dtbinding_st stm32 vbat
• dtbinding_st stm32 vref
• dtbinding_st stm32 watchdog
• dtbinding_st stm32 window watchdog
• dtbinding_st stm32c0 hsi clock
• dtbinding_st stm32c0 temp cal
• dtbinding_st stm32f0 pll clock
• dtbinding_st stm32f0 rcc
• dtbinding_st stm32f1 adc
• dtbinding_st stm32f1 flash_controller
• dtbinding_st stm32f1 pinctrl
• dtbinding_st stm32f1 pll clock
• dtbinding_st stm32f1 rcc
• dtbinding_st stm32f100 pll clock
• dtbinding_st stm32f105 pll clock
• dtbinding_st stm32f105_pll2_clock
• dtbinding_st stm32f2_flash_controller
• dtbinding_st stm32f2_pll_clock
• dtbinding_st stm32f3_rcc
• dtbinding_st stm32f4_adc
• dtbinding_st stm32f4_flash_controller
• dtbinding_st stm32f4_fsotg
• dtbinding_st stm32f4_pll_clock
• dtbinding_st stm32f4_pll2s_clock
• dtbinding_st stm32f412_pll2s_clock
• dtbinding_st stm32f7_pll_clock
• dtbinding_st stm32f7_pll_clock
• dtbinding_st stm32g0_exti
• dtbinding_st stm32g0_flash_controller
• dtbinding_st stm32g0_hsi_clock
• dtbinding_st stm32g0_pll_clock
• dtbinding_st stm32g4_flash_controller
• dtbinding_st stm32g4_pll_clock
• dtbinding_st stm32h7_fdcan
• dtbinding_st stm32h7_pll_clock
• dtbinding_st stm32h7_fmc
• dtbinding_st stm32h7_pll_clock
• dtbinding_st stm32h7_i2s
• dtbinding_st stm32h7_pll_clock
• dtbinding_st stm32h7_pll_clock
• dtbinding_st stm32h7_pll_clock
• dtbinding_st stm32l0_msi_clock
• dtbinding_st stm32l0_pll_clock
• dtbinding_st stm32l4_flash_controller
• dtbinding_st stm32l4_pll_clock
• dtbinding_st stm32l5_flash_controller
• dtbinding_st stm32mp1_rcc
• dtbinding_st stm32u5_dma
• dtbinding_st stm32u5_msi_clock
• dtbinding_st stm32u5_pll_clock
• dtbinding_st stm32u5_pll_clock
• dtbinding_st stm32u5_pll_clock
• dtbinding_st stm32u5_pll_clock
• dtbinding_st stm32u5_pll_clock
• dtbinding_st stm32u5_pll_clock
• dtbinding_st stm32wb_rcc
• dtbinding_st_stm32wb_ble_rf
• dtbinding_st_stm32wba_flash_controller
• dtbinding_st_stm32wba_hse_clock
• dtbinding_st_stm32wba_pll_clock
• dtbinding_st_stm32wba_rcc
• dtbinding_st_stm32wl_hse_clock
• dtbinding_st_stm32wl_rcc
• dtbinding_st_stm32wl_subghz_radio
• dtbinding_st_stmpe1600
• dtbinding_st_stmpe811
• dtbinding_st_stts751_i2c
• dtbinding_st_vl53l0x
• dtbinding_st_vl53l1x

Synopsys, Inc. (snps)
• dtbinding_snps_arc_iot_sysconf
• dtbinding_snps_arc_timer
• dtbinding_snps_arcem
• dtbinding_snps_archs_ici
• dtbinding_snps_archs_idu_intc
• dtbinding_snps_arcv2_intc
• dtbinding_snps_creg_gpio
• dtbinding_snps_designware_dma
• dtbinding_snps_designware_ethernet
• dtbinding_snps_designware_gpio
• dtbinding_snps_designware_i2c
• dtbinding_snps_designware_intc
• dtbinding_snps_designware_spi
• dtbinding_snps_designware_usb
• dtbinding_snps_designware_watchdog
• dtbinding_snps_dw_timers
• dtbinding_snps_dwc2
• dtbinding_snps_emsdp_pinctrl
• dtbinding_snps_ethernet_cyclonev
• dtbinding_snps_hostlink_uart
• dtbinding_snps_nsim_uart
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**Synopsys, Inc. (formerly ARC International PLC) (arc)**
- dtbinding_arc_dccm
- dtbinding_arc_iccm
- dtbinding_arc_xccm
- dtbinding_arc_yccm

**TDK Corporation. (tdk)**
- dtbinding_tdk_ntcg163jf103ft1

**Telink Semiconductor (telink)**
- dtbinding_telink_b91
- dtbinding_telink_b91_adc
- dtbinding_telink_b91_flash_controller
- dtbinding_telink_b91_gpio
- dtbinding_telink_b91_i2c
- dtbinding_telink_b91_pinctrl
- dtbinding_telink_b91_power
- dtbinding_telink_b91_pwm
- dtbinding_telink_b91_spi
- dtbinding_telink_b91_trng
- dtbinding_telink_b91_uart
- dtbinding_telink_b91_zb
- dtbinding_telink_machine_timer

**Telit Cinterion (telit)**
- dtbinding_telit_me910g1

**Texas Instruments (ti)**
- dtbinding_ti_ads1013
- dtbinding_ti_ads1014
- dtbinding_ti_ads1015
- dtbinding_ti_ads1112
- dtbinding_ti_ads1113
- dtbinding_ti_ads1114
- dtbinding_ti_ads1115
- dtbinding_ti_ads1119
- dtbinding_ti_ads114s08
- dtbinding_ti_ads114s0x_gpio
- dtbinding_ti_ads7052
- dtbinding_ti_boosterpack_header
- dtbinding_ti bq24190
- dtbinding_ti bq25180
- dtbinding_ti bq274xx
- dtbinding_ti bq27z746
- dtbinding_ti cc1200
- dtbinding_ti cc13xx cc26xx_adc
- dtbinding_ti cc13xx cc26xx flash_controller
- dtbinding_ti cc13xx cc26xx_gpio
- dtbinding_ti cc13xx cc26xx_i2c
- dtbinding_ti cc13xx cc26xx ieee802154
- dtbinding_ti cc13xx cc26xx ieee802154 subghz
- dtbinding_ti cc13xx cc26xx pinctrl
- dtbinding_ti cc13xx cc26xx radio
- dtbinding_ti cc13xx cc26xx rtc_timer
- dtbinding_ti cc13xx cc26xx spi
- dtbinding_ti cc13xx cc26xx timer
- dtbinding_ti cc13xx cc26xx timer_pwm
- dtbinding_ti cc13xx cc26xx trng
- dtbinding_ti cc13xx cc26xx_uart
- dtbinding_ti cc13xx cc26xx watchdog
- dtbinding_ti cc2520
- dtbinding_ti cc32xx adc
- dtbinding_ti cc32xx_gpio
- dtbinding_ti cc32xx_i2c
- dtbinding_ti cc32xx_pinctrl
- dtbinding_ti cc32xx_uart
- dtbinding_ti cc32xx watchdog
- dtbinding_ti dac43608
- dtbinding_ti dac53608
- dtbinding_ti dac60508
- dtbinding_ti dac70508
- dtbinding_ti dac80508
- dtbinding_ti davinci_gpio
- dtbinding_ti davinci_gpio_nexus
- dtbinding_ti fdc2x1x
- dtbinding_ti hdc
- dtbinding_ti hdc2010
- dtbinding_ti hdc2021
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• dtbinding_ti_tla2021
• dtbinding_ti_tlc59108
• dtbinding_ti_tlc5971
• dtbinding_ti_tlv320dac
• dtbinding_ti_tmag5170
• dtbinding_ti_tmag5273
• dtbinding_ti_tmp007
• dtbinding_ti_tmp108
• dtbinding_ti_tmp112
• dtbinding_ti_tmp116
• dtbinding_ti_tmp116_eeprom
• dtbinding_ti_tps382x
• dtbinding_ti_vim

u-blox (u-blox)
• dtbinding_u_blox_sara_r4
• dtbinding_u_blox_sara_r5

UltraChip Inc. (ultrachip)
• dtbinding_ultrachip_uc8175
• dtbinding_ultrachip_uc8176
• dtbinding_ultrachip_uc8179

Vishay Intertechnology, Inc (vishay)
• dtbinding_vishay_vcnl36825t
• dtbinding_vishay_vcnl4040
• dtbinding_vishay_veml7700

Wistron NeWeb Corporation (wnc)
• dtbinding_wnc_m14a2a

WIZnet Co., Ltd. (wiznet)
• dtbinding_wiznet_w5500

Worldsemi Co., Limited (worldsemi)
• dtbinding_worldsemi_ws2812_gpio
• dtbinding_worldsemi_ws2812_i2s
• dtbinding_worldsemi_ws2812_rpi_pico_pio
• dtbinding_worldsemi_ws2812_spi
Würth Elektronik GmbH. (we)
- dtbinding_we_wsen_hids_i2c
- dtbinding_we_wsen_hids_spi
- dtbinding_we_wsen_itds
- dtbinding_we_wsen_pads_i2c
- dtbinding_we_wsen_pads_spi
- dtbinding_we_wsen_pdus
- dtbinding_we_wsen_tids

X-Powers (x-powers)
- dtbinding_x_powers_axp192
- dtbinding_x_powers_axp192_gpio
- dtbinding_x_powers_axp192_regulator

Xen Hypervisor (xen)
- dtbinding_xen_hvc_consoleio
- dtbinding_xen_hvc_uart
- dtbinding_xen_xen

Xilinx (xlnx)
- dtbinding_xlnx_fpga
- dtbinding_xlnx_gem
- dtbinding_xlnx_pinctrl_zynq
- dtbinding_xlnx_pinctrl_zynqmp
- dtbinding_xlnx_ps_gpio
- dtbinding_xlnx_ps_gpio_bank
- dtbinding_xlnx_ttcps
- dtbinding_xlnx_xps_gpio_1.00.a
- dtbinding_xlnx_xps_gpio_1.00.a_gpio2
- dtbinding_xlnx_xps_iic_2.00.a
- dtbinding_xlnx_xps_iic_2.1
- dtbinding_xlnx_xps_spi_2.00.a
- dtbinding_xlnx_xps_timebase_wdt_1.00.a
- dtbinding_xlnx_xps_timer_1.00.a
- dtbinding_xlnx_xps_timer_1.00.a_pwm
- dtbinding_xlnx_xps_uartlite_1.00.a
- dtbinding_xlnx_xuartps
- dtbinding_xlnx_zynq_ocm
- dtbinding_xlnx_zynqmp_ipi_mailbox

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Zephyr-specific binding (zephyr)

- dtbinding_zephyr_adc_emul
- dtbinding_zephyr_bram_emul
- dtbinding_zephyr_bt_hci_entropy
- dtbinding_zephyr_bt_hci_spi
- dtbinding_zephyr_bt_hci_spi_slave
- dtbinding_zephyr_can_loopback
- dtbinding_zephyr_cdc_acm_uart
- dtbinding_zephyr_cdc_ecm_ethernet
- dtbinding_zephyr_coredump
- dtbinding_zephyr_counter_watchdog
- dtbinding_zephyr_devmux
- dtbinding_zephyr_dma_emul
- dtbinding_zephyr_dummy_dc
- dtbinding_zephyr_emu_eeprom
- dtbinding_zephyr_espi_emul_controller
- dtbinding_zephyr_fake_can
- dtbinding_zephyr_fake_eeprom
- dtbinding_zephyr_fake_regulator
- dtbinding_zephyr_fake_rtc
- dtbinding_zephyr_flash_disk
- dtbinding_zephyr_fstab
- dtbinding_zephyr_fstab_littlefs
- dtbinding_zephyr_gpio_emul
- dtbinding_zephyr_gpio_emul SDL
- dtbinding_zephyr_gsm_ppp
- dtbinding_zephyr_i2c_dump_allowlist
- dtbinding_zephyr_i2c_emul_controller
- dtbinding_zephyr_i2c_target_eeprom
- dtbinding_zephyr_iEEE802154_uart_pipe
- dtbinding_zephyr_input_longpress
- dtbinding_zephyr_input(SDL)_touch
- dtbinding_zephyr_ipc_icbmsg
- dtbinding_zephyr_ipc_icmsg
- dtbinding_zephyr_ipc_icmsg_ME_follower
- dtbinding_zephyr_ipc_icmsg_ME_initiator
- dtbinding_zephyr_ipc_openamp_static_vrings
- dtbinding_zephyr_kscan_input
- dtbinding_zephyr_log_uart
• dtbinding_zephyr_lvgl_button_input
• dtbinding_zephyr_lvgl_encoder_input
• dtbinding_zephyr_lvgl_keypad_input
• dtbinding_zephyr_lvgl_pointer_input
• dtbinding_zephyr_mdio_gpio
• dtbinding_zephyr_memory_region
• dtbinding_zephyr_mipi_dbi_spi
• dtbinding_zephyr_mmc_disk
• dtbinding_zephyr_modbus_serial
• dtbinding_zephyr_native_linux_can
• dtbinding_zephyr_native_linux_evdev
• dtbinding_zephyr_native_posix_counter
• dtbinding_zephyr_native_posix_cpu
• dtbinding_zephyr_native_posix_rng
• dtbinding_zephyr_native_posix_uart
• dtbinding_zephyr_native_posix_udc
• dtbinding_zephyr_native_tty_uart
• dtbinding_panel_timing
• dtbinding_zephyr_power_state
• dtbinding_zephyr_psa_crypto_rng
• dtbinding_zephyr_ram_disk
• dtbinding_zephyr_retained_ram
• dtbinding_zephyr_retained_reg
• dtbinding_zephyr_retention
• dtbinding_zephyr_RTC_emul
• dtbinding_zephyr_sdhc_spi_slot
• dtbinding_zephyr_sdl_dc
• dtbinding_zephyr_sdhc_spi_slot
• dtbinding_zephyr_sensing
• dtbinding_zephyr_sensing_hinge_angle
• dtbinding_zephyr_sensing_phy_3d_sensor
• dtbinding_zephyr_sim_eeprom
• dtbinding_zephyr_sim_flash
• dtbinding_zephyr_spi_bitbang
• dtbinding_zephyr_spi_emul_controller
• dtbinding_zephyr_uac2
• dtbinding_zephyr_uac2_audio_streaming
• dtbinding_zephyr_uac2_clock_source
• dtbinding_zephyr_uac2_input_terminal
5.3 Configuration System (Kconfig)

The Zephyr kernel and subsystems can be configured at build time to adapt them for specific application and platform needs. Configuration is handled through Kconfig, which is the same configuration system used by the Linux kernel. The goal is to support configuration without having to change any source code.

Configuration options (often called symbols) are defined in Kconfig files, which also specify dependencies between symbols that determine what configurations are valid. Symbols can be grouped into menus and sub-menus to keep the interactive configuration interfaces organized.

The output from Kconfig is a header file autoconf.h with macros that can be tested at build time. Code for unused features can be compiled out to save space.

The following sections explain how to set Kconfig configuration options, go into detail on how Kconfig is used within the Zephyr project, and have some tips and best practices for writing Kconfig files.

5.3.1 Interactive Kconfig interfaces

There are two interactive configuration interfaces available for exploring the available Kconfig options and making temporary changes: menuconfig and guiconfig. menuconfig is a curses-based interface that runs in the terminal, while guiconfig is a graphical configuration interface.

**Note:** The configuration can also be changed by editing zephyr/.config in the application build directory by hand. Using one of the configuration interfaces is often handier, as they correctly handle dependencies between configuration symbols.

If you try to enable a symbol with unsatisfied dependencies in zephyr/.config, the assignment will be ignored and overwritten when re-configuring.

To make a setting permanent, you should set it in a *.conf file, as described in Setting Kconfig configuration values.
Tip: Saving a minimal configuration file (with e.g. D in menuconfig) and inspecting it can be handy when making settings permanent. The minimal configuration file only lists symbols that differ from their default value.

To run one of the configuration interfaces, do this:

1. Build your application as usual using either west or cmake:
   - Using west:
     ```bash
     west build -b <board>
     ```
   - Using CMake and ninja:
     ```bash
     mkdir build && cd build
     cmake -GNinja -DBOARD=<board> ..
     ninja
     ```

2. To run the terminal-based menuconfig interface, use either of these commands:
   ```bash
   west build -t menuconfig
   ```
   ```bash
   ninja menuconfig
   ```
   To run the graphical guiconfig, use either of these commands:
   ```bash
   west build -t guiconfig
   ```
   ```bash
   ninja guiconfig
   ```

Note: If you get an import error for tkinter when trying to run guiconfig, you are missing required packages. See Install Linux Host Dependencies. The package you need is usually called something like python3-tk/python3-tkinter.

tkinter is not included by default in many Python installations, despite being part of the standard library.

The two interfaces are shown below:

guiconfig always shows the help text and other information related to the currently selected item in the bottom window pane. In the terminal interface, press ? to view the same information.

Note: If you prefer to work in the guiconfig interface, then it’s a good idea to check any changes to Kconfig files you make in single-menu mode, which is toggled via a checkbox at the top. Unlike full-tree mode, single-menu mode will distinguish between symbols defined with config and symbols defined with menuconfig, showing you what things would look like in the menuconfig interface.

3. Change configuration values in the menuconfig interface as follows:
   - Navigate the menu with the arrow keys. Common Vim key bindings are supported as well.
   - Use Space and Enter to enter menus and toggle values. Menus appear with ---> next to them. Press ESC to return to the parent menu.
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Boolean configuration options are shown with \[/\] brackets, while numeric and string-valued configuration symbols are shown with \((\)) brackets. Symbol values that can’t be changed are shown as -- or -*-.

**Note:** You can also press Y or N to set a boolean configuration symbol to the corresponding value.

- Press ? to display information about the currently selected symbol, including its help text. Press ESC or Q to return from the information display to the menu.

In the `guiconfig` interface, either click on the image next to the symbol to change its value, or double-click on the row with the symbol (this only works if the symbol has no children, as double-clicking a symbol with children open/closes its menu instead).

`guiconfig` also supports keyboard controls, which are similar to `menuconfig`.

4. Pressing Q in the `menuconfig` interface will bring up the save-and-quit dialog (if there are changes to save):

Press Y to save the kernel configuration options to the default filename (`zephyr/.config`). You will typically save to the default filename unless you are experimenting with different configurations.

The `guiconfig` interface will also prompt for saving the configuration on exit if it has been modified.

**Note:** The configuration file used during the build is always `zephyr/.config`. If you have another saved configuration that you want to build with, copy it to `zephyr/.config`. Make sure to back up your original configuration file.

Also note that filenames starting with . are not listed by `ls` by default on Linux and macOS. Use the `-a` flag to see them.

Finding a symbol in the menu tree and navigating to it can be tedious. To jump directly to a symbol, press the / key (this also works in `guiconfig`). This brings up the following dialog, where you can search for symbols by name and jump to them. In `guiconfig`, you can also change symbol values directly within the dialog.
Type text to narrow the search. Regexes are supported (via Python's 're' module). The up/down cursor keys step in the list. [Enter] jumps to the selected symbol. [ESC] aborts the search. Type multiple space-separated strings/regexes to find entries that match all of them. Type Ctrl-F to view the help of the selected item without leaving the dialog.
If you jump to a symbol that isn’t currently visible (e.g., due to having unsatisfied dependencies), then show-all mode will be enabled. In show-all mode, all symbols are displayed, including currently invisible symbols. To turn off show-all mode, press A in menuconfig or Ctrl-A in guiconfig.

**Note:** Show-all mode can’t be turned off if there are no visible items in the current menu.

To figure out why a symbol you jumped to isn’t visible, inspect its dependencies, either by pressing ? in menuconfig or in the information pane at the bottom in guiconfig. If you discover that the symbol depends on another symbol that isn’t enabled, you can jump to that symbol in turn to see if it can be enabled.

**Note:** In menuconfig, you can press Ctrl-F to view the help of the currently selected item in the jump-to dialog without leaving the dialog.

For more information on menuconfig and guiconfig, see the Python docstrings at the top of menuconfig.py and guiconfig.py.

### 5.3.2 Setting Kconfig configuration values

The menuconfig and guiconfig interfaces can be used to test out configurations during application development. This page explains how to make settings permanent.

All Kconfig options can be searched in the Kconfig search page.

**Note:** Before making changes to Kconfig files, it’s a good idea to also go through the Kconfig - Tips and Best Practices page.

#### Visible and invisible Kconfig symbols

When making Kconfig changes, it’s important to understand the difference between visible and invisible symbols.

- **A visible symbol** is a symbol defined with a prompt. Visible symbols show up in the interactive configuration interfaces (hence visible), and can be set in configuration files.

  Here’s an example of a visible symbol:

  ```
  config FPU
  bool "Support floating point operations"
  depends on HAS_FPU
  ```

  The symbol is shown like this in menuconfig, where it can be toggled:

  `[ ] Support floating point operations`

- **An invisible symbol** is a symbol without a prompt. Invisible symbols are not shown in the interactive configuration interfaces, and users have no direct control over their value. They instead get their value from defaults or from other symbols.

  Here’s an example of an invisible symbol:
visible symbols can be configured by setting them in configuration files. The initial configuration is produced by merging a `*.defconfig` file for the board with application settings, usually from `prj.conf`. See *The Initial Configuration* below for more details.

Assignments in configuration files use this syntax:

```bash
CONFIG_<symbol name>=<value>
```

There should be no spaces around the equals sign.

`bool` symbols can be enabled or disabled by setting them to `y` or `n`, respectively. The FPU symbol from the example above could be enabled like this:

```bash
CONFIG_FPU=y
```

**Note:** A boolean symbol can also be set to `n` with a comment formatted like this:

```bash
# CONFIG_SOME_OTHER_BOOL is not set
```

This is the format you will see in the merged configuration in `zephyr/.config`. This style is accepted for historical reasons: Kconfig configuration files can be parsed as makefiles (though Zephyr doesn’t use this). Having `n`-valued symbols correspond to unset variables simplifies tests in Make.

Other symbol types are assigned like this:

```bash
CONFIG_SOME_STRING="cool value"
CONFIG_SOME_INT=123
```

Comments use a `#`:

```bash
# This is a comment
```

Assignments in configuration files are only respected if the dependencies for the symbol are satisfied. A warning is printed otherwise. To figure out what the dependencies of a symbol are, use one of the *interactive configuration interfaces* (you can jump directly to a symbol with `/`), or look up the symbol in the Kconfig search page.

**The Initial Configuration**

The initial configuration for an application comes from merging configuration settings from three sources:

1. A BOARD-specific configuration file stored in `boards/<architecture>/<BOARD>/`<BOARD>_defconfig
2. Any CMake cache entries prefix with `CONFIG_`
3. The application configuration
The application configuration can come from the sources below (each file is known as a Kconfig fragment, which are then merged to get the final configuration used for a particular build). By default, prj.conf is used.

1. If CONF_FILE is set, the configuration file(s) specified in it are merged and used as the application configuration. CONF_FILE can be set in various ways:
   1. In CMakeLists.txt, before calling find_package(Zephyr)
   2. By passing -DCONF_FILE=<conf file(s)>, either directly or via west
   3. From the CMake variable cache

   Furthermore if CONF_FILE is set as single configuration file of the form prj_<build>.conf and if file boards/<BOARD>_<build>.conf exists in same folder as file prj_<build>.conf, the result of merging prj_<build>.conf and boards/<BOARD>_<build>.conf is used.

2. Otherwise, prj_<BOARD>.conf is used if it exists in the application configuration directory.

3. Otherwise, if boards/<BOARD>.conf exists in the application configuration directory, the result of merging it with prj.conf is used.

4. Otherwise, if board revisions are used and boards/<BOARD>_<revision>.conf exists in the application configuration directory, the result of merging it with prj.conf and boards/<BOARD>.conf is used.

5. Otherwise, prj.conf is used from the application configuration directory. If it does not exist then a fatal error will be emitted.

All configuration files will be taken from the application's configuration directory except for files with an absolute path that are given with the CONF_FILE, EXTRA_CONF_FILE, DTC_OVERLAY_FILE, and EXTRA_DTC_OVERLAY_FILE arguments. For these, a file in a Zephyr module can be referred by escaping the Zephyr module dir variable like this \${ZEPHYR_<module>_MODULE_DIR}/<path-to>/<file> when setting any of said variables in the application's CMakeLists.txt.

See Application Configuration Directory on how the application configuration directory is defined.

If a symbol is assigned both in <BOARD>_defconfig and in the application configuration, the value set in the application configuration takes precedence.

The merged configuration is saved to zephyr/.config in the build directory.

As long as zephyr/.config exists and is up-to-date (is newer than any BOARD and application configuration files), it will be used in preference to producing a new merged configuration. zephyr/.config is also the configuration that gets modified when making changes in the interactive configuration interfaces.

Configuring invisible Kconfig symbols

When making changes to the default configuration for a board, you might have to configure invisible symbols. This is done in boards/<architecture>/<BOARD>/Kconfig.defconfig, which is a regular Kconfig file.

Note: Assignments in .config files have no effect on invisible symbols, so this scheme is not just an organizational issue.

Assigning values in Kconfig.defconfig relies on defining a Kconfig symbol in multiple locations. As an example, say we want to set FOO_WIDTH below to 32:

```plaintext
config FOO_WIDTH
int
```

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To do this, we extend the definition of FOO_WIDTH as follows, in Kconfig.defconfig:

```c
if BOARD_MY_BOARD
    config FOO_WIDTH
default 32
endif
```

**Note:** Since the type of the symbol (int) has already been given at the first definition location, it does not need to be repeated here. Only giving the type once at the “base” definition of the symbol is a good idea for reasons explained in *Common Kconfig shorthands*.

Default values in Kconfig.defconfig files have priority over default values given on the “base” definition of a symbol. Internally, this is implemented by including the Kconfig.defconfig files first. Kconfig uses the first default with a satisfied condition, where an empty condition corresponds to `if y` (is always satisfied).

Note that conditions from surrounding top-level `if`s are propagated to symbol properties, so the above default is equivalent to `default 32 if BOARD_MY_BOARD`.

**Multiple symbol definitions**  When a symbol is defined in multiple locations, each definition acts as an independent symbol that happens to share the same name. This means that properties are not appended to previous definitions. If the conditions for ANY definition result in the symbol resolving to `y`, the symbol will be `y`. It is therefore not possible to make the dependencies of a symbol more restrictive by defining it in multiple locations.

For example, the dependencies of the symbol FOO below are satisfied if either `DEP1` OR `DEP2` are true, it does not require both:

```c
config FOO
    ...
depends on DEP1
config FOO
    ...
depends on DEP2
```

**Warning:** Symbols without explicit dependencies still follow the above rule. A symbol without any dependencies will result in the symbol always being assignable. The definition below will result in FOO always being enabled by default, regardless of the value of `DEP1`.

```c
config FOO
    bool "FOO"
depends on DEP1
config FOO
    default y
```

This dependency weakening can be avoided with the `configdefault` extension if the desire is only to add a new default without modifying any other behaviour of the symbol.

**Note:** When making changes to Kconfig.defconfig files, always check the symbol's direct dependencies in one of the *interactive configuration interfaces* afterwards. It is often necessary to repeat dependencies from the base definition of the symbol to avoid weakening a symbol's dependencies.
Motivation for Kconfig.defconfig files  One motivation for this configuration scheme is to avoid making fixed BOARD-specific settings configurable in the interactive configuration interfaces. If all board configuration were done via <BOARD>_defconfig, all symbols would have to be visible, as values given in <BOARD>_defconfig have no effect on invisible symbols.

Having fixed settings be user-configurable would clutter up the configuration interfaces and make them harder to understand, and would make it easier to accidentally create broken configurations.

When dealing with fixed board-specific settings, also consider whether they should be handled via devicetree instead.

Configuring choices  There are two ways to configure a Kconfig choice:

1. By setting one of the choice symbols to y in a configuration file.

   Setting one choice symbol to y automatically gives all other choice symbols the value n.

   If multiple choice symbols are set to y, only the last one set to y will be honored (the rest will get the value n). This allows a choice selection from a board defconfig file to be overridden from an application prj.conf file.

2. By changing the default of the choice in Kconfig.defconfig.

   As with symbols, changing the default for a choice is done by defining the choice in multiple locations. For this to work, the choice must have a name.

   As an example, assume that a choice has the following base definition (here, the name of the choice is FOO):

   ```
   choice FOO
       bool "Foo choice"
       default B
   config A
       bool "A"
   config B
       bool "B"
   endchoice
   ```

   To change the default symbol of FOO to A, you would add the following definition to Kconfig.defconfig:

   ```
   choice FOO
       default A
   endchoice
   ```

   The Kconfig.defconfig method should be used when the dependencies of the choice might not be satisfied. In that case, you're setting the default selection whenever the user makes the choice visible.

More Kconfig resources  The Kconfig - Tips and Best Practices page has some tips for writing Kconfig files.

The kconfiglib.py docstring (at the top of the file) goes over how symbol values are calculated in detail.
5.3.3 Kconfig - Tips and Best Practices

This page covers some Kconfig best practices and explains some Kconfig behaviors and features that might be cryptic or that are easily overlooked.

Note: The official Kconfig documentation is kconfig-language.rst and kconfig-macro-language.rst.

- What to turn into Kconfig options
- What not to turn into Kconfig options
  - Options that specify a device in the system by name
  - Options that specify fixed hardware configuration
- select statements
  - select pitfalls
  - Alternatives to select
  - Using select for helper symbols
  - select recommendations
- (Lack of) conditional includes
- “Stuck” symbols in menuconfig and guiconfig
- Assignments to promptless symbols in configuration files
- depends on and string/int/hex symbols
- menuconfig symbols
- Commas in macro arguments
- Checking changes in menuconfig/guiconfig
- Checking changes with scripts/kconfig/lint.py
- Style recommendations and shorthands
  - Factoring out common dependencies
  - Redundant defaults
  - Common Kconfig shorthands
  - Prompt strings
  - Header comments and other nits
- Lesser-known/used Kconfig features
  - The imply statement
  - Optional prompts
  - Optional choices
  - visible if conditions
- Other resources
What to turn into Kconfig options

When deciding whether something belongs in Kconfig, it helps to distinguish between symbols that have prompts and symbols that don't.

If a symbol has a prompt (e.g. `bool "Enable foo"`), then the user can change the symbol's value in the menuconfig or guiconfig interface (see Interactive Kconfig interfaces), or by manually editing configuration files. Conversely, a symbol without a prompt can never be changed directly by the user, not even by manually editing configuration files.

Only put a prompt on a symbol if it makes sense for the user to change its value. Symbols without prompts are called hidden or invisible symbols, because they don't show up in menuconfig and guiconfig. Symbols that have prompts can also be invisible, when their dependencies are not satisfied.

Symbols without prompts can't be configured directly by the user (they derive their value from other symbols), so less restrictions apply to them. If some derived setting is easier to calculate in Kconfig than e.g. during the build, then do it in Kconfig, but keep the distinction between symbols with and without prompts in mind.

See the optional prompts section for a way to deal with settings that are fixed on some machines and configurable on other machines.

What not to turn into Kconfig options

In Zephyr, Kconfig configuration is done after selecting a target board. In general, it does not make sense to use Kconfig for a value that corresponds to a fixed machine-specific setting. Usually, such settings should be handled via devicetree instead.

In particular, avoid adding new Kconfig options of the following types:

Options that specify a device in the system by name  
For example, if you are writing an I2C device driver, avoid creating an option named `MY_DEVICE_I2C_BUS_NAME` for specifying the bus node your device is controlled by. See Device drivers that depend on other devices for alternatives.

Similarly, if your application depends on a hardware-specific PWM device to control an RGB LED, avoid creating an option like `MY_PWM_DEVICE_NAME`. See Applications that depend on board-specific devices for alternatives.

Options that specify fixed hardware configuration  
For example, avoid Kconfig options specifying a GPIO pin.

An alternative applicable to device drivers is to define a GPIO specifier with type phandle-array in the device binding, and using the GPIO devicetree API from C. Similar advice applies to other cases where devicetree.h provides Hardware specific APIs for referring to other nodes in the system. Search the source code for drivers using these APIs for examples.

An application-specific devicetree binding to identify board specific properties may be appropriate. See tests/drivers/gpio/gpio_basic_api for an example.

For applications, see blinky for a devicetree-based alternative.

select statements

The select statement is used to force one symbol to y whenever another symbol is y. For example, the following code forces CONSOLE to y whenever USB_CONSOLE is y:
This section covers some pitfalls and good uses for `select`.

**select pitfalls**  
select might seem like a generally useful feature at first, but can cause configuration issues if overused.

For example, say that a new dependency is added to the CONSOLE symbol above, by a developer who is unaware of the USB_CONSOLE symbol (or simply forgot about it):

```plaintext
config CONSOLE
  bool "Console support"
...
config USB_CONSOLE
  bool "USB console support"
  select CONSOLE
depends on STRING_ROUTINES
```

Enabling USB_CONSOLE now forces CONSOLE to `y`, even if STRING_ROUTINES is `n`.

To fix the problem, the STRING_ROUTINES dependency needs to be added to USB_CONSOLE as well:

```plaintext
config USB_CONSOLE
  bool "USB console support"
  select CONSOLE
  depends on STRING_ROUTINES
...
config STRING_ROUTINES
  bool "Include string routines"
```

More insidious cases with dependencies inherited from `if` and `menu` statements are common.

An alternative attempt to solve the issue might be to turn the `depends on` into another `select`:

```plaintext
config CONSOLE
  bool "Console support"
  select STRING_ROUTINES
...
config USB_CONSOLE
  bool "USB console support"
  select CONSOLE
```

In practice, this often amplifies the problem, because any dependencies added to STRING_ROUTINES now need to be copied to both CONSOLE and USB_CONSOLE.

In general, whenever the dependencies of a symbol are updated, the dependencies of all symbols that (directly or indirectly) select it have to be updated as well. This is very often overlooked in practice, even for the simplest case above.

Chains of symbols selecting each other should be avoided in particular, except for simple helper symbols, as covered below in *Using select for helper symbols*.

Liberal use of `select` also tends to make Kconfig files harder to read, both due to the extra dependencies and due to the non-local nature of `select`, which hides ways in which a symbol might get enabled.
Alternatives to select  For the example in the previous section, a better solution is usually to turn the select into a depends on:

```c
config CONSOLE
    bool "Console support"

...

config USB_CONSOLE
    bool "USB console support"
    depends on CONSOLE
```

This makes it impossible to generate an invalid configuration, and means that dependencies only ever have to be updated in a single spot.

An objection to using depends on here might be that configuration files that enable USB_CONSOLE now also need to enable CONSOLE:

```plaintext
CONFIG_CONSOLE=y
CONFIG_USB_CONSOLE=y
```

This comes down to a trade-off, but if enabling CONSOLE is the norm, then a mitigation is to make CONSOLE default to y:

```c
config CONSOLE
    bool "Console support"
    default y
```

This gives just a single assignment in configuration files:

```plaintext
CONFIG_USB_CONSOLE=y
```

Note that configuration files that do not want CONSOLE enabled now have to explicitly disable it:

```plaintext
CONFIG_CONSOLE=n
```

Using select for helper symbols  A good and safe use of select is for setting “helper” symbols that capture some condition. Such helper symbols should preferably have no prompt or dependencies.

For example, a helper symbol for indicating that a particular CPU/SoC has an FPU could be defined as follows:

```c
config CPU_HAS_FPU
    bool
    help If y, the CPU has an FPU

...

config SOC_FOO
    bool "FOO SoC"
    select CPU_HAS_FPU

...

config SOC_BAR
    bool "BAR SoC"
    select CPU_HAS_FPU
```

This makes it possible for other symbols to check for FPU support in a generic way, without having to look for particular architectures:
The alternative would be to have dependencies like the following, possibly duplicated in several spots:

```
config FPU
    bool "Support floating point operations"
    depends on CPU_HAS_FPU
```

Invisible helper symbols can also be useful without select. For example, the following code defines a helper symbol that has the value \( y \) if the machine has some arbitrarily-defined “large” amount of memory:

```
config LARGE_MEM
    def_bool MEM_SIZE >= 64
```

**Note:** This is short for the following:

```
config LARGE_MEM
    bool
    default MEM_SIZE >= 64
```

**select recommendations**  In summary, here are some recommended practices for select:

- Avoid selecting symbols with prompts or dependencies. Prefer depends on. If depends on causes annoying bloat in configuration files, consider adding a Kconfig default for the most common value.

  Rare exceptions might include cases where you're sure that the dependencies of the selecting and selected symbol will never drift out of sync, e.g. when dealing with two simple symbols defined close to one another within the same if.

  Common sense applies, but be aware that select often causes issues in practice. depends on is usually a cleaner and safer solution.

- Select simple helper symbols without prompts and dependencies however much you like. They're a great tool for simplifying Kconfig files.

**(Lack of) conditional includes**

if blocks add dependencies to each item within the if, as if depends on was used.

A common misunderstanding related to if is to think that the following code conditionally includes the file Kconfig.other:

```
if DEP
    source "Kconfig.other"
endif
```

In reality, there are no conditional includes in Kconfig. if has no special meaning around a source.

**Note:** Conditional includes would be impossible to implement, because if conditions may contain (either directly or indirectly) forward references to symbols that haven't been defined yet.
Say that `Kconfig.other` above contains this definition:

```plaintext
config FOO
  bool "Support foo"
```

In this case, `FOO` will end up with this definition:

```plaintext
config FOO
  bool "Support foo"
daeps on DEP
```

Note that it is redundant to add `depends on DEP` to the definition of `FOO` in `Kconfig.other`, because the `DEP` dependency has already been added by `if DEP`.

In general, try to avoid adding redundant dependencies. They can make the structure of the `Kconfig` files harder to understand, and also make changes more error-prone, since it can be hard to spot that the same dependency is added twice.

### “Stuck” symbols in `menuconfig` and `guiconfig`

There is a common subtle gotcha related to interdependent configuration symbols with prompts. Consider these symbols:

```plaintext
config FOO
  bool "Foo"

cfign STACK_SIZE
  hex "Stack size"
  default 0x200 if FOO
  default 0x100
```

Assume that the intention here is to use a larger stack whenever `FOO` is enabled, and that the configuration initially has `FOO` disabled. Also, remember that Zephyr creates an initial configuration in `zephyr/.config` in the build directory by merging configuration files (including e.g. `prj.conf`). This configuration file exists before `menuconfig` or `guiconfig` is run.

When first entering the configuration interface, the value of `STACK_SIZE` is 0x100, as expected. After enabling `FOO`, you might reasonably expect the value of `STACK_SIZE` to change to 0x200, but it stays as 0x100.

To understand what’s going on, remember that `STACK_SIZE` has a prompt, meaning it is user-configurable, and consider that all `Kconfig` has to go on from the initial configuration is this:

```
CONFIG_STACK_SIZE=0x100
```

Since `Kconfig` can’t know if the 0x100 value came from a `default` or was typed in by the user, it has to assume that it came from the user. Since `STACK_SIZE` is user-configurable, the value from the configuration file is respected, and any symbol defaults are ignored. This is why the value of `STACK_SIZE` appears to be “frozen” at 0x100 when toggling `FOO`.

The right fix depends on what the intention is. Here’s some different scenarios with suggestions:

- If `STACK_SIZE` can always be derived automatically and does not need to be user-configurable, then just remove the prompt:

  ```plaintext
  config STACK_SIZE
    hex
    default 0x200 if FOO
    default 0x100
  ```

  Symbols without prompts ignore any value from the saved configuration.
• If \texttt{STACK\_SIZE} should usually be user-configurable, but needs to be set to 0x200 when \texttt{FOO} is enabled, then disable its prompt when \texttt{FOO} is enabled, as described in \textit{optional prompts}:

```
config STACK\_SIZE
  hex "Stack size" if !\texttt{FOO}
  default 0x200 if \texttt{FOO}
  default 0x100
```

• If \texttt{STACK\_SIZE} should usually be derived automatically, but needs to be set to a custom value in rare circumstances, then add another option for making \texttt{STACK\_SIZE} user-configurable:

```
config CUSTOM\_STACK\_SIZE
  bool "Use a custom stack size"
  help Enable this if you need to use a custom stack size. When disabled, a suitable stack size is calculated automatically.

config STACK\_SIZE
  hex "Stack size" if CUSTOM\_STACK\_SIZE
  default 0x200 if \texttt{FOO}
  default 0x100
```

As long as \texttt{CUSTOM\_STACK\_SIZE} is disabled, \texttt{STACK\_SIZE} will ignore the value from the saved configuration.

It is a good idea to try out changes in the \texttt{menuconfig} or \texttt{guiconfig} interface, to make sure that things behave the way you expect. This is especially true when making moderately complex changes like these.

\textbf{Assignments to promptless symbols in configuration files}

Assignments to hidden (promptless, also called \textit{invisible}) symbols in configuration files are always ignored. Hidden symbols get their value indirectly from other symbols, via e.g. \texttt{default} and \texttt{select}.

A common source of confusion is opening the output configuration file (\texttt{zephyr/.config}), seeing a bunch of assignments to hidden symbols, and assuming that those assignments must be respected when the configuration is read back in by Kconfig. In reality, all assignments to hidden symbols in \texttt{zephyr/.config} are ignored by Kconfig, like for other configuration files.

To understand why \texttt{zephyr/.config} still includes assignments to hidden symbols, it helps to realize that \texttt{zephyr/.config} serves two separate purposes:

1. It holds the saved configuration, and
2. It holds configuration output. \texttt{zephyr/.config} is parsed by the CMake files to let them query configuration settings, for example.

The assignments to hidden symbols in \texttt{zephyr/.config} are just configuration output. Kconfig itself ignores assignments to hidden symbols when calculating symbol values.

\textbf{Note:} A \textit{minimal configuration}, which can be generated from within the \texttt{menuconfig} and \texttt{guiconfig interfaces}, could be considered closer to just a saved configuration, without the full configuration output.

\textbf{depends on and string/int/hex symbols}

\textbf{depends on} works not just for \texttt{bool} symbols, but also for \texttt{string}, \texttt{int}, and \texttt{hex} symbols (and for choices).
The Kconfig definitions below will hide the FOO_DEVICE_FREQUENCY symbol and disable any configuration output for it when FOO_DEVICE is disabled.

```plaintext
config FOO_DEVICE
  bool "Foo device"

config FOO_DEVICE_FREQUENCY
  int "Foo device frequency"
  depends on FOO_DEVICE
```

In general, it's a good idea to check that only relevant symbols are ever shown in the menuconfig/guiconfig interface. Having FOO_DEVICE_FREQUENCY show up when FOO_DEVICE is disabled (and possibly hidden) makes the relationship between the symbols harder to understand, even if code never looks at FOO_DEVICE_FREQUENCY when FOO_DEVICE is disabled.

**menuconfig symbols**

If the definition of a symbol FOO is immediately followed by other symbols that depend on FOO, then those symbols become children of FOO. If FOO is defined with `config FOO`, then the children are shown indented relative to FOO. Defining FOO with `menuconfig FOO` instead puts the children in a separate menu rooted at FOO.

`menuconfig` has no effect on evaluation. It's just a display option.

`menuconfig` can cut down on the number of menus and make the menu structure easier to navigate. For example, say you have the following definitions:

```plaintext
menu "Foo subsystem"

config FOO_SUBSYSTEM
  bool "Foo subsystem"

if FOO_SUBSYSTEM

  config FOO_FEATURE_1
      bool "Foo feature 1"

  config FOO_FEATURE_2
      bool "Foo feature 2"

  config FOO_FREQUENCY
      int "Foo frequency"

... lots of other FOO-related symbols

endif # FOO_SUBSYSTEM

endmenu
```

In this case, it's probably better to get rid of the `menu` and turn FOO_SUBSYSTEM into a `menuconfig` symbol:

```plaintext
menuconfig FOO_SUBSYSTEM
  bool "Foo subsystem"

if FOO_SUBSYSTEM

  config FOO_FEATURE_1
      bool "Foo feature 1"

  config FOO_FEATURE_2

```
bool "Foo feature 2"

config FOO_FREQUENCY
    int "Foo frequency"

... lots of other FOO-related symbols

endif # FOO_SUBSYSTEM

In the menuconfig interface, this will be displayed as follows:

[*] Foo subsystem --->

Note that making a symbol without children a menuconfig is meaningless. It should be avoided, because it looks identical to a symbol with all children invisible:

[*] I have no children ----
[*] All my children are invisible ----

Commas in macro arguments

Kconfig uses commas to separate macro arguments. This means a construct like this will fail:

config FOO
    bool default y if $(dt_chosen_enabled,"zephyr,bar")

To solve this problem, create a variable with the text and use this variable as argument, as follows:

DT_CHOSEN_ZEPHYR_BAR := zephyr,bar

config FOO
    bool default y if $(dt_chosen_enabled,$(DT_CHOSEN_ZEPHYR_BAR))

Checking changes in menuconfig/guiconfig

When adding new symbols or making other changes to Kconfig files, it is a good idea to look up the symbols in menuconfig or guiconfig afterwards. To get to a symbol quickly, use the jump-to feature (press /).

Here are some things to check:

- Are the symbols placed in a good spot? Check that they appear in a menu where they make sense, close to related symbols.

  If one symbol depends on another, then it's often a good idea to place it right after the symbol it depends on. It will then be shown indented relative to the symbol it depends on in the menuconfig interface, and in a separate menu rooted at the symbol in guiconfig. This also works if several symbols are placed after the symbol they depend on.

- Is it easy to guess what the symbols do from their prompts?

- If many symbols are added, do all combinations of values they can be set to make sense?

  For example, if two symbols FOO_SUPPORT and NO_FOO_SUPPORT are added, and both can be enabled at the same time, then that makes a nonsensical configuration. In this case, it's probably better to have a single FOO_SUPPORT symbol.
• Are there any duplicated dependencies?
  This can be checked by selecting a symbol and pressing ? to view the symbol information. If there are duplicated dependencies, then use the Included via … path shown in the symbol information to figure out where they come from.

Checking changes with scripts/kconfig/lint.py

After you make Kconfig changes, you can use the scripts/kconfig/lint.py script to check for some potential issues, like unused symbols and symbols that are impossible to enable. Use --help to see available options.

Some checks are necessarily a bit heuristic, so a symbol being flagged by a check does not necessarily mean there’s a problem. If a check returns a false positive e.g. due to token pasting in C (CONFIG_FOO_##index##_BAR), just ignore it.

When investigating an unknown symbol FOO_BAR, it is a good idea to run git grep FOO_BAR to look for references. It is also a good idea to search for some components of the symbol name with e.g. git grep FOO and git grep BAR, as it can help uncover token pasting.

Style recommendations and shorthands

This section gives some style recommendations and explains some common Kconfig shorthands.

Factoring out common dependencies  If a sequence of symbols/choices share a common dependency, the dependency can be factored out with an if.

As an example, consider the following code:

```c
config FOO
  bool "Foo"
  depends on DEP

config BAR
  bool "Bar"
  depends on DEP

choice
  prompt "Choice"
  depends on DEP

config BAZ
  bool "Baz"

config QAZ
  bool "Qaz"
endchoice
```

Here, the DEP dependency can be factored out like this:

```c
if DEP

config FOO
  bool "Foo"

config BAR
  bool "Bar"
```

(continues on next page)
Note: Internally, the second version of the code is transformed into the first.

If a sequence of symbols/choices with shared dependencies are all in the same menu, the dependency can be put on the menu itself:

```c
menu "Foo features"
    depends on FOO_SUPPORT

config FOO_FEATURE_1
    bool "Foo feature 1"

config FOO_FEATURE_2
    bool "Foo feature 2"
endmenu
```

If FOO_SUPPORT is n, the entire menu disappears.

**Redundant defaults** bool symbols implicitly default to n, and string symbols implicitly default to the empty string. Therefore, default n and default "" are (almost) always redundant.

The recommended style in Zephyr is to skip redundant defaults for bool and string symbols. That also generates clearer documentation: *(Implicitly defaults to n instead of n if <dependencies, possibly inherited>).*

Defaults should always be given for int and hex symbols, however, as they implicitly default to the empty string. This is partly for compatibility with the C Kconfig tools, though an implicit 0 default might be less likely to be what was intended compared to other symbol types as well.

The one case where default n/default "" is not redundant is when defining a symbol in multiple locations and wanting to override e.g. a default y on a later definition. Note that a default n does not override a previously defined default y.

That is, FOO will be set to n in the example below. If the default n was omitted in the first definition, FOO would have been set to y.

```c
config FOO
    bool "foo"
    default n

config FOO
    bool "foo"
    default y
```

In the following example FOO will get the value y.
Common Kconfig shorthands  Kconfig has two shorthands that deal with prompts and defaults.

- `<type> "prompt"` is a shorthand for giving a symbol/choice a type and a prompt at the same time. These two definitions are equal:

  ```
  config FOO
  bool "foo"
  ```

  ```
  config FOO
  bool
  prompt "foo"
  ```

  The first style, with the shorthand, is preferred in Zephyr.

- `def_<type> <value>` is a shorthand for giving a type and a value at the same time. These two definitions are equal:

  ```
  config FOO
  def_bool BAR & & BAZ
  ```

  ```
  config FOO
  bool
  default BAR & & BAZ
  ```

  Using both the `<type> "prompt"` and the `def_<type> <value>` shorthand in the same definition is redundant, since it gives the type twice.

  The `def_<type> <value>` shorthand is generally only useful for symbols without prompts, and somewhat obscure.

  **Note:** For a symbol defined in multiple locations (e.g., in a Kconfig.defconfig file in Zephyr), it is best to only give the symbol type for the “base” definition of the symbol, and to use `default` (instead of `def_<type> value`) for the remaining definitions. That way, if the base definition of the symbol is removed, the symbol ends up without a type, which generates a warning that points to the other definitions. That makes the extra definitions easier to discover and remove.

Prompt strings  For a Kconfig symbol that enables a driver/subsystem FOO, consider having just “Foo” as the prompt, instead of “Enable Foo support” or the like. It will usually be clear in the context of an option that can be toggled on/off, and makes things consistent.

Header comments and other nits  A few formatting nits, to help keep things consistent:

- Use this format for any header comments at the top of Kconfig files:

  ```
  # <Overview of symbols defined in the file, preferably in plain English>
  (Blank line)
  # Copyright (c) 2019 ...
  ```
# Kconfig definitions

- Format comments as `# Comment` rather than `#Comment`
- Put a blank line before/after each top-level `if` and `endif`
- Use a single tab for each indentation
- Indent help text with two extra spaces

## Lesser-known/used Kconfig features

This section lists some more obscure Kconfig behaviors and features that might still come in handy.

### The `imply` statement

The `imply` statement is similar to `select`, but respects dependencies and doesn't force a value. For example, the following code could be used to enable USB keyboard support by default on the FOO SoC, while still allowing the user to turn it off:

```c
config SOC_FOO
  bool "FOO SoC"
  imply USB_KEYBOARD

...

config USB_KEYBOARD
  bool "USB keyboard support"
```

`imply` acts like a suggestion, whereas `select` forces a value.

### Optional prompts

A condition can be put on a symbol's prompt to make it optionally configurable by the user. For example, a value `MASK` that's hardcoded to `0xFF` on some boards and configurable on others could be expressed as follows:

```c
config MASK
  hex "Bitmask" if HAS_CONFIGURABLE_MASK
  default 0xFF
```

**Note:** This is short for the following:

```c
config MASK
  hex
    prompt "Bitmask" if HAS_CONFIGURABLE_MASK
    default 0xFF
```

The `HAS_CONFIGURABLE_MASK` helper symbol would get selected by boards to indicate that `MASK` is configurable. When `MASK` is configurable, it will also default to `0xFF`.

### Optional choices

Defining a choice with the `optional` keyword allows the whole choice to be toggled off to select none of the symbols:
In the menuconfig interface, this will be displayed e.g. as [x] Use legacy protocol (Legacy protocol 1) --->, where the choice can be toggled off to enable neither of the symbols.

**visible if conditions** Putting a `visible if` condition on a menu hides the menu and all the symbols within it, while still allowing symbol default values to kick in.

As a motivating example, consider the following code:

```
menu "Foo subsystem"
  depends on HAS_CONFIGURABLE_FOO

config FOO_SETTING_1
  int "Foo setting 1"
  default 1

config FOO_SETTING_2
  int "Foo setting 2"
  default 2
endmenu
```

When `HAS_CONFIGURABLE_FOO` is n, no configuration output is generated for `FOO_SETTING_1` and `FOO_SETTING_2`, as the code above is logically equivalent to the following code:

```
config FOO_SETTING_1
  int "Foo setting 1"
  default 1
  depends on HAS_CONFIGURABLE_FOO

config FOO_SETTING_2
  int "Foo setting 2"
  default 2
  depends on HAS_CONFIGURABLE_FOO
```

If we want the symbols to still get their default values even when `HAS_CONFIGURABLE_FOO` is n, but not be configurable by the user, then we can use `visible if` instead:

```
menu "Foo subsystem"
  visible if HAS_CONFIGURABLE_FOO

config FOO_SETTING_1
  int "Foo setting 1"
  default 1

config FOO_SETTING_2
  int "Foo setting 2"
  default 2
endmenu
```
This is logically equivalent to the following:

```
config FOO_SETTING_1
  int "Foo setting 1" if HAS_CONFIGURABLE_FOO
  default 1
config FOO_SETTING_2
  int "Foo setting 2" if HAS_CONFIGURABLE_FOO
  default 2
```

**Note:** See the *optional prompts* section for the meaning of the conditions on the prompts.

When HAS_CONFIGURABLE is n, we now get the following configuration output for the symbols, instead of no output:

```
... CONFIG_FOO_SETTING_1=1 CONFIG_FOO_SETTING_2=2 ...
```

**Other resources**

The *Intro to symbol values* section in the *Kconfiglib docstring* goes over how symbols values are calculated in more detail.

### 5.3.4 Custom Kconfig Preprocessor Functions

Kconfiglib supports custom Kconfig preprocessor functions written in Python. These functions are defined in `scripts/kconfig/kconfigfunctions.py`.

**Note:** The official Kconfig preprocessor documentation can be found [here](#).

Most of the custom preprocessor functions are used to get devicetree information into Kconfig. For example, the default value of a Kconfig symbol can be fetched from a devicetree `reg` property.

#### Devicetree-related Functions

The functions listed below are used to get devicetree information into Kconfig. See the Python docstrings in `scripts/kconfig/kconfigfunctions.py` for detailed documentation.

The `*_int` version of each function returns the value as a decimal integer, while the `*_hex` version returns a hexadecimal value starting with `0x`.

```
$(dt_alias_enabled,<node alias>)
$(dt_chosen_bool_prop, <property in /chosen>, <prop>)
$(dt_chosen_enabled,<property in /chosen>)
$(dt_chosen_has_compat,<property in /chosen>)
$(dt_chosen_label,<property in /chosen>)
$(dt_chosen_path,<property in /chosen>)
$(dt_chosen_reg_addr_hex,<property in /chosen>[,<index>,<unit>])
$(dt_chosen_reg_addr_int,<property in /chosen>[,<index>,<unit>])
$(dt_chosen_reg_size_hex,<property in /chosen>[,<index>,<unit>])
$(dt_chosen_reg_size_int,<property in /chosen>[,<index>,<unit>])
$(dt_compat_enabled,<compatible string>)
```

(continues on next page)
Example Usage  Assume that the devicetree for some board looks like this:

```c
{
    soc {
        #address-cells = <1>;
        #size-cells = <1>;

        spi0: spi@0014000 {
            compatible = "sifive_spi0";
            reg = <0x20014000 0x1000 0x20010000 0x3c09000>;
            reg-names = "control", "mem";
            ...;
        }
    }
};
```

The second entry in reg in spi@0014000 (0x20014000 0x1000 0x20010000 0x3c09000) corresponds to mem, and has the address 0x20010000. This address can be inserted into Kconfig as follows:

```plaintext
config FLASH_BASE_ADDRESS
    default $(dt_node_reg_addr_hex,/soc/spi@0014000,1)
```

After preprocessor expansion, this turns into the definition below:

```plaintext
config FLASH_BASE_ADDRESS
    default 0x20010000
```

### 5.3.5 Kconfig extensions

Zephyr uses the Kconfiglib implementation of Kconfig, which includes some Kconfig extensions:
• Default values can be applied to existing symbols without weakening the symbols dependencies through the use of `configdefault`.

```
config FOO
  bool "FOO"
  depends on BAR
configdefault FOO
  default y if FIZZ
```

The statement above is equivalent to:

```
config FOO
  bool "Foo"
  default y if FIZZ
  depends on BAR
configdefault FOO
```

`configdefault` symbols cannot contain any fields other than `default`, however they can be wrapped in `if` statements. The two statements below are equivalent:

```
configdefault FOO
  default y if BAR
if BAR
configdefault FOO
  default y
endif # BAR
```

• Environment variables in `source` statements are expanded directly, meaning no “bounce” symbols with option `env="ENV_VAR"` need to be defined.

**Note:** option `env` has been removed from the C tools as of Linux 4.18 as well.

The recommended syntax for referencing environment variables is `${FOO}` rather than `$FOO`. This uses the new Kconfig preprocessor. The `${FOO}` syntax for expanding environment variables is only supported for backwards compatibility.

• The `source` statement supports glob patterns and includes each matching file. A pattern is required to match at least one file.

Consider the following example:

```
source "foo/bar/*/Kconfig"
```

If the pattern `foo/bar/*/Kconfig` matches the files `foo/bar/baz/Kconfig` and `foo/bar/qaz/Kconfig`, the statement above is equivalent to the following two `source` statements:

```
source "foo/bar/baz/Kconfig"
source "foo/bar/qaz/Kconfig"
```

If no files match the pattern, an error is generated.

The wildcard patterns accepted are the same as for the Python `glob` module.

For cases where it's okay for a pattern to match no files (or for a plain filename to not exist), a separate `osource` (optional `source`) statement is available. `osource` is a no-op if no file matches.

**Note:** `source` and `osource` are analogous to `include` and `-include` in Make.
• An `source` statement is available for including files specified with a relative path. The path is relative to the directory of the `Kconfig` file that contains the `source` statement.

As an example, assume that `foo/Kconfig` is the top-level `Kconfig` file, and that `foo/bar/Kconfig` has the following statements:

```
source "qaz/Kconfig1"
source "qaz/Kconfig2"
```

This will include the two files `foo/qaz/Kconfig1` and `foo/bar/qaz/Kconfig2`.

`source` can be used to create `Kconfig` “subtrees” that can be moved around freely.

`source` also supports glob patterns.

A drawback of `source` is that it can make it harder to figure out where a file gets included, so only use it if you need it.

• An `orsource` statement is available that combines `osource` and `source`.

For example, the following statement will include `Kconfig1` and `Kconfig2` from the current directory (if they exist):

```
orsource "Kconfig[12]"
```

• `def_int`, `def_hex`, and `def_string` keywords are available, analogous to `def_bool`. These set the type and add a default at the same time.

Users interested in optimizing their configuration for security should refer to the Zephyr Security Guide's section on the Hardening Tool.

## 5.4 Snippets

Snippets are a way to save build system settings in one place, and then use those settings when you build any Zephyr application. This lets you save common configuration separately when it applies to multiple different applications.

Some example use cases for snippets are:

• changing your board's console backend from a “real” UART to a USB CDC-ACM UART

• enabling frequently-used debugging options

• applying interrelated configuration settings to your “main” CPU and a co-processor core on an AMP SoC

The following pages document this feature.

### 5.4.1 Using Snippets

**Tip:** See `Built-in snippets` for a list of snippets that are provided by Zephyr.

Snippets have names. You use snippets by giving their names to the build system.

**With west build**

To use a snippet named `foo` when building an application app:
west build -S foo app

To use multiple snippets:
west build -S snippet1 -S snippet2 [...] app

With cmake

If you are running CMake directly instead of using west build, use the SNIPPET variable. This is a whitespace- or semicolon-separated list of snippet names you want to use. For example:
cmake -Sapp -Bbuild -DSNIPPET="snippet1;snippet2" [...] 
cmake --build build

Application required snippets

If an application should always be compiled with a given snippet, it can be added to that application's CMakeLists.txt file. For example:

```cmake
if(NOT snippet1 IN_LIST SNIPPET)
  set(SNIPPET snippet1 ${SNIPPET} CACHE STRING "" FORCE)
endif()
find_package(Zephyr ....)
```

### 5.4.2 Built-in snippets

**CDC-ACM Console Snippet (cdc-acm-console)**

west build -S cdc-acm-console [...] 

**Overview**  This snippet redirects serial console output to a CDC ACM UART. The USB device which should be used is configured using Devicetree.

**Requirements**  Hardware support for:

- CONFIG_USB_DEVICE_STACK
- CONFIG_SERIAL
- CONFIG_CONSOLE
- CONFIG_UART_CONSOLE
- CONFIG_UART_LINE_CTRL

A devicetree node with node label zephyr_udc0 that points to an enabled USB device node with driver support. This should look roughly like this in your devicetree:

```plaintext
zephyr_udc0: usbd@deadbeef {
    compatible = "vnd,usb-device";
}/* ... */
```
**Nordic PPR snippet (nordic-ppr)**

**Overview**  This snippet allows users to build Zephyr with the capability to boot Nordic PPR (Peripheral Processor) from another core.

**Xen Dom0: universal snippet for XEN control domain**

**Overview**  This snippet allows user to build Zephyr as a Xen initial domain (Dom0). The feature is implemented as configuration snippet to allow support for any compatible platform.

**How to add support of a new board**

- add board dts overlay to this snippet which deletes/adds memory and deletes UART nodes;
- add correct memory and hypervisor nodes, based on regions Xen picked for Domain-0 on your setup.

**Programming**  Correct snippet designation for Xen must be entered when you invoke `west build`. For example:

```
west build -b qemu_cortex_a53 -S xen_dom0 samples/synchronization
```

**QEMU example with Xen**  Overlay for qemu_cortex_a53 board, that is present in `board/` directory of this snippet is QEMU Xen control domain example. To run such setup, you need to:

- fetch and build Xen (e.g. RELEASE-4.17.0) for arm64 platform
- take and compile sample device tree from `example/` directory
- build your Zephyr sample/application with `xen_dom0` snippet and start it as Xen control domain

For starting you can use QEMU from Zephyr SDK by following command:

```
<path to Zephyr SDK>/sysroots/x86_64-pokysdk-linux/usr/bin/qemu-system-aarch64 -cpu cortex-a53 -m 6G -nographic -machine virt,gic-version=3,virtualization=true -chardev stdio,id=con,mux=on -serial chardev:con -mon chardev=con,mode=readline -pidfile qemu.pid -device loader,file=<path to Zephyr app build>/zephyr.bin,addr=0x40600000 -dtb <path to DTB>/xen.dtb -kernel <path to Xen build>/xen
```

This will start you a Xen hypervisor with your application as Xen control domain. To make it usable, you can add `zephyr-xenlib` by Xen-troops library to your project. It'll provide basic domain management functionalities - domain creation and configuration.

### 5.4.3 Writing Snippets

- **Basics**
- **Namespaceing**
- **Where snippets are located**
- **Processing order**
- **Devicetree overlays (.overlay)**
Basics

Snippets are defined using YAML files named `snippet.yml`. A `snippet.yml` file contains the name of the snippet, along with additional build system settings, like this:

```
name: snippet-name
# ... build system settings go here ...
```

Build system settings go in other keys in the file as described later on in this page. You can combine settings whenever they appear under the same keys. For example, you can combine a snippet-specific devicetree overlay and a `.conf` file like this:

```
name: foo
append:
  EXTRA_DTC_OVERLAY_FILE: foo.overlay
  EXTRA_CONF_FILE: foo.conf
```

NAMESPACE

When writing devicetree overlays in a snippet, use `snippet_<name>` or `snippet-<name>` as a namespace prefix when choosing names for node labels, node names, etc. This avoids namespace conflicts. For example, if your snippet is named `foo-bar`, write your devicetree overlays like this:

```
chosen {
    zephyr,baz = &snippet_foo_bar_dev;
};

snippet_foo_bar_dev: device@12345678 {
    /* ... */
};
```

Where snippets are located

The build system looks for snippets in these places:

1. In directories configured by the `SNIPPET_ROOT` CMake variable. This always includes the zephyr repository (so `snippets/` is always a source of snippets) and the application source directory (so `<app>/snippets` is also).

   Additional directories can be added manually at CMake time.

   The variable is a whitespace- or semicolon-separated list of directories which may contain snippet definitions.
For each directory in the list, the build system looks for snippet.yml files underneath a subdirectory named snippets/, if one exists.

For example, if SNIPPET_ROOT is set to /foo;/bar, the build system will look for snippet.yml files underneath the following subdirectories:

- /foo/snippets/
- /bar/snippets/

The snippet.yml files can be nested anywhere underneath these locations.

2. In any module whose module.yml file provides a snippet_root setting.

For example, in a zephyr module named baz, you can add this to your module.yml file:

```yaml
settings:
  snippet_root: .
```

And then any snippet.yml files in baz/snippets will automatically be discovered by the build system, just as if the path to baz had appeared in SNIPPET_ROOT.

**Processing order**

Snippets are processed in the order they are listed in the SNIPPET variable, or in the order of the -S arguments if using west.

To apply bar after foo:

```
cmake -S app -B build -DSNIPPET="foo;bar" [...] 
cmake --build build
```

The same can be achieved with west as follows:

```
west build -S foo -S bar [...] app
```

When multiple snippets set the same configuration, the configuration value set by the last processed snippet ends up in the final configurations.

For instance, if foo sets CONFIG_FOO=1 and bar sets CONFIG_FOO=2 in the above example, the resulting final configuration will be CONFIG_FOO=2 because bar is processed after foo.

This principle applies to both Kconfig fragments (.conf files) and devicetree overlays (.overlay files).

**Devicetree overlays (.overlay)**

This snippet.yml adds foo.overlay to the build:

```yaml
name: foo
append:
  EXTRA_DTC_OVERLAY_FILE: foo.overlay
```

The path to foo.overlay is relative to the directory containing snippet.yml.

**.conf files**

This snippet.yml adds foo.conf to the build:
name: foo
append:
  EXTRA_CONF_FILE: foo.conf

The path to foo.conf is relative to the directory containing snippet.yml.

DTS_EXTRA_CPPFLAGS

This snippet.yml adds DTS_EXTRA_CPPFLAGS CMake Cache variables to the build:

name: foo
append:
  DTS_EXTRA_CPPFLAGS: -DMY_DTS_CONFIGURE

Adding these flags enables control over the content of a devicetree file.

Board-specific settings

You can write settings that only apply to some boards.

The settings described here are applied in **addition** to snippet settings that apply to all boards. (This is similar, for example, to the way that an application with both prj.conf and boards/foo.conf files will use both .conf files in the build when building for board foo, instead of just boards/foo.conf)

By name

```
name: ...
boards:
  bar: # settings for board "bar" go here
  append:
    EXTRA_DTC_OVERLAY_FILE: bar.overlay
  baz: # settings for board "baz" go here
  append:
    EXTRA_DTC_OVERLAY_FILE: baz.overlay
```

The above example uses bar.overlay when building for board bar, and baz.overlay when building for baz.

By regular expression You can enclose the board name in slashes (/) to match the name against a regular expression in the CMake syntax. The regular expression must match the entire board name.

For example:

```
name: foo
boards:
  /my_vendor_.*/:
    append:
      EXTRA_DTC_OVERLAY_FILE: my_vendor.overlay
```

The above example uses devicetree overlay my_vendor.overlay when building for either board my_vendor_board1 or my_vendor_board2. It would not use the overlay when building for either another_vendor_board or x_my_vendor_board.
5.4.4 Snippets Design

This page documents design goals for the snippets feature. Further information can be found in Issue #51834.

- **extensible**: for example, it is possible to add board support for an existing built-in snippet without modifying the zephyr repository
- **composable**: it is possible to use multiple snippets at once, for example using:

  ```
  west build -S <snippet1> -S <snippet2> ...
  ```

- **able to combine multiple types of configuration**: snippets make it possible to store multiple different types of build system settings in one place, and apply them all together
- **specializable**: for example, it is possible to customize a snippet's behavior for a particular board, or board revision
- **future-proof and backwards-compatible**: arbitrary future changes to the snippets feature will be possible without breaking backwards compatibility for older snippets
- **applicable to purely “software” changes**: unlike the shields feature, snippets do not assume the presence of a “daughterboard”, “shield”, “hat”, or any other type of external assembly which is connected to the main board
- **DRY (don’t repeat yourself)**: snippets allow you to skip unnecessary repetition; for example, you can apply the same board-specific configuration to boards `foo` and `bar` by specifying `/(<foo>|<bar>)/` as a regular expression for the settings, which will then apply to both boards

5.5 Zephyr CMake Package

The Zephyr CMake package is a convenient way to create a Zephyr-based application.

**Note**: The Application types section introduces the application types used in this page.

The Zephyr CMake package ensures that CMake can automatically select a Zephyr installation to use for building the application, whether it is a Zephyr repository application, a Zephyr workspace application, or a Zephyr freestanding application.

When developing a Zephyr-based application, then a developer simply needs to write `find_package(Zephyr)` in the beginning of the application `CMakeLists.txt` file.

To use the Zephyr CMake package it must first be exported to the CMake user package registry. This is means creating a reference to the current Zephyr installation inside the CMake user package registry.

**Ubuntu**

In Linux, the CMake user package registry is found in:

`~/.cmake/packages/Zephyr`

**macOS**

In macOS, the CMake user package registry is found in:

`~/.cmake/packages/Zephyr`

**Windows**

In Windows, the CMake user package registry is found in:

HKEY_CURRENT_USER\Software\Kitware\CMake\Packages\Zephyr
The Zephyr CMake package allows CMake to automatically find a Zephyr base. One or more Zephyr installations must be exported. Exporting multiple Zephyr installations may be useful when developing or testing Zephyr freestanding applications, Zephyr workspace application with vendor forks, etc..

### 5.5.1 Zephyr CMake package export (west)

When installing Zephyr using *west* then it is recommended to export Zephyr using *west zephyr-export*.

### 5.5.2 Zephyr CMake package export (without west)

Zephyr CMake package is exported to the CMake user package registry using the following commands:

```
cmake -P <PATH-TO-ZEPHYR>/share/zephyr-package/cmake/zephyr_export.cmake
```

This will export the current Zephyr to the CMake user package registry.

To also export the Zephyr Unittest CMake package, run the following command in addition:

```
cmake -P <PATH-TO-ZEPHYR>/share/zephyrunittest-package/cmake/zephyr_export.cmake
```

### 5.5.3 Zephyr Base Environment Setting

The Zephyr CMake package search functionality allows for explicitly specifying a Zephyr base using an environment variable.

To do this, use the following `find_package()` syntax:

```
find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})
```

This syntax instructs CMake to first search for Zephyr using the Zephyr base environment setting `ZEPHYR_BASE` and then use the normal search paths.

### 5.5.4 Zephyr CMake Package Search Order

When Zephyr base environment setting is not used for searching, the Zephyr installation matching the following criteria will be used:

- A Zephyr repository application will use the Zephyr in which it is located. For example:
  ```
  <projects>/zephyr-workspace/zephyr
  ├── samples
  │   └── hello_world
  ```
  In this example, `hello_world` will use `<projects>/zephyr-workspace/zephyr`.

- Zephyr workspace application will use the Zephyr that share the same workspace. For example:
  ```
  <projects>/zephyr-workspace
  ├── zephyr
  │   └── ...
  │       └── my_applications
  │               └── my_first_app
  ```
in this example, my_first_app will use <projects>/zephyr-workspace/zephyr as this Zephyr is located in the same workspace as the Zephyr workspace application.

**Note:** The root of a Zephyr workspace is identical to `west topdir` if the workspace was installed using `west`.

- Zephyr freestanding application will use the Zephyr registered in the CMake user package registry. For example:

```plaintext
<projects>/zephyr-workspace-1
   └── zephyr
      (Not exported to CMake)

<projects>/zephyr-workspace-2
   └── zephyr
      (Exported to CMake)

<home>/app
   └── CMakeLists.txt
      └── prj.conf
         └── src
            └── main.c
```

in this example, only <projects>/zephyr-workspace-2/zephyr is exported to the CMake package registry and therefore this Zephyr will be used by the Zephyr freestanding application <home>/app.

If user wants to test the application with <projects>/zephyr-workspace-1/zephyr, this can be done by using the Zephyr Base environment setting, meaning set `ZEPHYR_BASE=<projects>/zephyr-workspace-1/zephyr`, before running CMake.

**Note:** The Zephyr package selected on the first CMake invocation will be used for all subsequent builds. To change the Zephyr package, for example to test the application using Zephyr base environment setting, then it is necessary to do a pristine build first (See Re-building an Application).

### 5.5.5 Zephyr CMake Package Version

When writing an application then it is possible to specify a Zephyr version number `x.y.z` that must be used in order to build the application.

Specifying a version is especially useful for a Zephyr freestanding application as it ensures the application is built with a minimal Zephyr version.

It also helps CMake to select the correct Zephyr to use for building, when there are multiple Zephyr installations in the system.

For example:

```bash
find_package(Zephyr 2.2.0)
project(app)
```

will require app to be built with Zephyr 2.2.0 as minimum. CMake will search all exported candidates to find a Zephyr installation which matches this version criteria.

Thus it is possible to have multiple Zephyr installations and have CMake automatically select between them based on the version number provided, see CMake package version for details.

For example:
in this case, there are two released versions of Zephyr installed at their own workspaces. Workspace 2.a and 2.b, corresponding to the Zephyr version.

To ensure app is built with minimum version 2.a the following find_package syntax may be used:

```cmake
find_package(Zephyr 2.a)
project(app)
```

Note that both 2.a and 2.b fulfill this requirement.

CMake also supports the keyword EXACT, to ensure an exact version is used, if that is required. In this case, the application CMakeLists.txt could be written as:

```cmake
find_package(Zephyr 2.a EXACT)
project(app)
```

In case no Zephyr is found which satisfies the version required, as example, the application specifies

```cmake
find_package(Zephyr 2.z)
project(app)
```

then an error similar to below will be printed:

```
Could not find a configuration file for package "Zephyr" that is compatible with requested version "2.z".
The following configuration files were considered but not accepted:
  /zephyr-workspace-2.a/zephyr/share/zephyr-package/cmake/ZephyrConfig.cmake,
  version: 2.a.0
  /zephyr-workspace-2.b/zephyr/share/zephyr-package/cmake/ZephyrConfig.cmake,
  version: 2.b.0
```

Note: It can also be beneficial to specify a version number for Zephyr repository applications and Zephyr workspace applications. Specifying a version in those cases ensures the application will only build if the Zephyr repository or workspace is matching. This can be useful to avoid accidental builds when only part of a workspace has been updated.

### 5.5.6 Multiple Zephyr Installations (Zephyr workspace)

Testing out a new Zephyr version, while at the same time keeping the existing Zephyr in the workspace untouched is sometimes beneficial.

Or having both an upstream Zephyr, Vendor specific, and a custom Zephyr in same workspace. For example:
in this setup, find_package(Zephyr) has the following order of precedence for selecting which
Zephyr to use:

• Project name: zephyr
• First project, when Zephyr projects are ordered lexicographical, in this case.
  – zephyr-custom
  – zephyr-vendor

This means that my_first_app will use <projects>/zephyr-workspace/zephyr.

It is possible to specify a Zephyr preference list in the application.

A Zephyr preference list can be specified as:

```cmake
set(ZEPHYR_PREFER "zephyr-custom" "zephyr-vendor")
find_package(Zephyr)
project(my_first_app)
```

the ZEPHYR_PREFER is a list, allowing for multiple Zephyrs. If a Zephyr is specified in the list, but
not found in the system, it is simply ignored and find_package(Zephyr) will continue to the next
candidate.

This allows for temporary creation of a new Zephyr release to be tested, without touching current
Zephyr. When testing is done, the zephyr-test folder can simply be removed. Such a CMake-
Lists.txt could look as:

```cmake
set(ZEPHYR_PREFER "zephyr-test")
find_package(Zephyr)
project(my_first_app)
```

### 5.5.7 Zephyr Build Configuration CMake packages

There are two Zephyr Build configuration packages which provide control over the build settings
in Zephyr in a more generic way. These packages are:

• **ZephyrBuildConfiguration**: Applies to all Zephyr applications in the workspace
• **ZephyrAppConfiguration**: Applies only to the application you are currently building

They are similar to the per-user .zephyrrc file that can be used to set Environment Variables, but
they set CMake variables instead. They also allow you to automatically share the build configuration
among all users through the project repository. They also allow more advanced use cases,
such as loading of additional CMake boilerplate code.

The Zephyr Build Configuration CMake packages will be loaded in the Zephyr boilerplate code
after initial properties and ZEPHYR_BASE has been defined, but before CMake code execution.
The ZephyrBuildConfiguration is included first and ZephyrAppConfiguration afterwards. That
means the application-specific package could override the workspace settings, if needed. This
allows the Zephyr Build Configuration CMake packages to setup or extend properties such as:
DTS_ROOT, BOARD_ROOT, TOOLCHAIN_ROOT / other toolchain setup, fixed overlays, and any other
property that can be controlled. It also allows inclusion of additional boilerplate code.
To provide a ZephyrBuildConfiguration or ZephyrAppConfiguration, create ZephyrBuildConfig.
cmake and/or ZephyrAppConfig.cmake respectively and place them in the appropriate location. The CMake find_package mechanism will search for these files with the steps below. Other default CMake package search paths and hints are disabled and there is no version checking implemented for these packages. This also means that these packages cannot be installed in the CMake package registry. The search steps are:

1. If ZephyrBuildConfiguration_ROOT, or ZephyrAppConfiguration_ROOT respectively, is set, search within this prefix path. If a matching file is found, execute this file. If no matching file is found, go to step 2.

2. Search within ${ZEPHYR_BASE}/../*, or ${APPLICATION_SOURCE_DIR} respectively. If a matching file is found, execute this file. If no matching file is found, abort the search.

It is recommended to place the files in the default paths from step 2, but with the <PackageName>_ROOT variables you have the flexibility to place them anywhere. This is especially necessary for freestanding applications, for which the default path to ZephyrBuildConfiguration usually does not work. In this case the <PackageName>_ROOT variables can be set on the CMake command line, before find_package(Zephyr ...), as environment variable or from a CMake cache initialization file with the -C command line option.

Note: The <PackageName>_ROOT variables, as well as the default paths, are just the prefixes to the search path. These prefixes get combined with additional path suffixes, which together form the actual search path. Any combination that honors the CMake package search procedure is valid and will work.

If you want to completely disable the search for these packages, you can use the special CMake CMAKE_DISABLE_FIND_PACKAGE_<PackageName> variable for that. Just set CMAKE_DISABLE_FIND_PACKAGE_ZephyrBuildConfiguration or CMAKE_DISABLE_FIND_PACKAGE_ZephyrAppConfiguration to TRUE to disable the package.

An example folder structure could look like this:

```
<projects>/zephyr-workspace
|-- zephyr
   |-- ...
   |   |-- manifest repo (can be named anything)
   |       |-- cmake/ZephyrBuildConfig.cmake
   |   |-- ...
   |   |-- zephyr application
   |       |-- share/zephyrapp-package/cmake/ZephyrAppConfig.cmake
```

A sample ZephyrBuildConfig.cmake can be seen below.

```
# ZephyrBuildConfig.cmake sample code

# To ensure final path is absolute and does not contain ../../../ in variable.
get_filename_component(APPLICATION_PROJECT_DIR
                      ${CMAKE_CURRENT_LIST_DIR}/../../../ABSOLUTE)

# Add this project to list of board roots
list(APPEND BOARD_ROOT ${APPLICATION_PROJECT_DIR})

# Default to GNU Arm Embedded toolchain if no toolchain is set
if(NOT ENV{ZEPHYR_TOOLCHAIN_VARIANT})
    set(ZEPHYR_TOOLCHAIN_VARIANT gnuarmemb)
    find_program(GNU_ARM_GCC arm-none-eabi-gcc)
    if(NOT ${GNU_ARM_GCC} STREQUAL GNU_ARM_GCC-NOTFOUND)
        # The toolchain root is located above the path to the compiler.
```

(continues on next page)
5.5.8 Zephyr CMake package source code

The Zephyr CMake package source code in `share/zephyr-package/cmake` and `share/zephyrunittest-package/cmake` contains the CMake config package which is used by the CMake `find_package` function.

It also contains code for exporting Zephyr as a CMake config package.

The following is an overview of the files in these directories:

- **ZephyrConfigVersion.cmake**: The Zephyr package version file. This file is called by CMake to determine if this installation fulfills the requirements specified by user when calling `find_package(Zephyr ...)`. It is also responsible for detection of Zephyr repository or workspace only installations.

- **ZephyrUnittestConfigVersion.cmake**: Same responsibility as `ZephyrConfigVersion.cmake`, but for unit tests. Includes `ZephyrConfigVersion.cmake`.

- **ZephyrConfig.cmake**: The Zephyr package file. This file is called by CMake to for the package meeting which fulfills the requirements specified by user when calling `find_package(Zephyr ...)`. This file is responsible for sourcing of boilerplate code.

- **ZephyrUnittestConfig.cmake**: Same responsibility as `ZephyrConfig.cmake`, but for unit tests. Includes `ZephyrConfig.cmake`.

- **zephyr_package_search.cmake**: Common file used for detection of Zephyr repository and workspace candidates. Used by `ZephyrConfigVersion.cmake` and `ZephyrConfig.cmake` for common code.

- **zephyr_export.cmake**: See [Zephyr CMake package export (without west)](#).

5.6 Sysbuild (System build)

Sysbuild is a higher-level build system that can be used to combine multiple other build systems together. It is a higher-level layer that combines one or more Zephyr build systems and optional additional build systems into a hierarchical build system.

For example, you can use sysbuild to build a Zephyr application together with the MCUboot bootloader, flash them both onto your device, and debug the results.

Sysbuild works by configuring and building at least a Zephyr application and, optionally, as many additional projects as you want. The additional projects can be either Zephyr applications or other types of builds you want to run.

Like Zephyr’s `build system`, sysbuild is written in CMake and uses `Kconfig`.

5.6.1 Definitions

The following are some key concepts used in this document:
Single-image build
When sysbuild is used to create and manage just one Zephyr application's build system.

Multi-image build
When sysbuild is used to manage multiple build systems. The word “image” is used because your main goal is usually to generate the binaries of the firmware application images from each build system.

Domain
Every Zephyr CMake build system managed by sysbuild.

Multi-domain
When more than one Zephyr CMake build system (domain) is managed by sysbuild.

5.6.2 Architectural Overview

This figure is an overview of sysbuild’s inputs, outputs, and user interfaces:

The following are some key sysbuild features indicated in this figure:

- You can run sysbuild either with `west build` or directly via `cmake`.
- You can use sysbuild to generate application images from each build system, shown above as ELF, BIN, and HEX files.
- You can configure sysbuild or any of the build systems it manages using various configuration variables. These variables are namespaced so that sysbuild can direct them to the right build system. In some cases, such as the `BOARD` variable, these are shared among multiple build systems.
- Sysbuild itself is also configured using Kconfig. For example, you can instruct sysbuild to build the MCUboot bootloader, as well as to build and link your main Zephyr application as an MCUboot-bootable image, using sysbuild’s Kconfig files.
• Sysbuild integrates with west's Building, Flashing and Debugging commands. It does this by managing the Flash and debug runners, and specifically the runners.yaml files that each Zephyr build system will contain. These are packaged into a global view of how to flash and debug each build system in a domains.yaml file generated and managed by sysbuild.

• Build names are prefixed with the target name and an underscore, for example the sysbuild target is prefixed with sysbuild_ and if MCUboot is enabled as part of sysbuild, it will be prefixed with mcuboot_. This also allows for running things like menuconfig with the prefix, for example (if using ninja) ninja sysbuild_menuconfig to configure sysbuild or (if using make) make mcuboot_menuconfig.

5.6.3 Building with sysbuild

As mentioned above, you can run sysbuild via west build or cmake.

west build

Here is an example. For details, see Sysbuild (multi-domain builds) in the west build documentation.

```
west build -b reel_board --sysbuild samples/hello_world
```

**Tip:** To configure west build to use --sysbuild by default from now on, run:

```
west config build.sysbuild True
```

Since sysbuild supports both single- and multi-image builds, this lets you use sysbuild all the time, without worrying about what type of build you are running.

To turn this off, run this before generating your build system:

```
west config build.sysbuild False
```

To turn this off for just one west build command, run:

```
west build --no-sysbuild ...
```

cmake

Here is an example using CMake and Ninja.

```
cmake -Bbuild -GNinja -DBOARD=reel_board -DAPP_DIR=samples/hello_world share/sysbuild
ninja -Cbuild
```

To use sysbuild directly with CMake, you must specify the sysbuild project as the source folder, and give -DAPP_DIR=<path-to-sample> as an extra CMake argument. APP_DIR is the path to the main Zephyr application managed by sysbuild.

5.6.4 Configuration namespaces

When building a single Zephyr application without sysbuild, all CMake cache settings and Kconfig build options given on the command line as -D<var>=<value> or -DCONFIG_<var>=<value> are handled by the Zephyr build system.

However, when sysbuild combines multiple Zephyr build systems, there could be Kconfig settings exclusive to sysbuild (and not used by any of the applications). To handle this, sysbuild has namespaces for configuration variables. You can use these namespaces to direct settings either
The following example shows how to build hello_world with MCUboot enabled, applying to both images debug optimizations:

```
west build
```

```
west build -b reel_board --sysbuild samples/hello_world --DSB_CONFIG_BOOTLOADER_MCUBOOT=y --DCONFIG_DEBUG_OPTIMIZATIONS=y -Dmcuboot_DEBUG_OPTIMIZATIONS=y
```

```
cmake
```

```
cmake -GNinja -DBOARD=reel_board -DAPP_DIR=samples/hello_world -DSB_CONFIG_BOOTLOADER_MCUBOOT=y -DCONFIG_DEBUG_OPTIMIZATIONS=y -Dmcuboot_DEBUG_OPTIMIZATIONS=y share/
```

```
ninja -Cbuild
```

See the following subsections for more information.

### CMake variable namespaces

CMake variable settings can be passed to CMake using `-D<var>=<value>` on the command line. You can also set Kconfig options via CMake as `-D<var>=<value>` or `-D<namespace>_CONFIG_<var>=<value>`.

Since sysbuild is the entry point for the build system, and sysbuild is written in CMake, all CMake variables are first processed by sysbuild.

Sysbuild creates a namespace for each domain. The namespace prefix is the domain's application name. See *Adding Zephyr applications to sysbuild* for more information.

To set the variable `<var>` in the namespace `<namespace>`, use this syntax:

```
-D<namespace>_<var>=<value>
```

For example, to set the CMake variable `FOO` in the `my_sample` application build system to the value `BAR`, run the following commands:

```
wester build
```

```
wester build --sysbuild ... -- Dmy_sample_FOO=BAR
```

```
cmake
```

```
cmake -Dmy_sample_FOO=BAR ...
```

### Kconfig namespaces

To set the sysbuild Kconfig option `<var>` to the value `<value>`, use this syntax:

```
-DSB_CONFIG_<var>=<value>
```

In the previous example, `SB_CONFIG` is the namespace prefix for sysbuild's Kconfig options.

To set a Zephyr application's Kconfig option instead, use this syntax:

```
-D<namespace>_CONFIG_<var>=<value>
```
In the previous example, `<namespace>` is the application name discussed above in *CMake variable naming*.

For example, to set the Kconfig option `FOO` in the `my_sample` application build system to the value `BAR`, run the following commands:

```
w west build
west build --sysbuild ... --Dmy_sample_CONFIG_FOO=BAR
```

```
cmake
```

```
cmake -Dmy_sample_CONFIG_FOO=BAR ...
```

**Tip:** When no `<namespace>` is used, the Kconfig setting is passed to the main Zephyr application `my_sample`.

This means that passing `-DCONFIG_<var>=<value>` and `-Dmy_sample_CONFIG_<var>=<value>` are equivalent.

This allows you to build the same application with or without sysbuild using the same syntax for setting Kconfig values at CMake time. For example, the following commands will work in the same way:

```
w west build -b <board> my_sample --DCONFIG_FOO=BAR
west build -b <board> --sysbuild my_sample --DCONFIG_FOO=BAR
```

### 5.6.5 Sysbuild flashing using `west flash`

You can use `west flash` to flash applications with sysbuild.

When invoking `west flash` on a build consisting of multiple images, each image is flashed in sequence. Extra arguments such as `--runner jlink` are passed to each invocation.

For more details, see *Multi-domain flashing*.

### 5.6.6 Sysbuild debugging using `west debug`

You can use `west debug` to debug the main application, whether you are using sysbuild or not. Just follow the existing `west debug` guide to debug the main sample.

To debug a different domain (Zephyr application), such as `mcuboot`, use the `--domain` argument, as follows:

```
w west debug --domain mcuboot
```

For more details, see *Multi-domain debugging*.

### 5.6.7 Building a sample with MCUboot

Sysbuild supports MCUboot natively.

To build a sample like `hello_world` with MCUboot, enable MCUboot and build and flash the sample as follows:

```
w west build
```
west build -b reel_board --sysbuild samples/hello_world --DSB_CONFIG_BOOTLOADER_MCUBOOT=y

cmake

cmake -Bbuild -GNinja -DBOARD=reel_board -DAPP_DIR=samples/hello_world -DSB_CONFIG_BOOTLOADER_MCUBOOT=y share/sysbuild
	ninja -Cbuild

This builds hello_world and mcuboot for the reel_board, and then flashes both the mcuboot and hello_world application images to the board.

More detailed information regarding the use of MCUboot with Zephyr can be found in the [MCUboot with Zephyr](https://mcuboot.org) documentation page on the MCUboot website.

**Note:** The deprecated MCUBoot Kconfig option `CONFIG_ZEPHYR_TRY_MASS_ERASE` will perform a full chip erase when flashed. If this option is enabled, then flashing only MCUBoot, for example using `west flash --domain mcuboot`, may erase the entire flash, including the main application image.

### 5.6.8 Sysbuild Kconfig file

You can set sysbuild's Kconfig options for a single application using configuration files. By default, sysbuild looks for a configuration file named `sysbuild.conf` in the application top-level directory.

In the following example, there is a `sysbuild.conf` file that enables building and flashing with MCUboot whenever sysbuild is used:

```
<home>/application
├── CMakeLists.txt
├── prj.conf
└── sysbuild.conf
```

```
SB_CONFIG_BOOTLOADER_MCUBOOT=y
```

You can set a configuration file to use with the `-DSB_CONF_FILE=<sysbuild-conf-file>` CMake build setting.

For example, you can create `sysbuild-mcuboot.conf` and then specify this file when building with sysbuild, as follows:

```
west build
```

```
west build -b reel_board --sysbuild samples/hello_world --DSB_CONF_FILE=sysbuild-mcuboot.conf
```

cmake

cmake -Bbuild -GNinja -DBOARD=reel_board -DAPP_DIR=samples/hello_world -DSB_CONF_FILE=sysbuild-mcuboot.conf share/sysbuild
	ninja -Cbuild
```

### 5.6.9 Sysbuild targets

Sysbuild creates build targets for each image (including sysbuild itself) for the following modes:

- menuconfig
• hardenconfig
• guiconfig

For the main application (as is the same without using sysbuild) these can be ran normally without any prefix. For other images (including sysbuild), these are ran with a prefix of the image name and an underscore e.g. sysbuild_ or mcuboot_, using ninja or make - for details on how to run image build targets that do not have mapped build targets in sysbuild, see the Dedicated image build targets section.

5.6.10 Dedicated image build targets

Not all build targets for images are given equivalent prefixed build targets when sysbuild is used, for example build targets like ram_report, rom_report, footprint, puncover and pahole are not exposed. When using Trusted Firmware, this includes build targets prefix with tfm_ and bl2_, for example: tfm_rom_report and bl2_ram_report. To run these build targets, the build directory of the image can be provided to west/ninja/make along with the name of the build target to execute and it will run.

west
Assuming that a project has been configured and built using west using sysbuild with mcuboot enabled in the default build folder location, the rom_report build target for mcuboot can be ran with:

west build -d build/mcuboot -t rom_report

ninja
Assuming that a project has been configured using cmake and built using ninja using sysbuild with mcuboot enabled, the rom_report build target for mcuboot can be ran with:

ninja -C mcuboot rom_report

make
Assuming that a project has been configured using cmake and built using make using sysbuild with mcuboot enabled, the rom_report build target for mcuboot can be ran with:

make -C mcuboot rom_report

5.6.11 Adding Zephyr applications to sysbuild

You can use the ExternalZephyrProject_Add() function to add Zephyr applications as sysbuild domains. Call this CMake function from your application's sysbuild.cmake file, or any other CMake file you know will run as part sysbuild CMake invocation.

Targeting the same board

To include my_sample as another sysbuild domain, targeting the same board as the main image, use this example:

```cmake
ExternalZephyrProject_Add(
    APPLICATION my_sample
    SOURCE_DIR <path-to>/my_sample
)
```

This could be useful, for example, if your board requires you to build and flash an SoC-specific bootloader along with your main application.
Targeting a different board

In sysbuild and Zephyr CMake build system a board may refer to:

- A physical board with a single core SoC.
- A specific core on a physical board with a multi-core SoC, such as nrf5340dk_nrf5340.
- A specific SoC on a physical board with multiple SoCs, such as nrf9160dk_nrf9160 and nrf9160dk_nrf52840.

If your main application, for example, is built for mps2_an521, and your helper application must target the mps2_an521_remote board (cpu1), add a CMake function call that is structured as follows:

```
ExternalZephyrProject_Add(
  APPLICATION my_sample
  SOURCE_DIR <path-to>/my_sample
  BOARD mps2_an521_remote
)
```

This could be useful, for example, if your main application requires another helper Zephyr application to be built and flashed alongside it, but the helper runs on another core in your SoC.

Targeting conditionally using Kconfig

You can control whether extra applications are included as sysbuild domains using Kconfig.

If the extra application image is specific to the board or an application, you can create two additional files: sysbuild.cmake and Kconfig.sysbuild.

For an application, this would look like this:

```
<home>/application
├── CMakeLists.txt
├── prj.conf
├── Kconfig.sysbuild
└── sysbuild.cmake
```

In the previous example, sysbuild.cmake would be structured as follows:

```
if(SB_CONFIG_SECOND_SAMPLE)
  ExternalZephyrProject_Add(
    APPLICATION second_sample
    SOURCE_DIR <path-to>/second_sample
  )
endif()
```

Kconfig.sysbuild would be structured as follows:

```
source "sysbuild/Kconfig"
config SECOND_SAMPLE
  bool "Second sample"
  default y
```

This will include second_sample by default, while still allowing you to disable it using the Kconfig option SECOND_SAMPLE.

For more information on setting sysbuild Kconfig options, see Kconfig namespace.
Building without flashing

You can mark `my_sample` as a build-only application in this manner:

```cmake
ExternalZephyrProject_Add(
    APPLICATION my_sample
    SOURCE_DIR <path-to>/my_sample
    BUILD_ONLY TRUE
)
```

As a result, `my_sample` will be built as part of the sysbuild build invocation, but it will be excluded from the default image sequence used by `west flash`. Instead, you may use the outputs of this domain for other purposes - for example, to produce a secondary image for DFU, or to merge multiple images together.

You can also replace `TRUE` with another boolean constant in CMake, such as a Kconfig option, which would make `my_sample` conditionally build-only.

**Note:** Applications marked as build-only can still be flashed manually, using `west flash --domain my_sample`. As such, the `BUILD_ONLY` option only controls the default behavior of `west flash`.

Zephyr application configuration

When adding a Zephyr application to sysbuild, such as MCUboot, then the configuration files from the application (MCUboot) itself will be used.

When integrating multiple applications with each other, then it is often necessary to make adjustments to the configuration of extra images.

Sysbuild gives users the ability of creating Kconfig fragments or devicetree overlays that will be used together with the application's default configuration. Sysbuild also allows users to change Application Configuration Directory in order to give users full control of an image's configuration.

**Zephyr application Kconfig fragment and devicetree overlay**  In the folder of the main application, create a Kconfig fragment or a devicetree overlay under a sysbuild folder, where the name of the file is `<image>.conf` or `<image>.overlay`, for example if your main application includes `my_sample` then create a `sysbuild/my_sample.conf` file or a devicetree overlay `sysbuild/my_sample.overlay`.

A Kconfig fragment could look as:

```cmake
# sysbuild/my_sample.conf
CONFIG_FOO=n
```

**Zephyr application configuration directory**  In the folder of the main application, create a new folder under `sysbuild/<image>/`. This folder will then be used as `APPLICATION_CONFIG_DIR` when building `<image>`. As an example, if your main application includes `my_sample` then create a `sysbuild/my_sample/` folder and place any configuration files in there as you would normally do:

```
<home>/application
├── CMakeLists.txt
├── prj.conf
└── sysbuild
    ├── my_sample
```

(continues on next page)
All configuration files under the sysbuild/my_sample/ folder will now be used when my_sample is included in the build, and the default configuration files for my_sample will be ignored. This gives you full control on how images are configured when integrating those with applications.

**Sysbuild file suffix support**  File suffix support through the makevar:FILE_SUFFIX is supported in sysbuild (see File Suffixes for details on this feature in applications). For sysbuild, a globally provided option will be passed down to all images. In addition, the image configuration file will have this value applied and used (instead of the build type) if the file exists.

Given the example project:

```plaintext
<home>/application
├── CMakeLists.txt
│   ├── prj.conf
│   │   └── app.overlay
│   └── boards
│       ├── <board_A>.conf
│       │   └── <board_A>.overlay
│       ├── <board_B>.conf
│       │   └── <board_B>.overlay
```

- If FILE_SUFFIX is not defined and both mcuboot and my_sample images are included, mcuboot will use the mcuboot.conf Kconfig fragment file and my_sample will use the my_sample.conf Kconfig fragment file. Sysbuild itself will use the sysbuild.conf Kconfig fragment file.
- If FILE_SUFFIX is set to max_log and both mcuboot and my_sample images are included, mcuboot will use the mcuboot_max_log.conf Kconfig fragment file and my_sample will use the my_sample.conf Kconfig fragment file (as it will fallback to the file without the suffix). Sysbuild itself will use the sysbuild.conf Kconfig fragment file (as it will fallback to the file without the suffix).
- If FILE_SUFFIX is set to test_key and both mcuboot and my_sample images are included, mcuboot will use the mcuboot.conf Kconfig fragment file and my_sample will use the my_sample.conf Kconfig fragment file (as it will fallback to the files without the suffix). Sysbuild itself will use the sysbuild_test_key.conf Kconfig fragment file. This can be used to apply a different sysbuild configuration, for example to use a different signing key in MCUboot and when signing the main application.

The FILE_SUFFIX can also be applied only to single images by prefixing the variable with the image name:

```shell
west build
west build -b reel_board --sysbuild file_suffix_example --DSB_CONFIG_BOOTLOADER_MCUBOOT=y
    --Dmcuboot_FILE_SUFFIX="max_log"
```

```shell
cmake
```
```shell
cmake -Bbuild -GNinja -DBOARD=reel_board -DAPP_DIR=<app_dir> -DSB_CONFIG_BOOTLOADER_MCUBOOT=y
                -Dmcuboot_FILE_SUFFIX="max_log" share/sysbuild
ninja -Cbuild
```
Adding dependencies among Zephyr applications

Sometimes, in a multi-image build, you may want certain Zephyr applications to be configured or flashed in a specific order. For example, if you need some information from one application's build system to be available to another's, then the first thing to do is to add a configuration dependency between them. Separately, you can also add flashing dependencies to control the sequence of images used by west flash; this could be used if a specific flashing order is required by an SoC, a _runner_, or something else.

By default, sysbuild will configure and flash applications in the order that they are added, as ExternalZephyrProject_Add() calls are processed by CMake. You can use the sysbuild_add_dependencies() function to make adjustments to this order, according to your needs. Its usage is similar to the standard add_dependencies() function in CMake.

Here is an example of adding configuration dependencies for my_sample:

```cmake
sysbuild_add_dependencies(IMAGES CONFIGURE my_sample sample_a sample_b)
```

This will ensure that sysbuild will run CMake for sample_a and sample_b (in some order) before doing the same for my_sample, when building these domains in a single invocation.

If you want to add flashing dependencies instead, then do it like this:

```cmake
sysbuild_add_dependencies(IMAGES FLASH my_sample sample_a sample_b)
```

As a result, my_sample will be flashed after sample_a and sample_b (in some order), when flashing these domains in a single invocation.

**Note:** Adding flashing dependencies is not allowed for build-only applications. If my_sample had been created with BUILD_ONLY TRUE, then the above call to sysbuild_add_dependencies() would have produced an error.

---

### 5.6.12 Adding non-Zephyr applications to sysbuild

You can include non-Zephyr applications in a multi-image build using the standard CMake module ExternalProject. Please refer to the CMake documentation for usage details.

When using ExternalProject, the non-Zephyr application will be built as part of the sysbuild build invocation, but west flash or west debug will not be aware of the application. Instead, you must manually flash and debug the application.

---

### 5.6.13 Extending sysbuild

Sysbuild can be extended by other modules to give it additional functionality or include other configuration or images, an example could be to add support for another bootloader or external signing method.

Modules can be extended by adding custom CMake or Kconfig files as normal modules do, this will cause the files to be included in each image that is part of a project. Alternatively, there are sysbuild-specific module extension files which can be used to include CMake and Kconfig files for the overall sysbuild image itself, this is where e.g. a custom image for a particular board or SoC can be added.
5.7 Application version management

Zephyr supports an application version management system for applications which is built around the system that Zephyr uses for its own version system management. This allows applications to define a version file and have application (or module) code include the auto-generated file and be able to access it, just as they can with the kernel version. This version information is available from multiple scopes, including:

- Code (C/C++)
- Kconfig
- CMake

which makes it a very versatile system for lifecycle management of applications. In addition, it can be used when building applications which target supported bootloaders (e.g. MCUboot) allowing images to be signed with correct version of the application automatically - no manual signing steps are required.

5.7.1 VERSION file

Application version information is set on a per-application basis in a file named VERSION, which must be placed at the base directory of the application, where the CMakeLists.txt file is located. This is a simple text file which contains the various version information fields, each on a newline. The basic VERSION file has the following structure:

```
VERSION_MAJOR =
VERSION_MINOR =
PATCHLEVEL =
VERSION_TWEAK =
EXTRAVERSION =
```

Each field and the values it supports is described below (note that there may be further restrictions depending upon what the version is used for, e.g. bootloaders might only support some of these fields or might place limits on the maximum values of fields):

<table>
<thead>
<tr>
<th>Field</th>
<th>Data type</th>
</tr>
</thead>
<tbody>
<tr>
<td>VERSION_MAJOR</td>
<td>Numerical</td>
</tr>
<tr>
<td>VERSION_MINOR</td>
<td>Numerical</td>
</tr>
<tr>
<td>PATCHLEVEL</td>
<td>Numerical</td>
</tr>
<tr>
<td>VERSION_TWEAK</td>
<td>Numerical</td>
</tr>
<tr>
<td>EXTRAVERSION</td>
<td>Alphanumerical (Lowercase a-z and 0-9)</td>
</tr>
</tbody>
</table>

When an application is configured using CMake, the version file will be automatically processed, and will be checked automatically each time the version is changed, so CMake does not need to be manually re-ran for changes to this file.

For the sections below, examples are provided for the following VERSION file:

```
VERSION_MAJOR = 1
VERSION_MINOR = 2
PATCHLEVEL = 3
VERSION_TWEAK = 4
EXTRAVERSION = unstable
```
5.7.2 Use in code

To use the version information in application code, the version file must be included, then the fields can be freely used. The include file name is app_version.h (no path is needed), the following defines are available:

<table>
<thead>
<tr>
<th>Define</th>
<th>Type</th>
<th>Field(s)</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>APPVERSION</td>
<td>Numerical</td>
<td>VERSION_MAJOR (left shifted by 24 bits),</td>
<td>0x1020304</td>
</tr>
<tr>
<td></td>
<td></td>
<td>VERSION_MINOR (left shifted by 16 bits),</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>PATCHLEVEL (left shifted by 8 bits),</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>VERSION_TWEAK</td>
<td></td>
</tr>
<tr>
<td>APP_VERSION_7</td>
<td>Numerical</td>
<td>VERSION_MAJOR (left shifted by 16 bits),</td>
<td>0x10203</td>
</tr>
<tr>
<td></td>
<td></td>
<td>VERSION_MINOR (left shifted by 8 bits),</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>PATCHLEVEL</td>
<td></td>
</tr>
<tr>
<td>APP_VERSION_?</td>
<td>Numerical</td>
<td>VERSION_MAJOR</td>
<td>1</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>APP_VERSION_?</td>
<td>Numerical</td>
<td>VERSION_MINOR</td>
<td>2</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>APP_PATCHLEVEL</td>
<td>Numerical</td>
<td>PATCHLEVEL</td>
<td>3</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>APP_VERSION_?</td>
<td>Numerical</td>
<td>VERSION_MINOR</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>APP_VERSION_?</td>
<td>Numerical</td>
<td>VERSION_MINOR</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>APP_BUILD_VERSION</td>
<td>String (unquoted)</td>
<td>None (value of git describe --abbrev=12 --always from application repository)</td>
<td>v3.3.0-18-g2c85d9224fca</td>
</tr>
</tbody>
</table>

5.7.3 Use in Kconfig

The following variables are available for usage in Kconfig files:
### Variable Types and Examples

<table>
<thead>
<tr>
<th>Variable</th>
<th>Type</th>
<th>Field(s)</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>$(VERSION_MAJOR)</td>
<td>Numerical</td>
<td>VERSION_MAJOR</td>
<td>1</td>
</tr>
<tr>
<td>$(VERSION_MINOR)</td>
<td>Numerical</td>
<td>VERSION_MINOR</td>
<td>2</td>
</tr>
<tr>
<td>$(PATCHLEVEL)</td>
<td>Numerical</td>
<td>PATCHLEVEL</td>
<td>3</td>
</tr>
<tr>
<td>$(VERSION_TWEAK)</td>
<td>Numerical</td>
<td>VERSION_TWEAK</td>
<td>4</td>
</tr>
<tr>
<td>$(APPVERSION)</td>
<td>String</td>
<td>VERSION_MAJOR, VERSION_MINOR, PATCHLEVEL, EXTRAVERSION</td>
<td>1.2.3-unstable</td>
</tr>
<tr>
<td>$(APP_VERSION_EXTENDED_STRING)</td>
<td>String</td>
<td>VERSION_MAJOR, VERSION_MINOR, PATCHLEVEL, EXTRAVERSION, VERSION_TWEAK</td>
<td>1.2.3-unstable+4</td>
</tr>
<tr>
<td>$(APP_VERSION_TWEAK_STRING)</td>
<td>String</td>
<td>VERSION_MAJOR, VERSION_MINOR, PATCHLEVEL, VERSION_TWEAK</td>
<td>1.2.3+4</td>
</tr>
</tbody>
</table>

### 5.7.4 Use in CMake

The following variable are available for usage in CMake files:

<table>
<thead>
<tr>
<th>Variable</th>
<th>Type</th>
<th>Field(s)</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>APPVERSION</td>
<td>Numerical (hex)</td>
<td>VERSION_MAJOR (left shifted by 24 bits), VERSION_MINOR (left shifted by 16 bits), PATCHLEVEL (left shifted by 8 bits), VERSION_TWEAK</td>
<td>0x1020304</td>
</tr>
<tr>
<td>APP_VERSION_NUMBER</td>
<td>Numerical (hex)</td>
<td>VERSION_MAJOR (left shifted by 16 bits), VERSION_MINOR (left shifted by 8 bits), PATCHLEVEL</td>
<td>0x10203</td>
</tr>
<tr>
<td>APP_VERSION_MAJOR</td>
<td>Numerical</td>
<td>VERSION_MAJOR</td>
<td>1</td>
</tr>
<tr>
<td>APP_VERSION_MINOR</td>
<td>Numerical</td>
<td>VERSION_MINOR</td>
<td>2</td>
</tr>
<tr>
<td>APP_PATCHLEVEL</td>
<td>Numerical</td>
<td>PATCHLEVEL</td>
<td>3</td>
</tr>
<tr>
<td>APP_VERSION_TWEAK</td>
<td>Numerical</td>
<td>VERSION_TWEAK</td>
<td>4</td>
</tr>
<tr>
<td>APP_VERSION_STRING</td>
<td>Numerical (hex)</td>
<td>VERSION_MAJOR, VERSION_MINOR, PATCHLEVEL, EXTRAVERSION</td>
<td>1.2.3-unstable</td>
</tr>
<tr>
<td>APP_VERSION_EXTENDED_STRING</td>
<td>String</td>
<td>VERSION_MAJOR, VERSION_MINOR, PATCHLEVEL, EXTRAVERSION, VERSION_TWEAK</td>
<td>1.2.3-unstable+4</td>
</tr>
<tr>
<td>APP_VERSION_TWEAK_STRING</td>
<td>String</td>
<td>VERSION_MAJOR, VERSION_MINOR, PATCHLEVEL, VERSION_TWEAK</td>
<td>1.2.3+4</td>
</tr>
</tbody>
</table>
5.7.5 Use in MCUboot-supported applications

No additional configuration needs to be done to the target application so long as it is configured to support MCUboot and a signed image is generated, the version information will be automatically included in the image data.
Chapter 6

Connectivity

6.1 Bluetooth

This section contains information regarding the Bluetooth stack of the Zephyr OS. You can use this information to understand the principles behind the operation of the layers and how they were implemented.

Zephyr includes a complete Bluetooth Low Energy stack from application to radio hardware, as well as portions of a Classical Bluetooth (BR/EDR) Host layer.

6.1.1 Overview

- **Supported Features**

Since its inception, Zephyr has had a strong focus on Bluetooth and, in particular, on Bluetooth Low Energy (BLE). Through the contributions of several companies and individuals involved in existing open source implementations of the Bluetooth specification (Linux's BlueZ) as well as the design and development of BLE radio hardware, the protocol stack in Zephyr has grown to be mature and feature-rich, as can be seen in the section below.

Supported Features

Zephyr comes integrated with a feature-rich and highly configurable Bluetooth stack.

- Bluetooth v5.3 compliant
  - Highly configurable
    - Features, buffer sizes/counts, stack sizes, etc.
  - Portable to all architectures supported by Zephyr (including big and little endian, alignment flavors and more)
  - Support for all combinations of Host and Controller builds:
    - Controller-only (HCI) over UART, SPI, USB and IPC physical transports
    - Host-only over UART, SPI, and IPC (shared memory)
    - Combined (Host + Controller)
- Bluetooth-SIG qualified
– Controller on Nordic Semiconductor hardware
– Conformance tests run regularly on all layers

**Bluetooth Low Energy Controller support (LE Link Layer)**
– Unlimited role and connection count, all roles supported
– All v5.3 specification features supported (except a few minor items)
– Concurrent multi-protocol support ready
– Intelligent scheduling of roles to minimize overlap
– Portable design to any open BLE radio, currently supports Nordic Semiconductor nRF51 and nRF52, as well as proprietary radios
– Supports little and big endian architectures, and abstracts the hard real-time specifics so that they can be encapsulated in a hardware-specific module
– Support for Controller (HCI) builds over different physical transports

**Bluetooth Host support**
– Generic Access Profile (GAP) with all possible LE roles
  – Peripheral & Central
  – Observer & Broadcaster
  – Multiple PHY support (2Mbit/s, Coded)
  – Extended Advertising
  – Periodic Advertising (including Sync Transfer)
– GATT (Generic Attribute Profile)
  – Server (to be a sensor)
  – Client (to connect to sensors)
  – Enhanced ATT (EATT)
  – GATT Database Hash
  – GATT Multiple Notifications
– Pairing support, including the Secure Connections feature from Bluetooth 4.2
– Non-volatile storage support for permanent storage of Bluetooth-specific settings and data
– Bluetooth Mesh support
  – Relay, Friend Node, Low-Power Node (LPN) and GATT Proxy features
  – Both Provisioning roles and bearers supported (PB-ADV & PB-GATT)
  – Foundation Models included
  – Highly configurable, fits as small as 16k RAM devices
– IPS/6LoWPAN for IPv6 connectivity over Bluetooth LE
  – IPS node sample application
– Basic Bluetooth BR/EDR (Classic) support
  – Generic Access Profile (GAP)
  – Logical Link Control and Adaptation Protocol (L2CAP)
  – Serial Port emulation (RFCOMM protocol)
  – Service Discovery Protocol (SDP)
Clean HCI driver abstraction
- 3-Wire (H:5) & 5-Wire (H:4) UART
- SPI
- Local controller support as a virtual HCI driver
- Verified with multiple popular controllers

• LE Audio in Host and Controller
  - Isochronous channels
    * Full Host support
    * Initial Controller support
  - Generic Audio Framework
    * Basic Audio Profile
      - Unicast server and client
      - Broadcast source and sink
      - Broadcast assistant
      - Scan delegator
    * Common Audio Profile
      - Acceptor
    * Volume Control Profile, Microphone Control Profile
    * Call Control Profile, Media Control Profile
    * Coordinated Set Identification Profile

6.1.2 Bluetooth Stack Architecture

Overview

This page describes the software architecture of Zephyr’s Bluetooth protocol stack.

**Note:** Zephyr supports mainly Bluetooth Low Energy (BLE), the low-power version of the Bluetooth specification. Zephyr also has limited support for portions of the BR/EDR Host. Throughout this architecture document we use BLE interchangeably for Bluetooth except when noted.

**BLE Layers**
There are 3 main layers that together constitute a full Bluetooth Low Energy protocol stack:

- **Host:** This layer sits right below the application, and is comprised of multiple (non real-time) network and transport protocols enabling applications to communicate with peer devices in a standard and interoperable way.

- **Controller:** The Controller implements the Link Layer (LE LL), the low-level, real-time protocol which provides, in conjunction with the Radio Hardware, standard-interoperable over-the-air communication. The LL schedules packet reception and transmission, guarantees the delivery of data, and handles all the LL control procedures.

- **Radio Hardware:** Hardware implements the required analog and digital baseband functional blocks that permit the Link Layer firmware to send and receive in the 2.4GHz band of the spectrum.
Host Controller Interface  The Bluetooth Specification describes the format in which a Host must communicate with a Controller. This is called the Host Controller Interface (HCI) protocol. HCI can be implemented over a range of different physical transports like UART, SPI, or USB. This protocol defines the commands that a Host can send to a Controller and the events that it can expect in return, and also the format for user and protocol data that needs to go over the air. The HCI ensures that different Host and Controller implementations can communicate in a standard way making it possible to combine Hosts and Controllers from different vendors.

Configurations  The three separate layers of the protocol and the standardized interface make it possible to implement the Host and Controller on different platforms. The two following configurations are commonly used:

• Single-chip configuration: In this configuration, a single microcontroller implements all three layers and the application itself. This can also be called a system-on-chip (SoC) implementation. In this case the BLE Host and the BLE Controller communicate directly through function calls and queues in RAM. The Bluetooth specification does not specify how HCI is implemented in this single-chip configuration and so how HCI commands, events, and data flows between the two can be implementation-specific. This configuration is well suited for those applications and designs that require a small footprint and the lowest possible power consumption, since everything runs on a single IC.

• Dual-chip configuration: This configuration uses two separate ICs, one running the Application and the Host, and a second one with the Controller and the Radio Hardware. This is sometimes also called a connectivity-chip configuration. This configuration allows for a wider variety of combinations of Hosts when using the Zephyr OS as a Controller. Since HCI ensures interoperability among Host and Controller implementations, including of course Zephyr's very own BLE Host and Controller, users of the Zephyr Controller can choose to use whatever Host running on any platform they prefer. For example, the host can be the Linux BLE Host stack (BlueZ) running on any processor capable of supporting Linux. The Host processor may of course also run Zephyr and the Zephyr OS BLE Host. Conversely, combining an IC running the Zephyr Host with an external Controller that does not run Zephyr is also supported.

Build Types  The Zephyr software stack as an RTOS is highly configurable, and in particular, the BLE subsystem can be configured in multiple ways during the build process to include only the features and layers that are required to reduce RAM and ROM footprint as well as power consumption. Here's a short list of the different BLE-enabled builds that can be produced from the Zephyr project codebase:

• Controller-only build: When built as a BLE Controller, Zephyr includes the Link Layer and a special application. This application is different depending on the physical transport chosen for HCI:
  – hci_uart
  – hci_usb
  – hci_spi
This application acts as a bridge between the UART, SPI or USB peripherals and the Controller subsystem, listening for HCI commands, sending application data and responding with events and received data. A build of this type sets the following Kconfig option values:
  – CONFIG_BT=y
  – CONFIG_BT_HCI=y
  – CONFIG_BT_HCI_RAW=y
  – CONFIG_BT_CTLR=y
  – CONFIG_BT_LL_SW_SPLIT=y (if using the open source Link Layer)
• **Host-only build:** A Zephyr OS Host build will contain the Application and the BLE Host, along with an HCI driver (UART or SPI) to interface with an external Controller chip. A build of this type sets the following Kconfig option values:
  
  - `CONFIG_BT = y`
  - `CONFIG_BT_HCI = y`
  - `CONFIG_BT_CTLR = n`

  All of the samples located in `samples/bluetooth` except for the ones used for Controller-only builds can be built as Host-only.

• **Combined build:** This includes the Application, the Host and the Controller, and it is used exclusively for single-chip (SoC) configurations. A build of this type sets the following Kconfig option values:
  
  - `CONFIG_BT = y`
  - `CONFIG_BT_HCI = y`
  - `CONFIG_BT_CTLR = y`
  - `CONFIG_BT_LL_SW_SPLIT = y` (if using the open source Link Layer)

  All of the samples located in `samples/bluetooth` except for the ones used for Controller-only builds can be built as Combined.

The picture below shows the SoC or single-chip configuration when using a Zephyr combined build (a build that includes both a BLE Host and a Controller in the same firmware image that is programmed onto the chip):

When using connectivity or dual-chip configurations, several Host and Controller combinations are possible, some of which are depicted below:

When using a Zephyr Host (left side of image), two instances of Zephyr OS must be built with different configurations, yielding two separate images that must be programmed into each of the chips respectively. The Host build image contains the application, the BLE Host and the selected HCI driver (UART or SPI), while the Controller build runs either the `hci_uart`, or the `hci_spi` app to provide an interface to the BLE Controller.

This configuration is not limited to using a Zephyr OS Host, as the right side of the image shows. One can indeed take one of the many existing GNU/Linux distributions, most of which include Linux's own BLE Host (BlueZ), to connect it via UART or USB to one or more instances of the Zephyr OS Controller build. BlueZ as a Host supports multiple Controllers simultaneously for applications that require more than one BLE radio operating at the same time but sharing the same Host stack.

**Source tree layout**

The stack is split up as follows in the source tree:

**subsys/bluetooth/host**

  The host stack. This is where the HCI command and event handling as well as connection tracking happens. The implementation of the core protocols such as L2CAP, ATT, and SMP is also here.

**subsys/bluetooth/controller**

  Bluetooth Controller implementation. Implements the controller-side of HCI, the Link Layer as well as access to the radio transceiver.

**include/bluetooth/**

  Public API header files. These are the header files applications need to include in order to use Bluetooth functionality.
Fig. 1: A Combined build on a Single-Chip configuration
drivers/bluetooth/
HCI transport drivers. Every HCI transport needs its own driver. For example, the two common types of UART transport protocols (3-Wire and 5-Wire) have their own drivers.
samples/bluetooth/
Sample Bluetooth code. This is a good reference to get started with Bluetooth application development.
tests/bluetooth/
Test applications. These applications are used to verify the functionality of the Bluetooth stack, but are not necessary the best source for sample code (see samples/bluetooth instead).
doc/guides/bluetooth/
Extra documentation, such as PICS documents.

Host

The Bluetooth Host implements all the higher-level protocols and profiles, and most importantly, provides a high-level API for applications. The following diagram depicts the main protocol & profile layers of the host.

Lowest down in the host stack sits a so-called HCI driver, which is responsible for abstracting away the details of the HCI transport. It provides a basic API for delivering data from the controller to the host, and vice-versa.

Perhaps the most important block above the HCI handling is the Generic Access Profile (GAP). GAP simplifies Bluetooth LE access by defining four distinct roles of BLE usage:

- Connection-oriented roles
Peripheral role  Most Zephyr-based BLE devices will most likely be peripheral-role devices. This means that they perform connectable advertising and expose one or more GATT services. After registering services using the `bt_gatt_service_register()` API the application will typically start connectable advertising using the `bt_le_adv_start()` API.

There are several peripheral sample applications available in the tree, such as `samples/bluetooth/peripheral_hr`.

Central role  Central role may not be as common for Zephyr-based devices as peripheral role, but it is still a plausible one and equally well supported in Zephyr. Rather than accepting connections from other devices a central role device will scan for available peripheral device and choose one to connect to. Once connected, a central will typically act as a GATT client, first performing discovery of available services and then accessing one or more supported services.

To initially discover a device to connect to the application will likely use the `bt_le_scan_start()` API, wait for an appropriate device to be found (using the scan callback), stop scanning using `bt_le_scan_stop()` and then connect to the device using `bt_conn_le_create()`. If the central wants to keep automatically reconnecting to the peripheral it should use the `bt_le_set_auto_conn()` API.

There are some sample applications for the central role available in the tree, such as `samples/bluetooth/central_hr`. 
Observer role An observer role device will use the `bt_le_scan_start()` API to scan for device, but it will not connect to any of them. Instead it will simply utilize the advertising data of found devices, combining it optionally with the received signal strength (RSSI).

Broadcaster role A broadcaster role device will use the `bt_le_adv_start()` API to advertise specific advertising data, but the type of advertising will be non-connectable, i.e. other device will not be able to connect to it.

Connections Connection handling and the related APIs can be found in the `Connection Management` section.

Security To achieve a secure relationship between two Bluetooth devices a process called pairing is used. This process can either be triggered implicitly through the security properties of GATT services, or explicitly using the `bt_conn_security()` API on a connection object.

To achieve a higher security level, and protect against Man-In-The-Middle (MITM) attacks, it is recommended to use some out-of-band channel during the pairing. If the devices have a sufficient user interface this “channel” is the user itself. The capabilities of the device are registered using the `bt_conn_auth_cb_register()` API. The `bt_conn_auth_cb` struct that's passed to this API has a set of optional callbacks that can be used during the pairing - if the device lacks some feature the corresponding callback may be set to NULL. For example, if the device does not have an input method but does have a display, the `passkey_entry` and `passkey_confirm` callbacks would be set to NULL, but the `passkey_display` would be set to a callback capable of displaying a passkey to the user.

Depending on the local and remote security requirements & capabilities, there are four possible security levels that can be reached:

- **BT_SECURITY_L1**
  - No encryption and no authentication.

- **BT_SECURITY_L2**
  - Encryption but no authentication (no MITM protection).

- **BT_SECURITY_L3**
  - Encryption and authentication using the legacy pairing method from Bluetooth 4.0 and 4.1.

- **BT_SECURITY_L4**
  - Encryption and authentication using the LE Secure Connections feature available since Bluetooth 4.2.

Note: Mesh has its own security solution through a process called provisioning. It follows a similar procedure as pairing, but is done using separate mesh-specific APIs.

L2CAP L2CAP stands for the Logical Link Control and Adaptation Protocol. It is a common layer for all communication over Bluetooth connections, however an application comes in direct contact with it only when using it in the so-called Connection-oriented Channels (CoC) mode. More information on this can be found in the `L2CAP API section`.

GATT The Generic Attribute Profile is the most common means of communication over LE connections. A more detailed description of this layer and the API reference can be found in the `GATT API reference section`.
Mesh  Mesh is a little bit special when it comes to the needed GAP roles. By default, mesh requires both observer and broadcaster role to be enabled. If the optional GATT Proxy feature is desired, then peripheral role should also be enabled.

The API reference for mesh can be found in the Mesh API reference section.

LE Audio  The LE audio is a set of profiles and services that utilizes GATT and Isochronous Channel to provide audio over Bluetooth Low Energy. The architecture and API references can be found in Bluetooth Audio Architecture.

Persistent storage  The Bluetooth host stack uses the settings subsystem to implement persistent storage to flash. This requires the presence of a flash driver and a designated “storage” partition on flash. A typical set of configuration options needed will look something like the following:

```bash
CONFIG_BT_SETTINGS=y
CONFIG_FLASH=y
CONFIG_FLASH_PAGE_LAYOUT=y
CONFIG_FLASH_MAP=y
CONFIG_NVS=y
CONFIG_SETTINGS=y
```

Once enabled, it is the responsibility of the application to call settings_load() after having initialized Bluetooth (using the bt_enable() API).

6.1.3 Bluetooth Low Energy Controller
Overview

1. HCI
   - Host Controller Interface, Bluetooth standard
   - Provides Zephyr Bluetooth HCI Driver

2. HAL
   - Hardware Abstraction Layer
   - Vendor Specific, and Zephyr Driver usage

3. Ticker
   - Soft real time radio/resource scheduling

4. LL_SW
   - Software-based Link Layer implementation
   - States and roles, control procedures, packet controller

5. Util
   - Bare metal memory pool management
   - Queues of variable count, lockless usage
   - FIFO of fixed count, lockless usage
   - Mayfly concept based deferred ISR executions

6.1. Bluetooth
Architecture

Execution Overview

Architecture Overview
Scheduling

Ticker

6.1. Bluetooth
Upper Link Layer and Lower Link Layer

Slot reservation protects full event (event execution fully resolved by ULL schedule)

Slot reservation partly protects event (occasional part of event execution is resolved by LLL)

Several slot reservations protects event (occasional part of event execution is fully resolved by ULL schedule)

Scheduling Variants

ULL and LLL Timing
6.1. Bluetooth

The ULL is unaware of the offset time domain and delayed execution in LLL:
1) The ULL can only queue prepare/abort commands.
2) The LLL returns event done for executed commands.
3) The ULL cannot peek into the LLL activity.

ULL Scheduling

LLL Event Handling
Scheduling Closely Spaced Events

Aborting Active Event
Cancelling Pending Event

Pre-emption of Active Event
Data Flow

Transmit Data Flow
6.1. Bluetooth

Receive Data Flow
Execution Priorities

• Event handle (0, 1) < Event preparation (2, 3) < Event/Rx done (4) < Tx request (5) < Role management (6) < Host (7).

• LLL is vendor ISR, ULL is Mayfly ISR concept, Host is kernel thread.

Lower Link Layer
LLL Resume

- Preempted event is resumed after the last event in the event queue (in this case after the current).
- New event reservation overlap with resumed event reservation = resumed event is moved to be after the new event.

Bare metal utilities

- Memory FIFO and Memory Queue

Mayfly
- Mayfly are multi-instance scalable ISR execution contexts
What a Work is to a Thread, Mayfly is to an ISR
List of functions executing in ISRs
Execution priorities map to IRQ priorities
Facilitate cross execution context scheduling
Race-to-idle execution
Lock-less, bare metal

Legacy Controller

Bluetooth Low Energy Controller - Vendor Specific Details

Hardware Requirements

Nordic Semiconductor  The Nordic Semiconductor Bluetooth Low Energy Controller implementation requires the following hardware peripherals.
## Table 1: SoC Peripheral Use

<table>
<thead>
<tr>
<th>Resource</th>
<th>nRF Peripheral</th>
<th># instances</th>
<th>Zephyr Driver Accessible</th>
<th>Description</th>
</tr>
</thead>
</table>
| Clock    | NRF_CLOCK     | 1           | Yes                      | • A Low Frequency Clock (LFCLOCK) or sleep clock, for low power consumption between Bluetooth radio events  
• A High Frequency Clock (HFCLOCK) or active clock, for high precision packet timing and software based transceiver state switching with inter-frame space (tIFS) timing inside Bluetooth radio events |
| RTC [a]  | NRF_RTC0      | 1           | No                       | • Uses 2 capture/compare registers |
| Timer    | NRF_TIMER1 or NRF_TIMER3 and NRF_TIMER4 or NRF_TIMER1 or NRF_TIMER4 | 2 or 1 | No | 2 instances, one each for packet timing and tIFS software switching, respectively  
7 capture/compare registers (3 mandatory, 1 optional for ISR profiling, 4 for single timer tIFS switching) on first instance  
4 capture/compare registers for second instance, if single tIFS timer is not used. |
| PPI [b]  | NRF_PPI       | 21 channels (20\(^2\), and 2 channel groups\(^3\)) | Yes\(^4\) | • Used for radio mode switching to achieve tIFS timings, for PA/LNA control |
| DPPI [c] | NRF_DPPI      | 20 channels, and 2 channel groups\(^3\) | Yes\(^1\) | • Used for radio mode switching to achieve tIFS timings, for PA/LNA control |
| SWI [d]  | NRF_SWI4 and NRF_SWI5, or NRF_SWI2 and NRF_SWI3 | 2 | No | 2 instances, for Lower Link Layer and Upper Link Layer Low priority execution context |
| Radio    | NRF_RADIO     | 1           | No                       | • 2.4 GHz radio transceiver with multiple radio standards such as 1 Mbps, 2 Mbps and Coded PHY S2/S8 Long Range Bluetooth Low Energy technology |
| RNG [e]  | NRF_RNG       | 1           | Yes                      | |
| ECB [f]  | NRF_ECB       | 1           | No                       | |
| CBC-CCM [g] | NRF_CCM     | 1           | No                       | |
| AAR [h]  | NRF_AAR       | 1           | No                       | |
| GPIO [i] | NRF_GPIO      | 2 GPIO pins for PA and LNA, 1 each | Yes | • Additionally, 10 Debug GPIO pins (optional) |
| GPIOTE [j] | NRF_GPIOTE    | 1           | Yes                      | |
| TEMP [k] | NRF_TEMP      | 1           | Yes                      | • For RC sourced LFCLOCK calibration |
| UART [l] | NRF_UART0     | 1           | Yes                      | • For HCI interface in Controller only builds |
| IPC [m]  | NRF_IPC       | 1           | Yes                      | • For HCI interface in Controller only builds |

---

\(^{1}\) Page 1534  
\(^{2}\) Page 1533  
\(^{3}\) Page 1534  
\(^{4}\) Page 1534  
\(^{5}\) Page 1534
6.1.4 Bluetooth Audio Architecture

![Bluetooth Audio Architecture Diagram]

**Generic Audio Framework (GAF)**

The Generic Audio Framework (GAF) is considered the middleware of the Bluetooth LE Audio architecture. The GAF contains the profiles and services that allow higher layer applications and profiles to set up streams, change volume, control media and telephony and more. The GAF builds on GATT, GAP and isochronous channels (ISO).

GAF uses GAP to connect, advertise and synchronize to other devices. GAF uses GATT to configure streams, associate streams with content (e.g. media or telephony), control volume and more. GAF uses ISO for the audio streams themselves, both as unicast (connected) audio streams or broadcast (unconnected) audio streams.

GAF mandates the use of the LC3 codec, but also supports other codecs.

The top-level profiles TMAP and HAP are not part of the GAF, but rather provide top-level requirements for how to use the GAF.

GAF has been implemented in Zephyr with the following structure.

**Bluetooth Audio Stack Status**  The following table shows the current status and support of the profiles in the Bluetooth Audio Stack.

---

1 CONFIG_BT_CTLR_SW_SWITCH_SINGLE_TIMER = y
2 CONFIG_BT_CTLR_TIFS_HW = n
3 When not using pre-defined PPI channels
4 For software-based tIFS switching
5 For nRF53x Series

---

Chapter 6. Connectivity
6.1. Bluetooth

Fig. 5: Generic Audio Framework

Fig. 6: Zephyr Generic Audio Framework
Table 2: Bluetooth Audio Profile status

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<tr>
<td>Broadcast Game Receiver</td>
<td>Re-</td>
<td>3.5</td>
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<td>• Feature complete</td>
<td>• Sample Application</td>
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<td></td>
<td></td>
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<td>• BSIM test</td>
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</tr>
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</table>

**Using the Bluetooth Audio Stack** To use any of the profiles in the Bluetooth Audio Stack, including the top-level profiles outside of GAF, `CONFIG_BT_AUDIO` shall be enabled. This Kconfig option allows the enabling of the individual profiles inside of the Bluetooth Audio Stack. Each profile can generally be enabled on its own, but enabling higher-layer profiles (such as CAP, TMAP and HAP) will typically require enabling some of the lower layer profiles.

It is, however, possible to create a device that uses e.g. only Stream Control (with just the BAP), without using any of the content control or rendering/capture control profiles, or vice versa. Using the higher layer profiles will however typically provide a better user experience and better interoperability with other devices.

**Common Audio Profile (CAP)** The Common Audio Profile introduces restrictions and requirements on the lower layer profiles. The procedures in CAP works on one or more streams for one or more devices. Is it thus possible via CAP to do a single function call to setup multiple streams across multiple devices.

The figure below shows a complete structure of the procedures in CAP and how they correspond to procedures from the other profiles. The circles with I, A and C show whether the procedure has active involvement or requirements from the CAP Initiator, CAP Accept and CAP Commander roles respectively.

The API reference for CAP can be found in *Common Audio Profile*.

**Stream Control (BAP)** Stream control is implemented by the Basic Audio Profile. This profile defines multiple roles:

- Unicast Client
- Unicast Server
- Broadcast Source
- Broadcast Sink
- Scan Delegator (not yet implemented)
- Broadcast assistant (not yet implemented)
Each role can be enabled individually, and it is possible to support more than one role.
The API reference for stream control can be found in *Bluetooth Audio*.

**Rendering and Capture Control**  Rendering and capture control is implemented by the Volume Control Profile (VCP) and Microphone Control Profile (MICP).
The VCP implementation supports the following roles
- Volume Control Service (VCS) Server
- Volume Control Service (VCS) Client
The MICP implementation supports the following roles
- Microphone Control Profile (MICP) Microphone Device (server)
- Microphone Control Profile (MICP) Microphone Controller (client)
The API reference for volume control can be found in *Bluetooth Volume Control*.
The API reference for Microphone Control can be found in *Bluetooth Microphone Control*.

**Content Control**  Content control is implemented by the Call Control Profile (CCP) and Media Control Profile (MCP).
The CCP implementation is not yet implemented in Zephyr.
The MCP implementation supports the following roles
- Media Control Service (MCS) Server via the Media Proxy module
- Media Control Client (MCC)
The API reference for media control can be found in *Bluetooth Media Control*.

**Coordinated Sets**  Coordinated Sets is implemented by the Coordinated Sets Identification Profile (CSIP).
The CSIP implementation supports the following roles
- Coordinated Set Identification Service (CSIP) Set Member
- Coordinated Set Identification Service (CSIP) Set Coordinator
The API reference for media control can be found in *Bluetooth Coordinated Sets*.

### 6.1.5 Bluetooth Qualification

**Qualification Listings**
The Zephyr BLE stack has obtained qualification listings for both the Host and the Controller. See the tables below for a list of qualification listings

<table>
<thead>
<tr>
<th>Zephyr version</th>
<th>Link</th>
<th>Qualifying Company</th>
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<tbody>
<tr>
<td>2.2.x</td>
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<tr>
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<td>QDID 139258</td>
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<td>1.13</td>
<td>QDID 119517</td>
<td>Nordic Semiconductor</td>
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</table>
Mesh qualifications

<table>
<thead>
<tr>
<th>Zephyr version</th>
<th>Link</th>
<th>Qualifying Company</th>
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<tbody>
<tr>
<td>1.14.x</td>
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<td>The Linux Foundation</td>
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Controller qualifications

<table>
<thead>
<tr>
<th>Zephyr version</th>
<th>Link</th>
<th>Qualifying Company</th>
<th>Compatible Hardware</th>
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<tbody>
<tr>
<td>2.2.x</td>
<td>QDID 150092</td>
<td>Nordic Semiconductor</td>
<td>nRF52x</td>
</tr>
<tr>
<td>1.14.x</td>
<td>QDID 135679</td>
<td>Nordic Semiconductor</td>
<td>nRF52x</td>
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<td>1.9 to 1.13</td>
<td>QDID 101395</td>
<td>Nordic Semiconductor</td>
<td>nRF52x</td>
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</table>

ICS Features

The ICS features for each supported protocol & profile can be found in the following documents:

**GAP ICS**  PTS version: 8.0.3
M - mandatory
O - optional

### Device Configuration

<table>
<thead>
<tr>
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<th>Selected</th>
<th>Description</th>
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</thead>
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<tr>
<td>TSPC_GAP_0_1</td>
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<td>BR/EDR (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_0_2</td>
<td>True</td>
<td>LE (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_0_3</td>
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<td>BR/EDR/LE (C.3)</td>
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### Modes

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<td>Non-discoverable mode (C.1)</td>
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<td>TSPC_GAP_1_2</td>
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<td>Limited-discoverable mode (O)</td>
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<td>TSPC_GAP_1_3</td>
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<td>General-discoverable mode (O)</td>
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<tr>
<td>TSPC_GAP_1_4</td>
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<td>Non-connectable mode (O)</td>
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<tr>
<td>TSPC_GAP_1_5</td>
<td>False</td>
<td>Connectable mode (M)</td>
</tr>
<tr>
<td>TSPC_GAP_1_6</td>
<td>False</td>
<td>Non-bondable mode (O)</td>
</tr>
<tr>
<td>TSPC_GAP_1_7</td>
<td>False</td>
<td>Bondable mode (C.2)</td>
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<tr>
<td>TSPC_GAP_1_8</td>
<td>False</td>
<td>Non-Synchronizable Mode (C.3)</td>
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<tr>
<td>TSPC_GAP_1_9</td>
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<td>Synchronizable Mode (C.4)</td>
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## Security Aspects

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<td>Authentication procedure (C.1)</td>
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<td>TSPC_GAP_2_2</td>
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<td>Support of LMP-Authentication (M)</td>
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<tr>
<td>TSPC_GAP_2_3</td>
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<td>Initiate LMP-Authentication (C.5)</td>
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<tr>
<td>TSPC_GAP_2_4</td>
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<td>Security mode 1 (C.2)</td>
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<tr>
<td>TSPC_GAP_2_5</td>
<td>False</td>
<td>Security mode 2 (O)</td>
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<td>TSPC_GAP_2_6</td>
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<td>Security mode 3 (C.7)</td>
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<tr>
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<tr>
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<td>Security Optional (C.6)</td>
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<td>TSPC_GAP_2_12</td>
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<td>TSPC_GAP_2_13</td>
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<td>128-bit encryption key size capable (C.11)</td>
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## Idle Mode Procedures

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<tr>
<td>TSPC_GAP_3_3</td>
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<td>Initiation of name discovery (O)</td>
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<tr>
<td>TSPC_GAP_3_4</td>
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<td>Initiation of device discovery (O)</td>
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<tr>
<td>TSPC_GAP_3_5</td>
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<td>Initiation of general bonding (O)</td>
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## Establishment Procedures

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<td>TSPC_GAP_4_1</td>
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<td>Support link establishment as initiator (M)</td>
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<tr>
<td>TSPC_GAP_4_2</td>
<td>False</td>
<td>Support link establishment as acceptor (M)</td>
</tr>
<tr>
<td>TSPC_GAP_4_3</td>
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<td>Support channel establishment as initiator (O)</td>
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<tr>
<td>TSPC_GAP_4_4</td>
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<td>Support channel establishment as acceptor (M)</td>
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<td>TSPC_GAP_4_7</td>
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## LE Roles

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### Broadcaster Physical Layer

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### Broadcaster Link Layer States

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### Broadcaster Link Layer Advertising Event Types

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<th>Selected</th>
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</thead>
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<tr>
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<td>Non-Connectable Undirected Event (M)</td>
</tr>
<tr>
<td>TSPC_GAP_8_2</td>
<td>True</td>
<td>Scannable Undirected Event (O)</td>
</tr>
<tr>
<td>TSPC_GAP_8_3</td>
<td>True</td>
<td>Non-Connectable and Non-Scannable Directed Event (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_8_4</td>
<td>True</td>
<td>Scannable Directed Event (C.1)</td>
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### Broadcaster Link Layer Advertising Data Types

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<td>TSPC_GAP_8a_3</td>
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<td>AD Type – Flags (O)</td>
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<td>TSPC_GAP_8a_4</td>
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<td>AD Type – Manufacturer Specific Data (O)</td>
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### Broadcaster Connection Modes and Procedures

<table>
<thead>
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<th>Parameter Name</th>
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<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>TSPC_GAP_9_1</td>
<td>True</td>
<td>Non-Connectable Mode (M)</td>
</tr>
</tbody>
</table>

### Broadcaster Broadcasting and Observing Features
## Zephyr Project Documentation, Release 3.6.0-rc3

### Parameter Name  | Selected | Description                                           
--- | --- | ---                                                   
TSPC_GAP_10_1 | True | Broadcast Mode (M)                                    
TSPC_GAP_10_2 | False | Broadcast Isochronous Synchronizability mode (C.1)     
TSPC_GAP_10_3 | False | Broadcast Isochronous Broadcasting mode (C.2)         
TSPC_GAP_10_4 | False | Broadcast Isochronous Terminate procedure (C.1)       
TSPC_GAP_10_5 | False | Broadcast Isochronous Channel Map Update Procedure (C.1)  

### Broadcaster Privacy Feature

| Parameter Name  | Selected | Description                                           
--- | --- | ---                                                   
TSPC_GAP_11_1 | True | Privacy Feature (O)                                    
TSPC_GAP_11_2 | True | Resolvable Private Address Generation Procedure (C.1)  
TSPC_GAP_11_3 | True | Non-Resolvable Private Address Generation Procedure (C.2)  

### Periodic Advertising Modes and Procedures

| Parameter Name  | Selected | Description                                           
--- | --- | ---                                                   
TSPC_GAP_11a_1 | False | Periodic Advertising Synchronizability mode (C.1)      
TSPC_GAP_11a_2 | False | Periodic Advertising mode (C.2)                       

### Broadcaster Security Aspects Features

| Parameter Name  | Selected | Description                                           
--- | --- | ---                                                   
TSPC_GAP_11b_1 | False | LE Security Mode 3 (C.1)                              
TSPC_GAP_11b_2 | False | LE Security Mode 3, Level 1 (C.2)                    
TSPC_GAP_11b_3 | False | LE Security Mode 3, Level 2 (C.2)                    
TSPC_GAP_11b_4 | False | LE Security Mode 3, Level 3 (C.2)                    

### Observer Physical Layer

| Parameter Name  | Selected | Description                                           
--- | --- | ---                                                   
TSPC_GAP_12_1 | True | Receiver (M)                                         
TSPC_GAP_12_2 | True | Transmitter (O)                                      

### Observer Link Layer States

| Parameter Name  | Selected | Description                                           
--- | --- | ---                                                   
TSPC_GAP_13_1 | True | Standby (M)                                           
TSPC_GAP_13_2 | True | Scanning (M)                                          

### Observer Link Layer Scanning Types

| Parameter Name  | Selected | Description                                           
--- | --- | ---                                                   
TSPC_GAP_14_1 | True | Passive Scanning (M)                                  
TSPC_GAP_14_2 | True | Active Scanning (O)                                   

### 6.1. Bluetooth

### Observer Connection Modes and Procedures

<table>
<thead>
<tr>
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<tr>
<td>TSPC_GAP_15_1</td>
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<td>Non-Connectable Modes (M)</td>
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### Observer Broadcasting and Observing Features

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<tr>
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<tr>
<td>TSPC_GAP_16_1</td>
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<td>Observation Procedure (M)</td>
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<tr>
<td>TSPC_GAP_16_2</td>
<td>False</td>
<td>Broadcast Isochronous Synchronization Establishment procedure (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_16_3</td>
<td>False</td>
<td>Broadcast Isochronous Termination procedure (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_16_4</td>
<td>False</td>
<td>Broadcast Isochronous Channel Map Update Procedure (C.2)</td>
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### Observer Privacy Feature

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<td>Privacy Feature (O)</td>
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<td>TSPC_GAP_17_2</td>
<td>True</td>
<td>Non-Resolvable Private Address Generation Procedure (C.1)</td>
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<tr>
<td>TSPC_GAP_17_3</td>
<td>True</td>
<td>Resolvable Private Address Resolution Procedure (O)</td>
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<tr>
<td>TSPC_GAP_17_4</td>
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<td>Resolvable Private Address Generation Procedure (C.2)</td>
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### Periodic Advertising Modes and Procedures

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<td>Periodic Advertising Synchronization Establishment procedure without listening for periodic advertising (C.1)</td>
</tr>
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### Observer Security Aspects Features

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<td>LE Security Mode 3, Level 1 (C.2)</td>
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<td>TSPC_GAP_17b_3</td>
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### Peripheral Physical Layer

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<td>Receiver (M)</td>
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Peripheral Link Layer States

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<tr>
<td>TSPC_GAP_19_1</td>
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<td>Standby (M)</td>
</tr>
<tr>
<td>TSPC_GAP_19_2</td>
<td>True</td>
<td>Advertising (M)</td>
</tr>
<tr>
<td>TSPC_GAP_19_3</td>
<td>True</td>
<td>Connection, Peripheral Role (M)</td>
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Peripheral Link Layer Advertising Event Types

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<tr>
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<td>Connectable and Scannable Undirected Event (M)</td>
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<tr>
<td>TSPC_GAP_20_2</td>
<td>True</td>
<td>Connectable Directed Event (O)</td>
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<tr>
<td>TSPC_GAP_20_3</td>
<td>True</td>
<td>Non-Connectable and Non-Scannable Undirected Event (O)</td>
</tr>
<tr>
<td>TSPC_GAP_20_4</td>
<td>True</td>
<td>Scannable Undirected Event (O)</td>
</tr>
<tr>
<td>TSPC_GAP_20_5</td>
<td>True</td>
<td>Connectable Undirected Event (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_20_6</td>
<td>True</td>
<td>Non-Connectable and Non-Scannable Directed Event (C.1)</td>
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<tr>
<td>TSPC_GAP_20_7</td>
<td>True</td>
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Peripheral Link Layer Advertising Data Types

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<tr>
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<td>AD Type – Service UUID (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_2</td>
<td>True</td>
<td>AD Type – Local Name (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_20A_3</td>
<td>True</td>
<td>AD Type – Flags (C.2)</td>
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<tr>
<td>TSPC_GAP_20A_4</td>
<td>True</td>
<td>AD Type – Manufacturer Specific Data (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_5</td>
<td>True</td>
<td>AD Type – TX Power Level (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_6</td>
<td>False</td>
<td>AD Type – Security Manager Out of Band (OOB) (C.3)</td>
</tr>
<tr>
<td>TSPC_GAP_20A_7</td>
<td>True</td>
<td>AD Type – Security Manager TK Value (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_20A_8</td>
<td>True</td>
<td>AD Type – Peripheral Connection Interval Range (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_20A_9</td>
<td>True</td>
<td>AD Type – Service Solicitation (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_10</td>
<td>True</td>
<td>AD Type – Service Data (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_11</td>
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<td>AD Type – Appearance (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_12</td>
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<td>AD Type – Public Target Address (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_13</td>
<td>True</td>
<td>AD Type – Random Target Address (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_14</td>
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<td>AD Type – Advertising Interval (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_15</td>
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<td>AD Type – LE Bluetooth Device Address (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_16</td>
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<td>AD Type – LE Role (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_17</td>
<td>True</td>
<td>AD Type – URI (O)</td>
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Peripheral Link Layer Control Procedures

6.1. Bluetooth
### Peripheral Discovery Modes and Procedures

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<tr>
<td>TSPC_GAP_22_1</td>
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<td>Non-Discoverable Mode (M)</td>
</tr>
<tr>
<td>TSPC_GAP_22_2</td>
<td>True</td>
<td>Limited Discoverable Mode (O)</td>
</tr>
<tr>
<td>TSPC_GAP_22_3</td>
<td>True</td>
<td>General Discoverable Mode (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_22_4</td>
<td>True</td>
<td>Name Discovery Procedure (O)</td>
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### Peripheral Connection Modes and Procedures

<table>
<thead>
<tr>
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<tr>
<td>TSPC_GAP_23_1</td>
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<td>Non-Connectable Mode (M)</td>
</tr>
<tr>
<td>TSPC_GAP_23_2</td>
<td>False</td>
<td>Directed Connectable Mode (O)</td>
</tr>
<tr>
<td>TSPC_GAP_23_3</td>
<td>True</td>
<td>Undirected Connectable Mode (M)</td>
</tr>
<tr>
<td>TSPC_GAP_23_4</td>
<td>True</td>
<td>Connection Parameter Update Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_23_5</td>
<td>True</td>
<td>Terminate Connection Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_23_6</td>
<td>False</td>
<td>Connected Isochronous Stream Request procedure (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_23_7</td>
<td>False</td>
<td>Connected Isochronous Stream Termination procedure (C.1)</td>
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### Peripheral Bonding Modes and Procedures

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<td>Non-Bondable Mode (M)</td>
</tr>
<tr>
<td>TSPC_GAP_24_2</td>
<td>True</td>
<td>Bondable Mode (O)</td>
</tr>
<tr>
<td>TSPC_GAP_24_3</td>
<td>True</td>
<td>Bonding Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_24_4</td>
<td>True</td>
<td>Multiple Bonds (C.1)</td>
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### Peripheral Security Aspects Features
### Parameter Name

<table>
<thead>
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<tr>
<td>TSPC_GAP_25_1</td>
<td>True</td>
<td>Security Mode 1 (O)</td>
</tr>
<tr>
<td>TSPC_GAP_25_2</td>
<td>True</td>
<td>Security Mode 2 (O)</td>
</tr>
<tr>
<td>TSPC_GAP_25_3</td>
<td>True</td>
<td>Authentication Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_25_4</td>
<td>True</td>
<td>Authorization Procedure (O)</td>
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<tr>
<td>TSPC_GAP_25_5</td>
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<td>Connection Data Signing Procedure (O)</td>
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<tr>
<td>TSPC_GAP_25_6</td>
<td>True</td>
<td>Authenticate Signed Data Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_25_7</td>
<td>True</td>
<td>Authenticated Pairing (LE security mode 1 level 3) (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_25_8</td>
<td>True</td>
<td>Unauthenticated Pairing (LE security mode 1 level 2) (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_25_9</td>
<td>True</td>
<td>LE Security Mode 1 Level 4 (C.3)</td>
</tr>
<tr>
<td>TSPC_GAP_25_10</td>
<td>True</td>
<td>Secure Connections Only Mode (C.4)</td>
</tr>
<tr>
<td>TSPC_GAP_25_11</td>
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<td>Unauthenticated Pairing (LE security mode 1 level 2) with LE Secure Connections Pairing only (C.3)</td>
</tr>
<tr>
<td>TSPC_GAP_25_12</td>
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<td>Authenticated Pairing (LE security mode 1 level 3) with LE Secure Connections Pairing only (C.3)</td>
</tr>
<tr>
<td>TSPC_GAP_25_13</td>
<td>True</td>
<td>Minimum 128 Bit entropy key (C.5)</td>
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### Peripheral Privacy Feature

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<td>Non-Resolvable Private Address Generation Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_26_3</td>
<td>True</td>
<td>Resolvable Private Address Generation Procedure (C.1)</td>
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<tr>
<td>TSPC_GAP_26_4</td>
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<td>Resolvable Private Address Resolution Procedure (C.1)</td>
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### Peripheral GAP Characteristics

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<tr>
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<td>True</td>
<td>Appearance (M)</td>
</tr>
<tr>
<td>TSPC_GAP_27_5</td>
<td>True</td>
<td>Peripheral Preferred Connection Parameters (O)</td>
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<tr>
<td>TSPC_GAP_27_6</td>
<td>True</td>
<td>Writeable Device Name (O)</td>
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<tr>
<td>TSPC_GAP_27_7</td>
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<td>Writeable Appearance (O)</td>
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<tr>
<td>TSPC_GAP_27_9</td>
<td>True</td>
<td>Central Address Resolution (C.1)</td>
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### Periodic Advertising Modes and Procedures

<table>
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<td>Periodic Advertising Synchronization Transfer procedure (C.1)</td>
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<td>Periodic Advertising Synchronization Establishment procedure over an LE connection without listening for periodic advertising (C.2)</td>
</tr>
<tr>
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### Central Physical Layer

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### Central Link Layer States

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<tr>
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### Central Link Layer Scanning Types

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### Central Link Layer Control Procedures

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<td>Channel Map Update Procedure (M)</td>
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<td>Encryption Procedure (O)</td>
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<td>TSPC_GAP_31_4</td>
<td>True</td>
<td>Central Initiated Feature Exchange Procedure (M)</td>
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<td>TSPC_GAP_31_5</td>
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<td>Version Exchange Procedure (M)</td>
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### Central Discovery Modes and Procedures

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<tr>
<td>TSPC_GAP_32_3</td>
<td>True</td>
<td>Name Discovery Procedure (O)</td>
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### Central Connection Modes and Procedures
<table>
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<tbody>
<tr>
<td>TSPC_GAP_33_1</td>
<td>True</td>
<td>Auto Connection Establishment Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_33_2</td>
<td>True</td>
<td>General Connection Establishment Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_33_3</td>
<td>False</td>
<td>Selective Connection Establishment Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_33_4</td>
<td>True</td>
<td>Selective Connection Establishment Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_33_5</td>
<td>True</td>
<td>Connection Parameter Update Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_33_6</td>
<td>True</td>
<td>Terminate Connection Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_33_7</td>
<td>False</td>
<td>Connected Isochronous Stream Creation procedure (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_33_8</td>
<td>False</td>
<td>Connected Isochronous Stream Termination procedure (C.1)</td>
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**Central Bonding Modes and Procedures**

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<tr>
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<td>Non-Bondable Mode (M)</td>
</tr>
<tr>
<td>TSPC_GAP_34_2</td>
<td>True</td>
<td>Bondable Mode (O)</td>
</tr>
<tr>
<td>TSPC_GAP_34_3</td>
<td>True</td>
<td>Bonding Procedure (O)</td>
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**Central Security Features**

<table>
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<td>Security Mode 1 (O)</td>
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<tr>
<td>TSPC_GAP_35_2</td>
<td>True</td>
<td>Security Mode 2 (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_3</td>
<td>True</td>
<td>Authentication Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_4</td>
<td>False</td>
<td>Authorization Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_5</td>
<td>True</td>
<td>Connection Data Signing Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_6</td>
<td>True</td>
<td>Authenticate Signed Data Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_7</td>
<td>True</td>
<td>Unauthenticated Pairing (LE security mode 1 level 3) (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_35_8</td>
<td>True</td>
<td>LE Security Mode 1 Level 4 (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_35_9</td>
<td>True</td>
<td>Secure Connections Only Mode (C.3)</td>
</tr>
<tr>
<td>TSPC_GAP_35_10</td>
<td>False</td>
<td>Unauthenticated Pairing (LE security mode 1 level 2) with LE Secure Connections Pairing only (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_35_11</td>
<td>False</td>
<td>Authenticated Pairing (LE security mode 1 level 3) with LE Secure Connections Pairing only (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_35_12</td>
<td>True</td>
<td>Minimum 128 Bit entropy key (C.4)</td>
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**Central Privacy Feature**

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<td>Privacy Feature (O)</td>
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<td>TSPC_GAP_36_2</td>
<td>True</td>
<td>Non-Resolvable Private Address Generation Procedure (O)</td>
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<tr>
<td>TSPC_GAP_36_3</td>
<td>True</td>
<td>Resolvable Private Address Resolution Procedure (C.1)</td>
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<tr>
<td>TSPC_GAP_36_5</td>
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<td>Resolvable Private Address Generation Procedure (C.1)</td>
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**Central GAP Characteristics**
### Periodic Advertising Modes and Procedures

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<td>Device Name (M)</td>
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<td>TSPC_GAP_37_2</td>
<td>True</td>
<td>Appearance (M)</td>
</tr>
<tr>
<td>TSPC_GAP_37_3</td>
<td>True</td>
<td>Central Address Resolution (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_37a_1</td>
<td>False</td>
<td>Periodic Advertising Synchronization Transfer procedure (C.1)</td>
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<tr>
<td>TSPC_GAP_37a_2</td>
<td>False</td>
<td>Periodic Advertising Synchronization Establishment procedure over an LE connection without listening for periodic advertising (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_37a_3</td>
<td>False</td>
<td>Periodic Advertising Synchronization Establishment procedure over an LE connection with listening for periodic advertising (C.3)</td>
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### BR/EDR/LE Roles

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<td>Broadcaster (C.1)</td>
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<td>TSPC_GAP_38_2</td>
<td>False</td>
<td>Observer (C.1)</td>
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<tr>
<td>TSPC_GAP_38_3</td>
<td>False</td>
<td>Peripheral (C.1)</td>
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<tr>
<td>TSPC_GAP_38_4</td>
<td>False</td>
<td>Central (C.1)</td>
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### Central BR/EDR/LE Security Aspects

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<td>Security Aspects (M)</td>
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<tr>
<td>TSPC_GAP_41_2a</td>
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<td>Derivation of BR/EDR Link Key from LE LTK (C.1)</td>
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<tr>
<td>TSPC_GAP_41_2b</td>
<td>False</td>
<td>Derivation of LE LTK from BR/EDR Link Key (C.2)</td>
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### Peripheral BR/EDR/LE Security Aspects

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<td>Security Aspects (M)</td>
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<tr>
<td>TSPC_GAP_43_2a</td>
<td>False</td>
<td>Derivation of BR/EDR Link Key from LE LTK (C.1)</td>
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<tr>
<td>TSPC_GAP_43_2b</td>
<td>False</td>
<td>Derivation of LE LTK from BR/EDR Link Key (C.2)</td>
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### Central Simultaneous BR/EDR and LE Transports

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<td>TSPC_GAP_44_1</td>
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<td>Simultaneous BR/EDR and LE Transports – BR/EDR Peripheral to the same device (O)</td>
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<tr>
<td>TSPC_GAP_44_2</td>
<td>False</td>
<td>Simultaneous BR/EDR and LE Transports – BR/EDR Central to the same device (O)</td>
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</table>
## Peripheral Simultaneous BR/EDR and LE Transports

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<tr>
<td>TSPC_GAP_45_1</td>
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<td>Simultaneous BR/EDR and LE Transports – BR/EDR Peripheral to the same device (O)</td>
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<tr>
<td>TSPC_GAP_45_2</td>
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<td>Simultaneous BR/EDR and LE Transports – BR/EDR Central to the same device (O)</td>
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**GATT ICS**  PTS version: 8.0.3

M - mandatory
O - optional

### Generic Attribute Profile Support

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<tr>
<td>TSPC_GATT_1_1</td>
<td>True</td>
<td>Generic Attribute Profile (GATT) Client (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_1_2</td>
<td>True</td>
<td>Generic Attribute Profile (GATT) Server (C.2)</td>
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### GATT role configuration

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<tr>
<td>TSPC_GATT_1a_1</td>
<td>True</td>
<td>GATT Client over LE (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_1a_2</td>
<td>False</td>
<td>GATT Client over BR/EDR (C.2)</td>
</tr>
<tr>
<td>TSPC_GATT_1a_3</td>
<td>True</td>
<td>GATT Server over LE (C.3)</td>
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<tr>
<td>TSPC_GATT_1a_4</td>
<td>False</td>
<td>GATT Server over BR/EDR (C.4)</td>
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### Attribute Protocol Transport

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<tr>
<td>TSPC_GATT_2_1</td>
<td>False</td>
<td>Attribute Protocol Supported over BR/EDR (L2CAP fixed channel support) (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_2_2</td>
<td>True</td>
<td>Attribute Protocol Supported over LE (C.2)</td>
</tr>
<tr>
<td>TSPC_GATT_2_3</td>
<td>True</td>
<td>Enhanced ATT bearer Attribute Protocol Supported (L2CAP fixed EATT PSM supported) (C.3)</td>
</tr>
<tr>
<td>TSPC_GATT_2_4</td>
<td>True</td>
<td>Enhanced ATT bearer supported over LE (C.4)</td>
</tr>
<tr>
<td>TSPC_GATT_2_5</td>
<td>False</td>
<td>Enhanced ATT bearer supported over BR/EDR (C.5)</td>
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### Generic Attribute Profile Feature Support, by Client

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<td>Exchange MTU (C.11)</td>
</tr>
<tr>
<td>TSPC_GATT_3_2</td>
<td>True</td>
<td>Discover All Primary Services (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_3</td>
<td>True</td>
<td>Discover Primary Services by Service UUID (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_4</td>
<td>True</td>
<td>Find Included Services (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_5</td>
<td>True</td>
<td>Discover All characteristics of a Service (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_6</td>
<td>True</td>
<td>Discover Characteristics by UUID (O)</td>
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6.1. Bluetooth
### Table 3 – continued from previous page

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<td>True</td>
<td>Discover All Characteristic Descriptors (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_8</td>
<td>True</td>
<td>Read Characteristic Value (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_9</td>
<td>True</td>
<td>Read Using Characteristic UUID (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_10</td>
<td>True</td>
<td>Read Long Characteristic Values (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_11</td>
<td>True</td>
<td>Read Multiple Characteristic Values (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_12</td>
<td>True</td>
<td>Write without Response (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_13</td>
<td>True</td>
<td>Signed Write Without Response (C.11)</td>
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<tr>
<td>TSPC_GATT_3_14</td>
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<td>Write Characteristic Value (O)</td>
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<tr>
<td>TSPC_GATT_3_15</td>
<td>True</td>
<td>Write Long Characteristic Values (O)</td>
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<tr>
<td>TSPC_GATT_3_16</td>
<td>True</td>
<td>Characteristic Value Reliable Writes (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_17</td>
<td>True</td>
<td>Notifications (C.7)</td>
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<tr>
<td>TSPC_GATT_3_18</td>
<td>True</td>
<td>Indications (M)</td>
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<tr>
<td>TSPC_GATT_3_19</td>
<td>True</td>
<td>Read Characteristic Descriptors (O)</td>
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<tr>
<td>TSPC_GATT_3_20</td>
<td>True</td>
<td>Read Long Characteristic Descriptors (O)</td>
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<td>TSPC_GATT_3_21</td>
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<td>Write Characteristic Descriptors (O)</td>
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<td>True</td>
<td>Write Long Characteristic Descriptors (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_23</td>
<td>True</td>
<td>Service Changed Characteristic (M)</td>
</tr>
<tr>
<td>TSPC_GATT_3_24</td>
<td>False</td>
<td>Configured Broadcast (C.2)</td>
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<td>TSPC_GATT_3_25</td>
<td>True</td>
<td>Client Supported Features Characteristic (C.4)</td>
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<td>TSPC_GATT_3_26</td>
<td>True</td>
<td>Database Hash Characteristic (C.4)</td>
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<td>TSPC_GATT_3_27</td>
<td>False</td>
<td>Read and Interpret Characteristic Presentation Format (O)</td>
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<td>TSPC_GATT_3_28</td>
<td>False</td>
<td>Read and Interpret Characteristic Aggregate Format (C.6)</td>
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<tr>
<td>TSPC_GATT_3_29</td>
<td>False</td>
<td>Read Multiple Variable Length Characteristic Values (C.9)</td>
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<tr>
<td>TSPC_GATT_3_30</td>
<td>False</td>
<td>Multiple Variable Length Notifications (C.10)</td>
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### Generic Attribute Profile Feature Support, by Server

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<td>Exchange MTU (C.6)</td>
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<td>True</td>
<td>Discover All Primary Services (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_3</td>
<td>True</td>
<td>Discover Primary Services by Service UUID (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_4</td>
<td>True</td>
<td>Find Included Services (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_5</td>
<td>True</td>
<td>Discover All characteristics of a Service (M)</td>
</tr>
<tr>
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<td>True</td>
<td>Discover Characteristics by UUID (M)</td>
</tr>
<tr>
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<td>True</td>
<td>Discover All Characteristic Descriptors (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_8</td>
<td>True</td>
<td>Read Characteristic Value (M)</td>
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<tr>
<td>TSPC_GATT_4_9</td>
<td>True</td>
<td>Read Using Characteristic UUID (M)</td>
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<td>True</td>
<td>Read Long Characteristic Values (C.12)</td>
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<td>Signed Write Without Response (C.6)</td>
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<td>Indications (C.1)</td>
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<td>Configured Broadcast (C.5)</td>
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<td>Execute Write Request with empty queue (C.7)</td>
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<td>Client Supported Features Characteristic (C.9)</td>
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<td>TSPC_GATT_4_27</td>
<td>True</td>
<td>Database Hash Characteristic (C.8)</td>
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<td>TSPC_GATT_4_28</td>
<td>False</td>
<td>Report Characteristic Value: Characteristic Presentation Format (O)</td>
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<td>False</td>
<td>Report aggregate Characteristic Value: Characteristic Aggregate Format (C.10)</td>
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<td>Read Multiple Variable Length Characteristic Values (C.13)</td>
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### SDP Interoperability

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<td>Discover GATT Services using Service Discovery Profile (C.1)</td>
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<td>TSPC_GATT_6_3</td>
<td>False</td>
<td>Publish SDP record for GATT services support via BR/EDR (C.2)</td>
</tr>
</tbody>
</table>

### Attribute Protocol Transport Security

<table>
<thead>
<tr>
<th>Parameter Name</th>
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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_GATT_7_1</td>
<td>False</td>
<td>Security Mode 4 (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_7_2</td>
<td>True</td>
<td>LE Security Mode 1 (C.5)</td>
</tr>
<tr>
<td>TSPC_GATT_7_3</td>
<td>True</td>
<td>LE Security Mode 2 (C.6)</td>
</tr>
<tr>
<td>TSPC_GATT_7_4</td>
<td>True</td>
<td>LE Authentication Procedure (C.4)</td>
</tr>
<tr>
<td>TSPC_GATT_7_5</td>
<td>True</td>
<td>LE connection data signing procedure (C.2)</td>
</tr>
<tr>
<td>TSPC_GATT_7_6</td>
<td>True</td>
<td>LE Authenticate signed data procedure (C.2)</td>
</tr>
<tr>
<td>TSPC_GATT_7_7</td>
<td>True</td>
<td>LE Authorization Procedure (C.3)</td>
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### Multiple Simultaneous ATT Bearers

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<tbody>
<tr>
<td>TSPC_GATT</td>
<td>False</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over LE and ATT over BR/EDR (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT</td>
<td>True</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over LE and EATT over LE (C.2)</td>
</tr>
<tr>
<td>TSPC_GATT</td>
<td>False</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over BR/EDR and EATT over BR/EDR (C.3)</td>
</tr>
<tr>
<td>TSPC_GATT</td>
<td>False</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over LE and EATT over BR/EDR (C.4)</td>
</tr>
<tr>
<td>TSPC_GATT</td>
<td>False</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over BR/EDR and EATT over LE (C.5)</td>
</tr>
<tr>
<td>TSPC_GATT</td>
<td>False</td>
<td>Support for multiple simultaneous active EATT bearers from same device – EATT over BR/EDR and EATT over LE (C.6)</td>
</tr>
<tr>
<td>TSPC_GATT</td>
<td>False</td>
<td>Support for multiple simultaneous active EATT bearers from same device – EATT over BR/EDR (C.7)</td>
</tr>
<tr>
<td>TSPC_GATT</td>
<td>True</td>
<td>Support for multiple simultaneous active EATT bearers from same device – EATT over LE (C.7)</td>
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</table>

### L2CAP ICS

PTS version: 8.0.3

M - mandatory

---

6.1. Bluetooth
## L2CAP Transport Configuration

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<tr>
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<th>Description</th>
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<tr>
<td>TSPC_L2CAP_0</td>
<td>False</td>
<td>BR/EDR (includes possible support of GAP LE Broadcaster or LE Observer roles) (C.1)</td>
</tr>
<tr>
<td>TSPC_L2CAP_0</td>
<td>True</td>
<td>LE (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_0</td>
<td>False</td>
<td>BR/EDR/LE (C.3)</td>
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### Roles

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<tr>
<td>TSPC_L2CAP_1_1</td>
<td>False</td>
<td>Data Channel Initiator (C.3)</td>
</tr>
<tr>
<td>TSPC_L2CAP_1_2</td>
<td>False</td>
<td>Data Channel Acceptor (C.1)</td>
</tr>
<tr>
<td>TSPC_L2CAP_1_3</td>
<td>True</td>
<td>LE Master (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_1_4</td>
<td>True</td>
<td>LE Slave (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_1_5</td>
<td>True</td>
<td>LE Data Channel Initiator (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_1_6</td>
<td>True</td>
<td>LE Data Channel Acceptor (C.5)</td>
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### General Operation

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<tr>
<td>TSPC_L2CAP_2_1</td>
<td>False</td>
<td>Support of L2CAP signalling channel (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_2</td>
<td>False</td>
<td>Support of configuration process (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_3</td>
<td>False</td>
<td>Support of connection oriented data channel (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_4</td>
<td>False</td>
<td>Support of command echo request (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_5</td>
<td>False</td>
<td>Support of command echo response (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_6</td>
<td>False</td>
<td>Support of command information request (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_7</td>
<td>False</td>
<td>Support of command information response (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_8</td>
<td>False</td>
<td>Support of a channel group (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_9</td>
<td>False</td>
<td>Support of packet for connectionless channel (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_10</td>
<td>False</td>
<td>Support retransmission mode (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_11</td>
<td>False</td>
<td>Support flow control mode (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_12</td>
<td>False</td>
<td>Enhanced Retransmission Mode (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_13</td>
<td>False</td>
<td>Streaming Mode (O)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_14</td>
<td>False</td>
<td>FCS Option (C.1)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_15</td>
<td>False</td>
<td>Generate Local Busy Condition (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_16</td>
<td>False</td>
<td>Send Reject (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_17</td>
<td>False</td>
<td>Send Selective Reject (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_18</td>
<td>False</td>
<td>Mandatory use of ERTM (C.3)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_19</td>
<td>False</td>
<td>Mandatory use of Streaming Mode (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_20</td>
<td>False</td>
<td>Optional use of ERTM (C.3)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_21</td>
<td>False</td>
<td>Optional use of Streaming Mode (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_22</td>
<td>False</td>
<td>Send data using SAR in ERTM (C.5)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_23</td>
<td>False</td>
<td>Send data using SAR in Streaming Mode (C.6)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_24</td>
<td>False</td>
<td>Actively request Basic Mode for a PSM that supports the use of ERTM or Streaming Mode (C.7)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_25</td>
<td>False</td>
<td>Supports performing L2CAP channel mode configuration fallback from SM to ERTM (C.8)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_26</td>
<td>False</td>
<td>Supports sending more than one unacknowledged I-Frame when operating in ERTM (C.9)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_27</td>
<td>False</td>
<td>Supports sending more than three unacknowledged I-Frame when operating in ERTM (C.9)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_28</td>
<td>False</td>
<td>Supports configuring the peer TxWindow greater than 1. (C.10)</td>
</tr>
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<table>
<thead>
<tr>
<th>Parameter Name</th>
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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_L2CAP_2_29</td>
<td>False</td>
<td>AMP Support (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_30</td>
<td>False</td>
<td>Fixed Channel Support (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_31</td>
<td>False</td>
<td>AMP Manager Support (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_32</td>
<td>False</td>
<td>ERTM over AMP (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_33</td>
<td>False</td>
<td>Streaming Mode Source over AMP Support (C.12)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_34</td>
<td>False</td>
<td>Streaming Mode Sink over AMP Support (C.12)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_35</td>
<td>False</td>
<td>Unicast Connectionless Data, Reception (O)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_36</td>
<td>False</td>
<td>Ability to transmit an unencrypted packet over a unicast connectionless L2CAP channel (M)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_37</td>
<td>False</td>
<td>Ability to transmit an encrypted packet over a unicast connectionless L2CAP channel (M)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_38</td>
<td>False</td>
<td>Extended Flow Specification for BR/EDR (C.7)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_39</td>
<td>False</td>
<td>Extended Window Size (C.7)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_40</td>
<td>True</td>
<td>Support of Low Energy signaling channel (C.13)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_41</td>
<td>True</td>
<td>Support of command reject (C.13)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_42</td>
<td>True</td>
<td>Send Connection Parameter Update Request (C.14)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_43</td>
<td>True</td>
<td>Send Connection Parameter Update Response (C.15)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_44</td>
<td>False</td>
<td>Extended Flow Specification for AMP (C.18)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_45</td>
<td>False</td>
<td>Send Disconnect Request Command (C.21)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_45a</td>
<td>True</td>
<td>Send Disconnect Request Command – LE (C.22)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_46</td>
<td>True</td>
<td>Support LE Credit Based Flow Control Mode (C.19)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_47</td>
<td>True</td>
<td>Support for LE Data Channel (C.20)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_48</td>
<td>True</td>
<td>Support Enhanced Credit Based Flow Control Mode (C.23)</td>
</tr>
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**Configurable Parameters**

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<tr>
<th>Parameter Name</th>
<th>Selected</th>
<th>Description</th>
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<tr>
<td>TSPC_L2CAP_3_</td>
<td>True</td>
<td>Support of RTX timer (M)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Support of ERTX timer (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Support minimum MTU size 48 octets (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Support MTU size larger than 48 octets (C.5)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Support of flush timeout value for reliable channel (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Support of flush timeout value for unreliable channel (C.5)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Support of bi-directional quality of service (QoS) option field (C.1)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Negotiate QoS service type (C.5)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Negotiate and support service type 'No Traffic' (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Negotiate and support service type 'Best effort' (C.3)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Negotiate and support service type 'Guaranteed' (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>True</td>
<td>Support minimum MTU size 23 octets (C.6)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Negotiate and support service type 'No traffic' for Extended Flow Specification (C.7)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Negotiate and support service type 'Best Effort' for Extended Flow Specification (C.8)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>False</td>
<td>Negotiate and support service type 'Guaranteed' for Extended Flow Specification. (C.9)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_</td>
<td>True</td>
<td>Support Multiple Simultaneous LE Data Channels (C.10)</td>
</tr>
</tbody>
</table>

**SM ICS**  PTS version: 8.0.3

M - mandatory
O - optional

6.1. Bluetooth  1561
## Role

<table>
<thead>
<tr>
<th>Parameter Name</th>
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<th>Description</th>
</tr>
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<tbody>
<tr>
<td>TSPC_SM_1_1</td>
<td>True</td>
<td>Central Role (Initiator) (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_1_2</td>
<td>True</td>
<td>Peripheral Role (Responder) (C.2)</td>
</tr>
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## Security Properties

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<tr>
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<th>Description</th>
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<tr>
<td>TSPC_SM_2_1</td>
<td>True</td>
<td>Authenticated MITM protection (O)</td>
</tr>
<tr>
<td>TSPC_SM_2_2</td>
<td>True</td>
<td>Unauthenticated no MITM protection (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_2_3</td>
<td>True</td>
<td>No security requirements (M)</td>
</tr>
<tr>
<td>TSPC_SM_2_4</td>
<td>True</td>
<td>OOB supported (O)</td>
</tr>
<tr>
<td>TSPC_SM_2_5</td>
<td>True</td>
<td>LE Secure Connections (O)</td>
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## Encryption Key Size

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<tr>
<td>TSPC_SM_3_1</td>
<td>True</td>
<td>Encryption Key Size (M)</td>
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## Pairing Method

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<tr>
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<th>Description</th>
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<tr>
<td>TSPC_SM_4_1</td>
<td>True</td>
<td>Just Works (O)</td>
</tr>
<tr>
<td>TSPC_SM_4_2</td>
<td>True</td>
<td>Passkey Entry (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_4_3</td>
<td>True</td>
<td>Out of Band (C.1)</td>
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## Security Initiation

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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_SM_5_1</td>
<td>True</td>
<td>Encryption Setup using STK (C.3)</td>
</tr>
<tr>
<td>TSPC_SM_5_2</td>
<td>True</td>
<td>Encryption Setup using LTK (O)</td>
</tr>
<tr>
<td>TSPC_SM_5_3</td>
<td>True</td>
<td>Peripheral Initiated Security (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_5_4</td>
<td>True</td>
<td>Peripheral Initiated Security – Central response (C.2)</td>
</tr>
<tr>
<td>TSPC_SM_5_5</td>
<td>False</td>
<td>Link Key Conversion Function h7 (C.4)</td>
</tr>
<tr>
<td>TSPC_SM_5_6</td>
<td>False</td>
<td>Link Key Conversion Function h6 (C.5)</td>
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## Signing Algorithm

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<tr>
<td>TSPC_SM_6_1</td>
<td>True</td>
<td>Signing Algorithm - Generation (O)</td>
</tr>
<tr>
<td>TSPC_SM_6_2</td>
<td>True</td>
<td>Signing Algorithm - Resolving (O)</td>
</tr>
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## Key Distribution

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<th>Description</th>
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<tr>
<td>TSPC_SM_7_1</td>
<td>True</td>
<td>Encryption Key (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_7_2</td>
<td>True</td>
<td>Identity Key (C.2)</td>
</tr>
<tr>
<td>TSPC_SM_7_3</td>
<td>True</td>
<td>Signing Key (C.3)</td>
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### Cross-Transport Key Derivation

<table>
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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_SM_8_1</td>
<td>False</td>
<td>Cross Transport Key Derivation Supported (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_8_2</td>
<td>False</td>
<td>Derivation of LE LTK from BR/EDR Link Key (C.2)</td>
</tr>
<tr>
<td>TSPC_SM_8_3</td>
<td>False</td>
<td>Derivation of BR/EDR Link Key from LE LTK (C.2)</td>
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</table>

### RFCOMM PICS

PTS version: 6.4
- different than PTS defaults

### Protocol Version

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<tr>
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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_RFCOMM_0_1</td>
<td>False</td>
<td>RFCOMM 1.1 with TS 07.10</td>
</tr>
<tr>
<td>TSPC_RFCOMM_0_2</td>
<td>True (*)</td>
<td>RFCOMM 1.2 with TS 07.10</td>
</tr>
</tbody>
</table>

### Supported Procedures

<table>
<thead>
<tr>
<th>Parameter Name</th>
<th>Selected</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>TSPC_RFCOMM_1_1</td>
<td>True (*)</td>
<td>Initialize RFCOMM Session</td>
</tr>
<tr>
<td>TSPC_RFCOMM_1_2</td>
<td>True (*)</td>
<td>Respond to Initialization of an RFCOMM Session</td>
</tr>
<tr>
<td>TSPC_RFCOMM_1_3</td>
<td>True</td>
<td>Shutdown RFCOMM Session</td>
</tr>
<tr>
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<td>Respond to a Shutdown of an RFCOMM Session</td>
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<tr>
<td>TSPC_RFCOMM_1_5</td>
<td>True (*)</td>
<td>Establish DLC</td>
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<tr>
<td>TSPC_RFCOMM_1_6</td>
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<td>Respond to Establishment of a DLC</td>
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<td>Disconnect DLC</td>
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<td>Respond to Disconnection of a DLC</td>
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<td>TSPC_RFCOMM_1_9</td>
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<td>Respond to and send MSC Command</td>
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<td>TSPC_RFCOMM_1_10</td>
<td>True</td>
<td>Initiate Transfer Information</td>
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<tr>
<td>TSPC_RFCOMM_1_11</td>
<td>True</td>
<td>Respond to Test Command</td>
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<tr>
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<td>Send Test Command</td>
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<tr>
<td>TSPC_RFCOMM_1_13</td>
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<td>React to Aggregate Flow Control</td>
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<td>Respond to RLS Command</td>
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<td>TSPC_RFCOMM_1_17</td>
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<td>TSPC_RFCOMM_1_18</td>
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<td>Send Non-Supported Command (NSC) response</td>
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<td>Respond to RPN Command</td>
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<td>Closing Multiplexer by First Sending a DISC Command</td>
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<td>TSPC_RFCOMM_1_22</td>
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<td>Support of Credit Based Flow Control</td>
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### MESH ICS

PTS version: 8.0.3

M - mandatory
O - optional

#### Major Profile Version (X.Y)

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### Node Capabilities - Provisioning

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### Node Capabilities – Network Layer

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<td>Transmitting and Receiving Secured Network Layer Messages (M)</td>
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<td>Relay Feature (C.1)</td>
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<td>TSPC_MESH_5_3</td>
<td>True</td>
<td>Network Message Cache (C.2)</td>
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### Node Capabilities – Lower Transport Layer

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<td>TSPC_MESH_6_3</td>
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<td>Friend Cache (C.1)</td>
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## Node Capabilities – Upper Transport Layer

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## Node Capabilities – Access Layer

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## Node Capabilities – Security

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## Node Capabilities – Mesh Management

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<td>Key Refresh Procedure (M)</td>
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<td>IV Update Procedure (M)</td>
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<td>IV Index Recovery Procedure (M)</td>
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## Node Capabilities – Foundation Mesh Models

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<td>TSPC_MESH_11_2</td>
<td>True</td>
<td>Health Server Model (M)</td>
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<td>TSPC_MESH_11_3</td>
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<td>Configuration Client Model (O)</td>
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<td>TSPC_MESH_11_4</td>
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## Node Capabilities – Proxy

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<td>TSPC_MESH_12_2</td>
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<td>GATT Server (C.2)</td>
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<tr>
<td>TSPC_MESH_12_3</td>
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<td>TSPC_MESH_12_4</td>
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<td>Advertising with Node Identity (C.2)</td>
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<td>TSPC_MESH_12_6</td>
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### Mesh GATT Services

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### GATT Server Requirements

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<tr>
<td>TSPC_MESH_14_2</td>
<td>True</td>
<td>Discover Primary Services by Service UUID (M)</td>
</tr>
<tr>
<td>TSPC_MESH_14_3</td>
<td>True</td>
<td>Write without Response (M)</td>
</tr>
<tr>
<td>TSPC_MESH_14_4</td>
<td>True</td>
<td>Notifications (M)</td>
</tr>
<tr>
<td>TSPC_MESH_14_5</td>
<td>True</td>
<td>Write Characteristic Descriptors (M)</td>
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### GATT Client Requirements

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<td>Discover Primary Services by Service UUID (C.1)</td>
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<td>TSPC_MESH_15_3</td>
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<td>Write without Response (M)</td>
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<td>TSPC_MESH_15_4</td>
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<td>TSPC_MESH_15_5</td>
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### GAP Requirements

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### Provisioner – Bearers

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### Provisioner – Provisioning
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**Provisioner – Mesh Management**

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**GATT Client Requirements**

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**GAP Requirements**

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**DIS ICS**  
PTS version: 8.0.3

M - mandatory
O - optional

**Service Version**

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6.1. Bluetooth
### Transport Requirements

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### Service Requirements

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<td>TSPC_DIS_2_5</td>
<td>True</td>
<td>Hardware Revision String Characteristic (O)</td>
</tr>
<tr>
<td>TSPC_DIS_2_6</td>
<td>True</td>
<td>Firmware Revision String Characteristic (O)</td>
</tr>
<tr>
<td>TSPC_DIS_2_7</td>
<td>True</td>
<td>Software Revision String Characteristic (O)</td>
</tr>
<tr>
<td>TSPC_DIS_2_8</td>
<td>False</td>
<td>System ID Characteristic (O)</td>
</tr>
<tr>
<td>TSPC_DIS_2_9</td>
<td>False</td>
<td>IEEE 11073-20601 Regulatory Certification Data List Characteristic (O)</td>
</tr>
<tr>
<td>TSPC_DIS_2_10</td>
<td>False</td>
<td>SDP Interoperability (C.1)</td>
</tr>
<tr>
<td>TSPC_DIS_2_11</td>
<td>True</td>
<td>PnP ID (O)</td>
</tr>
</tbody>
</table>

### 6.1.6 Bluetooth tools

This page lists and describes tools that can be used to assist during Bluetooth stack or application development in order to help, simplify and speed up the development process.

#### Mobile applications

It is often useful to make use of existing mobile applications to interact with hardware running Zephyr, to test functionality without having to write any additional code or requiring extra hardware.

The recommended mobile applications for interacting with Zephyr are:

- **Android:**
  - nRF Connect for Android
  - nRF Mesh for Android
  - LightBlue for Android

- **iOS:**
  - nRF Connect for iOS
  - nRF Mesh for iOS
  - LightBlue for iOS
Using BlueZ with Zephyr

The Linux Bluetooth Protocol Stack, BlueZ, comes with a very useful set of tools that can be used to debug and interact with Zephyr’s BLE Host and Controller. In order to benefit from these tools you will need to make sure that you are running a recent version of the Linux Kernel and BlueZ:

- Linux Kernel 4.10+
- BlueZ 4.45+

Additionally, some of the BlueZ tools might not be bundled by default by your Linux distribution. If you need to build BlueZ from scratch to update to a recent version or to obtain all of its tools you can follow the steps below:

```
git clone git://git.kernel.org/pub/scm/bluetooth/bluez.git
cd bluez
./bootstrap-configure --disable-android --disable-midi
make
```

You can then find `btattach`, `btmgt` and `btproxy` in the `tools/` folder and `btmon` in the `monitor/` folder.

You’ll need to enable BlueZ’s experimental features so you can access its most recent BLE functionality. Do this by editing the file `/lib/systemd/system/bluetooth.service` and making sure to include the `-E` option in the daemon’s execution start line:

```
ExecStart=/usr/libexec/bluetooth/bluetoothd -E
```

Finally, reload and restart the daemon:

```
sudo systemctl daemon-reload
sudo systemctl restart bluetooth
```

Running on QEMU or native_sim

It’s possible to run Bluetooth applications using either the QEMU emulator or native_sim. In either case, a Bluetooth controller needs to be exported from the host OS (Linux) to the emulator. For this purpose you will need some tools described in the Using BlueZ with Zephyr section.

Using the Host System Bluetooth Controller  The host OS’s Bluetooth controller is connected in the following manner:

- To the second QEMU serial line using a UNIX socket. This socket gets used with the help of the QEMU option `-serial unix:/tmp/bt-server-bredr`. This option gets passed to QEMU through `QEMU_EXTRA_FLAGS` automatically whenever an application has enabled Bluetooth support.
- To native_sim’s BT User Channel driver through the use of a command-line option passed to the `native_sim` executable: `--bt-dev=hci0`

On the host side, BlueZ allows you to export its Bluetooth controller through a so-called user channel for QEMU and native_sim to use.

**Note:** You only need to run `btproxy` when using QEMU. native_sim handles the UNIX socket proxying automatically.

If you are using QEMU, in order to make the Controller available you will need one additional step using `btproxy`:

1. Make sure that the Bluetooth controller is down

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2. Use the btproxy tool to open the listening UNIX socket, type:

```
sudo tools/btproxy -u -i 0
Listening on /tmp/bt-server-bredr
```

You might need to replace `-i 0` with the index of the Controller you wish to proxy.
If you see `Received unknown host packet type 0x00` when running QEMU, then add `-z` to
the btproxy command line to ignore any null bytes transmitted at startup.

Once the hardware is connected and ready to use, you can then proceed to building and running
a sample:

- Choose one of the Bluetooth sample applications located in `samples/bluetooth`.
- To run a Bluetooth application in QEMU, type:

```
west build -b qemu_x86 samples/bluetooth/<sample>
w west build -t run
```

Running QEMU now results in a connection with the second serial line to the
bt-server-bredr UNIX socket, letting the application access the Bluetooth controller.
- To run a Bluetooth application in native_sim, first build it:

```
w west build -b native_sim samples/bluetooth/<sample>
```

And then run it with:

```
$ sudo ./build/zephyr/zephyr.exe --bt-dev=hci0
```

**Using a Zephyr-based BLE Controller** Depending on which hardware you have available, you
can choose between two transports when building a single-mode, Zephyr-based BLE Controller:

- UART: Use the hci_uart sample and follow the instructions in bluetooth-hci-uart-qemu-posix.
- USB: Use the hci_usb sample and then treat it as a Host System Bluetooth Controller (see
previous section)

**HCI Tracing** When running the Host on a computer connected to an external Controller, it is
very useful to be able to see the full log of exchanges between the two, in the format of a Host
Controller Interface log. In order to see those logs, you can use the built-in btmon tool from BlueZ:

```
$ btmon
```

**Running on a Virtual Controller and native_sim**

An alternative to a Bluetooth physical controller is the use of a virtual controller. This controller
can be connected over an HCI TCP server. This TCP server must support the HCI H4 protocol.
In comparison to the physical controller variant, the virtual controller allows to test a Zephyr
application running on the native boards without a physical Bluetooth controller.

The main use case for a virtual controller is to do Bluetooth connectivity tests without the need
of Bluetooth hardware. This allows to automate Bluetooth integration tests with external applica-
tions such as a Bluetooth gateway or a mobile application.

To demonstrate this functionality an example is given to interact with a virtual controller. For
this purpose, the experimental python module Bumble from Google is used as it allows to create
a TCP Bluetooth virtual controller and connect with the Zephyr Bluetooth host. To install bumble
follow the Bumble Getting Started Guide.
**Note:** If your Zephyr application requires the use of the HCI LE Set extended commands, install the branch `controller-extended-advertising` from Bumble.

**Android Emulator** You can test the virtual controller by connecting a Bluetooth Zephyr application to the Android Emulator.

To connect your application to the Android Emulator follow the next steps:

1. Build your Zephyr application and disable the HCI ACL flow control (i.e. `CONFIG_BT_HCI_ACL_FLOW_CONTROL=n`) as the virtual controller from android does not support it at the moment.

2. Install Android Emulator version >= 33.1.4.0. The easiest way to do this is by installing the latest Android Studio Preview version.

3. Create a new Android Virtual Device (AVD) with the Android Device Manager. The AVD should use at least SDK API 34.

4. Run the Android Emulator via terminal as follows:
   ```bash
   emulator avd YOUR_AVD -packet-streamer-endpoint default
   ```

5. Create a Bluetooth bridge between the Zephyr application and the virtual controller from Android Emulator with the Bumble utility `hci-bridge`.
   ```bash
   bumble-hci-bridge tcp-server:_:1234 android-netsim
   ```
   This command will create a TCP server bridge on the local host IP address `127.0.0.1` and port number `1234`.

6. Run the Zephyr application and connect to the TCP server created in the last step.
   ```bash
   ./zephyr.exe --bt-dev=127.0.0.1:1234
   ```

After following these steps the Zephyr application will be available to the Android Emulator over the virtual Bluetooth controller that was bridged with Bumble. You can verify that the Zephyr application can communicate over Bluetooth by opening the Bluetooth settings in your AVD and scanning for your Zephyr application device. To test this you can build the Bluetooth peripheral samples such as Peripheral HR or Peripheral DIS

**Using Zephyr-based Controllers with BlueZ**

If you want to test a Zephyr-powered BLE Controller using BlueZ's Bluetooth Host, you will need a few tools described in the Using BlueZ with Zephyr section. Once you have installed the tools you can then use them to interact with your Zephyr-based controller:

```bash
sudo tools/btmgmt --index 0
[hci0]# auto-power
[hci0]# find -l
```

You might need to replace `--index 0` with the index of the Controller you wish to manage. Additional information about btmgmt can be found in its manual pages.

**6.1.7 Developing Bluetooth Applications**

Bluetooth applications are developed using the common infrastructure and approach that is described in the Application Development section of the documentation.

Additional information that is only relevant to Bluetooth applications can be found in this page.
Thread safety

Calling into the Bluetooth API is intended to be thread safe, unless otherwise noted in the documentation of the API function. The effort to ensure that this is the case for all API calls is an ongoing one, but the overall goal is formally stated in this paragraph. Bug reports and Pull Requests that move the subsystem in the direction of such goal are welcome.

Hardware setup

This section describes the options you have when building and debugging Bluetooth applications with Zephyr. Depending on the hardware that is available to you, the requirements you have and the type of development you prefer you may pick one or another setup to match your needs.

There are 4 possible hardware setups to use with Zephyr and Bluetooth:

1. Embedded
2. QEMU with an external Controller
3. native_sim with an external Controller
4. Simulated nRF5x with BabbleSim

**Embedded** This setup relies on all software running directly on the embedded platform(s) that the application is targeting. All the `Configurations` and `Build Types` are supported but you might need to build Zephyr more than once if you are using a dual-chip configuration or if you have multiple cores in your SoC each running a different build type (e.g., one running the Host, the other the Controller).

To start developing using this setup follow the **Getting Started Guide**, choose one (or more if you are using a dual-chip solution) boards that support Bluetooth and then run the application.

**Embedded HCI tracing** When running both Host and Controller in actual Integrated Circuits, you will only see normal log messages on the console by default, without any way of accessing the HCI traffic between the Host and the Controller. However, there is a special Bluetooth logging mode that converts the console to use a binary protocol that interleaves both normal log messages as well as the HCI traffic. Set the following Kconfig options to enable this protocol before building your application:

```
CONFIG_BT_DEBUG_MONITOR_UART=y
CONFIG_UART_CONSOLE=n
```

Setting `CONFIG_BT_DEBUG_MONITOR_UART` to `y` replaces the `CONFIG_BT_DEBUG_LOG` option, and setting `CONFIG_UART_CONSOLE` to `n` disables the default printk/printf hooks.

To decode the binary protocol that will now be sent to the console UART you need to use the `btmon` tool from `BlueZ`:

```
$ btmon --tty <console TTY> --tty-speed 115200
```

**Host on Linux with an external Controller**

**Note:** This is currently only available on GNU/Linux

This setup relies on a “dual-chip” `configuration` which is comprised of the following devices:

1. A `Host-only` application running in the QEMU emulator or the native_sim native port of Zephyr
2. A Controller, which can be one of the following types:
   - A commercially available Controller
   - A **Controller-only** build of Zephyr
   - A Virtual controller

**Warning:** Certain external Controllers are either unable to accept the Host to Controller flow control parameters that Zephyr sets by default (Qualcomm), or do not transmit any data from the Controller to the Host (Realtek). If you see a message similar to:

```
<wrn> bt_hci_core: opcode 0x0c33 status 0x12
```

when booting your sample of choice (make sure you have enabled `CONFIG_LOG` in your `prj.conf` before running the sample), or if there is no data flowing from the Controller to the Host, then you need to disable Host to Controller flow control. To do so, set `CONFIG_BT_HCI_ACL_FLOW_CONTROL=n` in your `prj.conf`.

**QEMU** You can run the Zephyr Host on the **QEMU emulator** and have it interact with a physical external Bluetooth Controller. Refer to **Running on QEMU or native_sim** for full instructions on how to build and run an application in this setup.

**native_sim**  
*Note:* This is currently only available on GNU/Linux

The native_sim target builds your Zephyr application with the Zephyr kernel, and some minimal HW emulation as a native Linux executable. This executable is a normal Linux program, which can be debugged and instrumented like any other, and it communicates with a physical or virtual external Controller.  

Refer to **Running on QEMU or native_sim** for full instructions on how to build and run an application with a physical controller. For the virtual controller refer to **Running on a Virtual Controller and native_sim**.

**Simulated nRF5x with BabbleSim**  
*Note:* This is currently only available on GNU/Linux

The nrf52_bsim and nrf5340bsim boards, are simulated target boards which emulate the necessary peripherals of a nRF52/53 SOC to be able to develop and test BLE applications. These boards, use:
- BabbleSim to simulate the nRF5x modem and the radio environment.
- The POSIX arch and native simulator to emulate the processor, and run natively on your host.
- **Models of the nrf5x HW**

Just like with the native_sim target, the build result is a normal Linux executable. You can find more information on how to run simulations with one or several devices in either of these boards's documentation.

With the nrf52_bsim, typically you do **Combined builds**, but it is also possible to build the controller with one of the HCI UART samples in one simulated device, and the host with the H4 driver instead of the integrated controller in another simulated device.
With the nrf5340bsim, you can build with either, both controller and host on its network core, or, with the network core running only the controller, the application core running the host and your application, and the HCI transport over IPC.

Initialization

The Bluetooth subsystem is initialized using the `bt_enable()` function. The caller should ensure that function succeeds by checking the return code for errors. If a function pointer is passed to `bt_enable()`, the initialization happens asynchronously, and the completion is notified through the given function.

Bluetooth Application Example

A simple Bluetooth beacon application is shown below. The application initializes the Bluetooth Subsystem and enables non-connectable advertising, effectively acting as a Bluetooth Low Energy broadcaster.

```c
/* Set Advertisement data. Based on the Eddystone specification: */
/* https://github.com/google/eddystone/blob/master/protocol-specification.md */
/* https://github.com/google/eddystone/tree/master/eddystone-url */
static const struct bt_data ad[] = {
    BT_DATA_BYTES(BT_DATA_FLAGS, BT_LE_AD_NO_BREDR),
    BT_DATA_BYTES(BT_DATA_UUID16_ALL, 0xaa, 0xfe),
    BT_DATA_BYTES(BT_DATA_SVC_DATA16, 0xaa, 0xfe, /* Eddystone UUID */
    0x10, /* Eddystone-URL frame type */
    0x00, /* Calibrated Tx power at 0m */
    0x80, /* URL Scheme Prefix http://www. */
    'z', 'e', 'p', 'h', 'y', 'r',
    'p', 'r', 'o', 'j', 'e', 'c', 't',
    0x08) /* .org */};

/* Set Scan Response data */
static const struct bt_data sd[] = {
    BT_DATA(BT_DATA_NAME_COMPLETE, DEVICE_NAME, DEVICE_NAME_LEN),
};

static void bt_ready(int err)
{
    char addr_s[BT_ADDR_LE_STR_LEN];
    bt_addr_le_t addr = {0};
    size_t count = 1;

    if (err) {
        printk("Bluetooth init failed (err %d)\n", err);
        return;
    }

    printk("Bluetooth initialized\n");

    /* Start advertising */
    err = bt_le_adv_start(BT_LE_ADV_NCONN_IDENTITY, ad, ARRAY_SIZE(ad),
        sd, ARRAY_SIZE(sd));
    if (err) {
        printk("Advertising failed to start (err %d)\n", err);
    }
}```
The key APIs employed by the beacon sample are `bt_enable()` that's used to initialize Bluetooth and then `bt_le_adv_start()` that's used to start advertising a specific combination of advertising and scan response data.

### 6.1.8 AutoPTS on Windows 10 with nRF52 board

**Overview**

This tutorial shows how to setup AutoPTS client and server to run both on Windows 10. We use WSL1 with Ubuntu only to build a Zephyr project to an elf file, because Zephyr SDK is not available on Windows yet. Tutorial covers only nrf52840dk.

**Update Windows and drivers**

Update Windows in:
Start -> Settings -> Update & Security -> Windows Update

Update drivers, following the instructions from your hardware vendor.

**Install Python 3**

Download and install Python 3. Setup was tested with versions >=3.8. Let the installer add the Python installation directory to the PATH and disable the path length limitation.
Install Git

Download and install Git. During installation enable option: Enable experimental support for pseudo consoles. We will use Git Bash as Windows terminal.
Install PTS 8

Install latest PTS from https://www.bluetooth.org. Remember to install drivers from installation directory “C:/Program Files (x86)/Bluetooth SIG/Bluetooth PTS/PTS Driver/win64/CSRBlueCoreUSB.inf”

Note: Starting with PTS 8.0.1 the Bluetooth Protocol Viewer is no longer included. So to capture Bluetooth events, you have to download it separately.

Setup Zephyr project for Windows

Perform Windows setup from Getting Started Guide.

Install nrftools

Connect devices
Flash board

In Device Manager find COM port of your nrf board. In my case it is COM3.
In Git Bash, go to zephyrproject

```bash
cd ~/zephyrproject
```

Build the auto-pts tester app

```bash
west build -p auto -b nrf52840dk_nrf52840 zephyr/tests/bluetooth/tester/
```

You can display flashing options with:

```bash
west flash --help
```

and flash board with built earlier elf file:

```bash
west flash --skip-rebuild --board-dir /dev/ttyS2 --elf-file ~/zephyrproject/build/zephyr/zephyr.elf
```

Note that west does not accept COMs, so use /dev/ttyS2 as the COM3 equivalent, /dev/ttyS2 as the COM3 equivalent, etc.(/dev/ttyS + decremented COM number).

**Setup auto-pts project**

In Git Bash, clone project repo:

```bash
git clone https://github.com/intel/auto-pts.git
```

Go into the project folder:

```bash
cd auto-pts
```

Install required python modules:
Install socat.exe

Download and extract socat.exe from [https://sourceforge.net/projects/unix-utils/files/socat/1.7.3.2/](https://sourceforge.net/projects/unix-utils/files/socat/1.7.3.2/) into folder `~/socat-1.7.3.2-1-x86_64/`.

Add path to directory of socat.exe to PATH:
Running AutoPTS

Server and client by default will run on localhost address. Run server:

```bash
python ./autoptsserver.py -S 65000
```

**Note:** If the error “ImportError: No module named pywintypes” appeared after the fresh setup, uninstall and install the pywin32 module:

```bash
pip install --upgrade --force-reinstall pywin32
```

Run client:

```bash
python ./autoptsclient-zephyr.py zephyr-master ~/zephyrproject/build/zephyr/zephyr.elf -t -COM3 -b nrf52 -S 65000 -C 65001
```
At the first run, when Windows asks, enable connection through firewall:

**Troubleshooting**

- “When running actual hardware test mode, I have only BTP TIMEOUTs.”

This is a problem with connection between auto-pts client and board. There are many possible causes. Try:

- Clean your auto-pts and zephyr repos with

```
git clean -fdx
```

then build and flash tester elf again.

---

### 6.1. Bluetooth

---
• If you have set up Windows on virtual machine, check if guest extensions are installed properly or change USB compatibility mode in VM settings to USB 2.0.
• Check, if firewall is not blocking python.exe or socat.exe.
• Check if board sends ready event after restart (hex 00 00 80 ff 00 00). Open serial connection to board with e.g. PuTTy with proper COM and baud rate. After board reset you should see some strings in console.
• Check if socat.exe creates tunnel to board. Run in console

```bash
socat.exe -x -v tcp-listen:65123 /dev/ttyS2,raw,b115200
```

where /dev/ttyS2 is the COM3 equivalent. Open PuTTY, set connection type to Raw, IP to 127.0.0.1, port to 65123. After board reset you should see some strings in console.

### 6.1.9 AutoPTS on Linux

**Overview**

This tutorial shows how to setup AutoPTS client on Linux with AutoPTS server running on Windows 10 virtual machine. Tested with Ubuntu 20.4 and Linux Mint 20.4.

You must have a Zephyr development environment set up. See *Getting Started Guide* for details.

Supported methods to test zephyr bluetooth host:

- Testing Zephyr Host Stack on QEMU
- Testing Zephyr Host Stack on native_sim
- Testing Zephyr combined (controller + host) build on Real hardware (such as nRF52)

For running with QEMU or native_sim, see *Running on QEMU or native_sim*.

**Setup Linux**

**Install nrftools (only required in the actual hardware test mode)**

After you extract archive, you will see 2 .deb files, e.g.:

- JLink_Linux_V688a_x86_64.deb
- nRF-Command-Line-Tools_10_12_1_Linux-amd64.deb

and README.md. To install the tools, double click on each .deb file or follow instructions from README.md.

**Setup Windows 10 virtual machine**

Choose and install your hypervisor like VMWare Workstation (preferred) or VirtualBox. On VirtualBox could be some issues, if your host has fewer than 6 CPU.

Create Windows virtual machine instance. Make sure it has at least 2 cores and installed guest extensions.

Setup tested with VirtualBox 6.1.18 and VMWare Workstation 16.1.1 Pro.

**Update Windows**  
Update Windows in:  
Start -> Settings -> Update & Security -> Windows Update

**Setup static IP**

**VMWare Works**  
On Linux, open Virtual Network Editor app and create network:
Open virtual machine network settings. Add custom adapter:

If you type ‘ifconfig’ in terminal, you should be able to find your host IP:
VirtualBox  Go to:
File -> Host Network Manager
and create network:

Open virtual machine network settings. On adapter 1 you will have created by default NAT. Add adapter 2:
Windows  Setup static IP on Windows virtual machine. Go to Settings -> Network & Internet -> Ethernet -> Unidentified network -> Edit and set:
Install Python 3  Download and install latest Python 3 on Windows. Let the installer add the Python installation directory to the PATH and disable the path length limitation.

Install Git  Download and install Git. During installation enable option: Enable experimental support for pseudo consoles. We will use Git Bash as Windows terminal.
Install PTS 8  On Windows virtual machine, install latest PTS from https://www.bluetooth.org. Remember to install drivers from installation directory “C:/Program Files (x86)/Bluetooth SIG/Bluetooth PTS/PTS Driver/win64/CSRBlueCoreUSB.inf”

Note: Starting with PTS 8.0.1 the Bluetooth Protocol Viewer is no longer included. So to capture Bluetooth events, you have to download it separately.

Connect PTS dongle  With VirtualBox there should be no problem. Just find dongle in Devices -> USB and connect.

With VMWare you might need to use some trick, if you cannot find dongle in VM -> Removable Devices. Type in Linux terminal:

```
usb-devices
```

and find in output your PTS Bluetooth USB dongle
Note Vendor and ProdID number. Close VMWare Workstation and open .vmx of your virtual machine (path similar to /home/codecoup/vmware/Windows 10/Windows 10.vmx) in text editor. Write anywhere in the file following line:

```
usb.autoConnect.device0 = "0x0a12:0x0001"
```

just replace 0x0a12 with Vendor number and 0x0001 with ProdID number you found earlier.

**Connect devices (only required in the actual hardware test mode)**
Flash board (only required in the actual hardware test mode)

On Linux, go to ~/zephyrproject. There should be already ~/zephyrproject/build directory. Flash board:

```
wes t flash
```

Setup auto-pts project

AutoPTS client on Linux  Clone auto-pts project:
Install socat, that is used to transfer BTP data stream from UART's tty file:

```bash
sudo apt-get install python-setuptools socat
```

Install required python modules:

```bash
cd auto-pts
pip3 install --user wheel
pip3 install --user -r autoptsclient_requirements.txt
```

**Autopts server on Windows virtual machine**
In Git Bash, clone auto-pts project repo:

```bash
git clone https://github.com/intel/auto-pts.git
```

Install required python modules:

```bash
cd auto-pts
pip3 install --user wheel
pip3 install --user -r autoptsserver_requirements.txt
```

Restart virtual machine.

### Running AutoPTS

Server and client by default will run on localhost address. Run server:

```bash
python ./autoptsserver.py
```

Testing Zephyr Host Stack on QEMU:

```bash
# A Bluetooth controller needs to be mounted.
# For running with HCI UART, please visit: https://docs.zephyrproject.org/latest/samples/
# bluetooth/hci_uart/README.html#bluetooth-hci-uart

python ./autoptsclient-zephyr.py "C:\Users\USER_NAME\Documents\Profile Tuning Suite\PTS_-
PROJECT\PTS_PROJECT.pqw6" \
~/zephyrproject/build/zephyr/zephyr.elf -i SERVER_IP -l LOCAL_IP
```

Testing Zephyr Host Stack on native_sim:

```bash
# A Bluetooth controller needs to be mounted.
# For running with HCI UART, please visit: https://docs.zephyrproject.org/latest/samples/
# bluetooth/hci_uart/README.html#bluetooth-hci-uart

west build -b native_sim zephyr/tests/bluetooth/tester/ -DEXTRA_CONF_FILE=overlay-native.

```

```bash
sudo python ./autoptsclient-zephyr.py "C:\Users\USER_NAME\Documents\Profile Tuning Suite\-
PTS_PROJECT\PTS_PROJECT.pqw6" \
~/zephyrproject/build/zephyr/zephyr.exe -i SERVER_IP -l LOCAL_IP --hci 0
```
Testing Zephyr combined (controller + host) build on nRF52:

**Note:** If the error “ImportError: No module named pywintypes” appeared after the fresh setup, uninstall and install the pywin32 module:

```
pip install --upgrade --force-reinstall pywin32
```

Run client:

```
python ./autoptsclient-zephyr.py zephyr-master ~/zephyrproject/build/zephyr/zephyr.elf -t /dev/ACM0 -b nrf52 -l 192.168.2.1 -i 192.168.2.2
```

At the first run, when Windows asks, enable connection through firewall:

Troubleshooting

- “After running one test, I need to restart my Windows virtual machine to run another, because of fail verdict from APICOM in PTS logs.”

It means your virtual machine has not enough processor cores or memory. Try to add more in settings. Note that a host with 4 CPUs could be not enough with VirtualBox as hypervisor. In this case, choose rather VMWare Workstation.
• “I cannot start autoptsserver-zephyr.py. I always got error:"

One or more of the following steps should help:

- Close all PTS Windows.
- Replug PTS bluetooth dongle.
- Delete temporary workspace. You will find it in auto-pts-code/workspaces/zephyr/zephyr-master/ as temp_zephyr-master. Be careful, do not remove the original one zephyr-master.pgw6.
- Restart Windows virtual machine.

6.1.10 Bluetooth APIs

Attribute Protocol (ATT)

API Reference

group bt_att

Attribute Protocol (ATT)

Defines

BT_ATT_ERR_SUCCESS
The ATT operation was successful.

BT_ATT_ERR_INVALID_HANDLE
The attribute handle given was not valid on the server.

BT_ATT_ERR_READ_NOT_PERMITTED
The attribute cannot be read.

BT_ATT_ERR_WRITE_NOT_PERMITTED
The attribute cannot be written.
BT_ATT_ERR_INVALID_PDU
The attribute PDU was invalid.

BT_ATT_ERR_AUTHENTICATION
The attribute requires authentication before it can be read or written.

BT_ATT_ERR_NOT_SUPPORTED
The ATT Server does not support the request received from the client.

BT_ATT_ERR_INVALID_OFFSET
Offset specified was past the end of the attribute.

BT_ATT_ERR_AUTHORIZATION
The attribute requires authorization before it can be read or written.

BT_ATT_ERR_PREPARE_QUEUE_FULL
Too many prepare writes have been queued.

BT_ATT_ERR_ATTRIBUTE_NOT_FOUND
No attribute found within the given attribute handle range.

BT_ATT_ERR_ATTRIBUTE_NOT_LONG
The attribute cannot be read using the ATT_READ_BLOB_REQ PDU.

BT_ATT_ERR_ENCRYPTION_KEY_SIZE
The Encryption Key Size used for encrypting this link is too short.

BT_ATT_ERR_INVALID_ATTRIBUTE_LEN
The attribute value length is invalid for the operation.

BT_ATT_ERR_UNLIKELY
The attribute request that was requested has encountered an error that was unlikely. The attribute request could therefore not be completed as requested.

BT_ATT_ERR_INSUFFICIENT_ENCRYPTION
The attribute requires encryption before it can be read or written.

BT_ATT_ERR_UNSUPPORTED_GROUP_TYPE
The attribute type is not a supported grouping attribute.

BT_ATT_ERR_INSUFFICIENT_RESOURCES
Insufficient Resources to complete the request.

BT_ATT_ERR_DB_OUT_OF_SYNC
The server requests the client to rediscover the database.
BT_ATT_ERR_VALUE_NOT_ALLOWED
   The attribute parameter value was not allowed.

BT_ATT_ERR_WRITE_REQ_REJECTED
   Write Request Rejected.

BT_ATT_ERR_CCC_IMPROPER_CONF
   Client Characteristic Configuration Descriptor Improperly Configured.

BT_ATT_ERR_PROCEDURE_IN_PROGRESS
   Procedure Already in Progress.

BT_ATT_ERR_OUT_OF_RANGE
   Out of Range.

BT_ATT_MAX_ATTRIBUTE_LEN

BT_ATT_FIRST_ATTRIBUTE_HANDLE

BT_ATT_LAST_ATTRIBUTE_HANDLE

BT_ATT_LAST_ATTRIBUTE_HANDLE

Enums

enum bt_att_chan_opt
   ATT channel option bit field values.

   Note: BT_ATT_CHAN_OPT_UNENHANCED_ONLY and
   BT_ATT_CHAN_OPT_ENHANCED_ONLY are mutually exclusive and both bits may
   not be set.

Values:

   enumerator BT_ATT_CHAN_OPT_NONE = 0x0
      Both Enhanced and Unenhanced channels can be used

   enumerator BT_ATT_CHAN_OPT_UNENHANCED_ONLY = BIT(0)
      Only Unenhanced channels will be used

   enumerator BT_ATT_CHAN_OPT_ENHANCED_ONLY = BIT(1)
      Only Enhanced channels will be used
Functions

```c
int bt_eatt_connect(struct bt_conn *conn, size_t num_channels)

Connect Enhanced ATT channels.

Sends a series of Credit Based Connection Requests to connect `num_channels` Enhanced ATT channels. The peer may have limited resources and fewer channels may be created.

**Parameters**

- `conn` – The connection to send the request on
- `num_channels` – The number of Enhanced ATT beares to request. Must be in the range 1 - CONFIG_BT_EATT_MAX, inclusive.

**Return values**

- `EINVAL` – if `num_channels` is not in the allowed range or `conn` is NULL.
- `ENOMEM` – if less than `num_channels` are allocated.
- `0` – in case of success

**Returns**

0 in case of success or negative value in case of error.
```

```c
size_t bt_eatt_count(struct bt_conn *conn)

Get number of EATT channels connected.
```

**Parameters**

- `conn` – The connection to get the number of EATT channels for.

**Returns**

The number of EATT channels connected. Returns 0 if `conn` is NULL or not connected.

Bluetooth Audio

**API Reference**

*group bt_audio*

Bluetooth Audio.

**Defines**

- `BT_AUDIO_BROADCAST_ID_SIZE`

- `BT_AUDIO_BROADCAST_ID_MAX`

  Maximum broadcast ID value.

- `BT_AUDIO_PD_PREF_NONE`

  Indicates that the server have no preference for the presentation delay.

- `BT_AUDIO_PD_MAX`

  Maximum presentation delay in microseconds.
**BT_AUDIO_BROADCAST_CODE_SIZE**

**BT_AUDIO_CODEC_CAP_CHAN_COUNT_MIN**
Minimum supported channel counts.

**BT_AUDIO_CODEC_CAP_CHAN_COUNT_MAX**
Maximum supported channel counts.

**BT_AUDIO_CODEC_CAP_CHAN_COUNT_SUPPORT(...)**
Channel count support capability.

Macro accepts variable number of channel counts. The allowed channel counts are defined by specification and have to be in range from `BT_AUDIO_CODEC_CAP_CHAN_COUNT_MIN` to `BT_AUDIO_CODEC_CAP_CHAN_COUNT_MAX` inclusive.

Example to support 1 and 3 channels: `BT_AUDIO_CODEC_CAP_CHAN_COUNT_SUPPORT(1, 3)`

**BT_AUDIO_CONTEXT_TYPE_ANY**
Any known context.

**BT_AUDIO_METADATA_TYPE_IS_KNOWN(_type)**
Helper to check whether metadata type is known by the stack.

---

**Note**: `_type` is evaluated thrice.

**BT_AUDIO_UNICAST_ANNOUNCEMENT_GENERAL**

**BT_AUDIO_UNICAST_ANNOUNCEMENT_TARGETED**

**BT_AUDIO_CODEC_DATA(_type, _bytes...)**
Helper to declare elements of `bt_audio_codec_cap` arrays.

This macro is mainly for creating an array of struct `bt_audio_codec_cap` data arrays.

**Parameters**

- `_type` – Type of advertising data field
- `_bytes` – Variable number of single-byte parameters

**BT_AUDIO_CODEC_CFG(_id, _cid, _vid, _data, _meta)**
Helper to declare Codec config parsing APIs.

**Parameters**

- `_id` – Codec ID
- `_cid` – Company ID
- `_vid` – Vendor ID
- `_data` – Codec Specific Data in LVT format
- `_meta` – Codec Specific Metadata in LVT format
BT_AUDIO_CODEC_CAP(_id, _cid, _vid, _data, _meta)
Helper to declare Codec capability parsing APIs structure.

**Parameters**
- _id – Codec ID
- _cid – Company ID
- _vid – Vendor ID
- _data – Codec Specific Data in LVT format
- _meta – Codec Specific Metadata in LVT format

BT_AUDIO_LOCATION_ANY
Any known location.

BT_AUDIO_CODEC_QOS(_interval, _framing, _phy, _sdu, _rtn, _latency, _pd)
Helper to declare elements of bt_audio_codec_qos.

**Parameters**
- _interval – SDU interval (usec)
- _framing – Framing
- _phy – Target PHY
- _sdu – Maximum SDU Size
- _rtn – Retransmission number
- _latency – Maximum Transport Latency (msec)
- _pd – Presentation Delay (usec)

BT_AUDIO_CODEC_QOS_UNFRAMED(_interval, _sdu, _rtn, _latency, _pd)
Helper to declare Input Unframed bt_audio_codec_qos.

**Parameters**
- _interval – SDU interval (usec)
- _sdu – Maximum SDU Size
- _rtn – Retransmission number
- _latency – Maximum Transport Latency (msec)
- _pd – Presentation Delay (usec)

BT_AUDIO_CODEC_QOS_FRAMED(_interval, _sdu, _rtn, _latency, _pd)
Helper to declare Input Framed bt_audio_codec_qos.

**Parameters**
- _interval – SDU interval (usec)
- _sdu – Maximum SDU Size
- _rtn – Retransmission number
- _latency – Maximum Transport Latency (msec)
- _pd – Presentation Delay (usec)

BT_AUDIO_CODEC_QOS_PREF(_unframed_supported, _phy, _rtn, _latency, _pd_min, _pd_max, _pref_pd_min, _pref_pd_max)
Helper to declare elements of bt_audio_codec_qos_pref.

**Parameters**
- _unframed_supported – Unframed PDUs supported
- _phy – Preferred Target PHY
- _rtn – Preferred Retransmission number
- _latency – Preferred Maximum Transport Latency (msec)
- _pd_min – Minimum Presentation Delay (usec)
- _pd_max – Maximum Presentation Delay (usec)
- _pref_pd_min – Preferred Minimum Presentation Delay (usec)
- _pref_pd_max – Preferred Maximum Presentation Delay (usec)

**Enums**

```c
enum bt_audio_codec_cap_type
{
    Codec capability types.
    Used to build and parse codec capabilities as specified in the PAC specification. Source
    is assigned numbers for Generic Audio, bluetooth.com.

    Values:

    enumerator BT_AUDIO_CODEC_CAP_TYPE_FREQ = 0x01
        Supported sampling frequencies.

    enumerator BT_AUDIO_CODEC_CAP_TYPE_DURATION = 0x02
        Supported frame durations.

    enumerator BT_AUDIO_CODEC_CAP_TYPE_CHAN_COUNT = 0x03
        Supported audio channel counts.

    enumerator BT_AUDIO_CODEC_CAP_TYPE_FRAME_LEN = 0x04
        Supported octets per codec frame.

    enumerator BT_AUDIO_CODEC_CAP_TYPE_FRAME_COUNT = 0x05
        Supported maximum codec frames per SDU
}
```

```c
enum bt_audio_codec_cap_freq
{
    Supported frequencies bitfield.

    Values:

    enumerator BT_AUDIO_CODEC_CAP_FREQ_8KHZ = BIT(0)
        8 KHz sampling frequency

    enumerator BT_AUDIO_CODEC_CAP_FREQ_11KHZ = BIT(1)
        11.025 KHz sampling frequency

    enumerator BT_AUDIO_CODEC_CAP_FREQ_16KHZ = BIT(2)
        16 KHz sampling frequency
}
```
enumerator BT_AUDIO_CODEC_CAP_FREQ_22KHZ = \textit{BIT}(3)
22.05 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_24KHZ = \textit{BIT}(4)
24 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_32KHZ = \textit{BIT}(5)
32 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_44KHZ = \textit{BIT}(6)
44.1 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_48KHZ = \textit{BIT}(7)
48 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_88KHZ = \textit{BIT}(8)
88.2 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_96KHZ = \textit{BIT}(9)
96 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_176KHZ = \textit{BIT}(10)
176.4 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_192KHZ = \textit{BIT}(11)
192 Khz sampling frequency

enumerator BT_AUDIO_CODEC_CAP_FREQ_384KHZ = \textit{BIT}(12)
384 Khz sampling frequency

Any frequency capability.

\textbf{enum bt\_audio\_codec\_cap\_frame\_dur}
\parSupported frame durations bitfield.
\par\textit{Values:}

enumerator BT_AUDIO_CODEC_CAP_DURATION_7_5 = \textit{BIT}(0)
7.5 msec frame duration capability

enumerator BT_AUDIO_CODEC_CAP_DURATION_10 = \textit{BIT}(1)
10 msec frame duration capability
enumerator BT_AUDIO_CODEC_CAP_DURATION_ANY =
(BT_AUDIO_CODEC_CAP_DURATION_7_5 | BT_AUDIO_CODEC_CAP_DURATION_10)
Any frame duration capability.

enumerator BT_AUDIO_CODEC_CAP_DURATION_PREFER_7_5 = BIT(4)
7.5 msec preferred frame duration capability.
This shall only be set if BT_AUDIO_CODEC_CAP_DURATION_7_5 is also set, and if
BT_AUDIO_CODEC_CAP_DURATION_PREFER_10 is not set.

enumerator BT_AUDIO_CODEC_CAP_DURATION_PREFER_10 = BIT(5)
10 msec preferred frame duration capability
This shall only be set if BT_AUDIO_CODEC_CAP_DURATION_10 is also set, and if
BT_AUDIO_CODEC_CAP_DURATION_PREFER_7_5 is not set.

enum bt_audio_codec_cap_chan_count
Values:

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_1 = BIT(0)
Supporting 1 channel.

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_2 = BIT(1)
Supporting 2 channel.

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_3 = BIT(2)
Supporting 3 channel.

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_4 = BIT(3)
Supporting 4 channel.

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_5 = BIT(4)
Supporting 5 channel.

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_6 = BIT(5)
Supporting 6 channel.

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_7 = BIT(6)
Supporting 7 channel.

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_8 = BIT(7)
Supporting 8 channel.

enumerator BT_AUDIO_CODEC_CAP_CHAN_COUNT_ANY =
(BT_AUDIO_CODEC_CAP_CHAN_COUNT_1 | BT_AUDIO_CODEC_CAP_CHAN_COUNT_2 |
BT_AUDIO_CODEC_CAP_CHAN_COUNT_3 | BT_AUDIO_CODEC_CAP_CHAN_COUNT_4 |
BT_AUDIO_CODEC_CAP_CHAN_COUNT_5 | BT_AUDIO_CODEC_CAP_CHAN_COUNT_6 |
BT_AUDIO_CODEC_CAP_CHAN_COUNT_7 | BT_AUDIO_CODEC_CAP_CHAN_COUNT_8)
Supporting all channels.

6.1. Bluetooth
enum bt_audio_codec_cfg_type
Codec configuration types.
Used to build and parse codec configurations as specified in the ASCS and BAP specifications. Source is assigned numbers for Generic Audio, bluetooth.com.

Values:

enumerator BT_AUDIO_CODEC_CFG_FREQ = 0x01
Sampling frequency.

enumerator BT_AUDIO_CODEC_CFG_DURATION = 0x02
Frame duration.

enumerator BT_AUDIO_CODEC_CFG_CHAN_ALLOC = 0x03
Audio channel allocation.

enumerator BT_AUDIO_CODEC_CFG_FRAME_LEN = 0x04
Octets per codec frame.

enumerator BT_AUDIO_CODEC_CFG_FRAME_BLKS_PER_SDU = 0x05
Codec frame blocks per SDU.

enum bt_audio_codecCfg_freq
Values:

enumerator BT_AUDIO_CODEC_CFG_FREQ_8KHZ = 0x01
8 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_11KHZ = 0x02
11.025 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_16KHZ = 0x03
16 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_22KHZ = 0x04
22.05 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_24KHZ = 0x05
24 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_32KHZ = 0x06
32 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_44KHZ = 0x07
44.1 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_48KHZ = 0x08
48 Khz codec sampling frequency
enumerator BT_AUDIO_CODEC_CFG_FREQ_88KHZ = 0x09
88.2 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_96KHZ = 0x0a
96 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_176KHZ = 0x0b
176.4 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_192KHZ = 0x0c
192 Khz codec sampling frequency

enumerator BT_AUDIO_CODEC_CFG_FREQ_384KHZ = 0x0d
384 Khz codec sampling frequency

enum bt_audio_codec_cfg_frame_dur
Values:

enumerator BT_AUDIO_CODEC_CFG_DURATION_7_5 = 0x00
7.5 msec Frame Duration configuration

enumerator BT_AUDIO_CODEC_CFG_DURATION_10 = 0x01
10 msec Frame Duration configuration

enum bt_audio_context
Audio Context Type for Generic Audio.
These values are defined by the Generic Audio Assigned Numbers, bluetooth.com
Values:

enumerator BT_AUDIO_CONTEXT_TYPE_PROHIBITED = 0

enumerator BT_AUDIO_CONTEXT_TYPE_UNSPECIFIED = BIT(0)

enumerator BT_AUDIO_CONTEXT_TYPE_CONVERSATIONAL = BIT(1)

enumerator BT_AUDIO_CONTEXT_TYPE_MEDIA = BIT(2)

enumerator BT_AUDIO_CONTEXT_TYPE_GAME = BIT(3)

enumerator BT_AUDIO_CONTEXT_TYPE_INSTRUCTIONAL = BIT(4)

enumerator BT_AUDIO_CONTEXT_TYPE_VOICE_ASSISTANTS = BIT(5)

enumerator BT_AUDIO_CONTEXT_TYPE_LIVE = BIT(6)

enumerator BT_AUDIO_CONTEXT_TYPE_SOUND_EFFECTS = BIT(7)
enumerator BT_AUDIO_CONTEXT_TYPE_NOTIFICATIONS = BIT(8)

enumerator BT_AUDIO_CONTEXT_TYPE_RINGTONE = BIT(9)

enumerator BT_AUDIO_CONTEXT_TYPE_ALERTS = BIT(10)

enumerator BT_AUDIO_CONTEXT_TYPE_EMERGENCY_ALARM = BIT(11)

enum bt_audio_parental_rating
Parental rating defined by the Generic Audio assigned numbers (bluetooth.com).
The numbering scheme is aligned with Annex F of EN 300 707 v1.2.1 which defined parental rating for viewing.
Values:

enumerator BT_AUDIO_PARENTAL_RATING_NO_RATING = 0x00

enumerator BT_AUDIO_PARENTAL_RATING_AGE_ANY = 0x01

enumerator BT_AUDIO_PARENTAL_RATING_AGE_5_OR_ABOVE = 0x02

enumerator BT_AUDIO_PARENTAL_RATING_AGE_6_OR_ABOVE = 0x03

enumerator BT_AUDIO_PARENTAL_RATING_AGE_7_OR_ABOVE = 0x04

enumerator BT_AUDIO_PARENTAL_RATING_AGE_8_OR_ABOVE = 0x05

enumerator BT_AUDIO_PARENTAL_RATING_AGE_9_OR_ABOVE = 0x06

enumerator BT_AUDIO_PARENTAL_RATING_AGE_10_OR_ABOVE = 0x07

enumerator BT_AUDIO_PARENTAL_RATING_AGE_11_OR_ABOVE = 0x08

enumerator BT_AUDIO_PARENTAL_RATING_AGE_12_OR_ABOVE = 0x09

enumerator BT_AUDIO_PARENTAL_RATING_AGE_13_OR_ABOVE = 0x0A

enumerator BT_AUDIO_PARENTAL_RATING_AGE_14_OR_ABOVE = 0x0B

enumerator BT_AUDIO_PARENTAL_RATING_AGE_15_OR_ABOVE = 0x0C

enumerator BT_AUDIO_PARENTAL_RATING_AGE_16_OR_ABOVE = 0x0D

enumerator BT_AUDIO_PARENTAL_RATING_AGE_17_OR_ABOVE = 0x0E

enumerator BT_AUDIO_PARENTAL_RATING_AGE_18_OR_ABOVE = 0x0F
enum bt_audio_active_state
Audio Active State defined by the Generic Audio assigned numbers (bluetooth.com).

Values:

enumerator BT_AUDIO_ACTIVE_STATE_DISABLED = 0x00
enumerator BT_AUDIO_ACTIVE_STATE_ENABLED = 0x01

enum bt_audio_metadata_type
Codec metadata type IDs.
Metadata types defined by the Generic Audio assigned numbers (bluetooth.com).

Values:

enumerator BT_AUDIO_METADATA_TYPE_PREF_CONTEXT = 0x01
Preferred audio context.

<table>
<thead>
<tr>
<th>Bitfield of preferred audio contexts.</th>
</tr>
</thead>
<tbody>
<tr>
<td>If 0, the context type is not a preferred use case for this codec configuration.</td>
</tr>
<tr>
<td>See the BT_AUDIO_CONTEXT_* for valid values.</td>
</tr>
</tbody>
</table>

enumerator BT_AUDIO_METADATA_TYPE_STREAM_CONTEXT = 0x02
Streaming audio context.

<table>
<thead>
<tr>
<th>Bitfield of streaming audio contexts.</th>
</tr>
</thead>
<tbody>
<tr>
<td>If 0, the context type is not a preferred use case for this codec configuration.</td>
</tr>
<tr>
<td>See the BT_AUDIO_CONTEXT_* for valid values.</td>
</tr>
</tbody>
</table>

enumerator BT_AUDIO_METADATA_TYPE_PROGRAM_INFO = 0x03
UTF-8 encoded title or summary of stream content.

enumerator BT_AUDIO_METADATA_TYPE_STREAM_LANG = 0x04
Stream language.

| 3 octet lower case language code defined by ISO 639-3 |

enumerator BT_AUDIO_METADATA_TYPE_CCID_LIST = 0x05
Array of 8-bit CCID values.

enumerator BT_AUDIO_METADATA_TYPE_PARENTAL_RATING = 0x06
Parental rating.

| See @ref bt_audio_parental_rating for valid values. |

enumerator BT_AUDIO_METADATA_TYPE_PROGRAM_INFO_URI = 0x07
UTF-8 encoded URI for additional Program information.
enumerator BT_AUDIO_METADATA_TYPE_AUDIO_STATE = 0x08
Audio active state.
See @ref bt_audio_active_state for valid values.

enumerator BT_AUDIO_METADATA_TYPE_BROADCAST_IMMEDIATE = 0x09
Broadcast Audio Immediate Rendering flag

enumerator BT_AUDIO_METADATA_TYPE_EXTENDED = 0xFE
Extended metadata.

enumerator BT_AUDIO_METADATA_TYPE_VENDOR = 0xFF
Vendor specific metadata.

enum bt_audio_location
Location values for BT Audio.
These values are defined by the Generic Audio Assigned Numbers, bluetooth.com
Values:

enumerator BT_AUDIO_LOCATION_MONO_AUDIO = 0
enumerator BT_AUDIO_LOCATION_FRONT_LEFT = BIT(0)
enumerator BT_AUDIO_LOCATION_FRONT_RIGHT = BIT(1)
enumerator BT_AUDIO_LOCATION_FRONT_CENTER = BIT(2)
enumerator BT_AUDIO_LOCATION_LOW_FREQ_EFFECTS_1 = BIT(3)
enumerator BT_AUDIO_LOCATION_BACK_LEFT = BIT(4)
enumerator BT_AUDIO_LOCATION_BACK_RIGHT = BIT(5)
enumerator BT_AUDIO_LOCATION_FRONT_LEFT_OF_CENTER = BIT(6)
enumerator BT_AUDIO_LOCATION_FRONT_RIGHT_OF_CENTER = BIT(7)
enumerator BT_AUDIO_LOCATION_BACK_CENTER = BIT(8)
enumerator BT_AUDIO_LOCATION_LOW_FREQ_EFFECTS_2 = BIT(9)
enumerator BT_AUDIO_LOCATION_SIDE_LEFT = BIT(10)
enumerator BT_AUDIO_LOCATION_SIDE_RIGHT = BIT(11)
enumerator BT_AUDIO_LOCATION_TOP_FRONT_LEFT = BIT(12)
enumerator BT_AUDIO_LOCATION_TOP_FRONT_RIGHT = BIT(13)

enumerator BT_AUDIO_LOCATION_TOP_FRONT_CENTER = BIT(14)

enumerator BT_AUDIO_LOCATION_TOP_CENTER = BIT(15)

enumerator BT_AUDIO_LOCATION_TOP_BACK_LEFT = BIT(16)

enumerator BT_AUDIO_LOCATION_TOP_BACK_RIGHT = BIT(17)

enumerator BT_AUDIO_LOCATION_TOP_SIDE_LEFT = BIT(18)

enumerator BT_AUDIO_LOCATION_TOP_SIDE_RIGHT = BIT(19)

enumerator BT_AUDIO_LOCATION_TOP_BACK_CENTER = BIT(20)

enumerator BT_AUDIO_LOCATION_BOTTOM_FRONT_CENTER = BIT(21)

enumerator BT_AUDIO_LOCATION_BOTTOM_FRONT_LEFT = BIT(22)

enumerator BT_AUDIO_LOCATION_BOTTOM_FRONT_RIGHT = BIT(23)

enumerator BT_AUDIO_LOCATION_FRONT_LEFT_WIDE = BIT(24)

enumerator BT_AUDIO_LOCATION_FRONT_RIGHT_WIDE = BIT(25)

enumerator BT_AUDIO_LOCATION_LEFT_SURROUND = BIT(26)

enumerator BT_AUDIO_LOCATION_RIGHT_SURROUND = BIT(27)

define bt_audio_dir

  Audio Capability type.

  Values:

  enumerator BT_AUDIO_DIR_SINK = 0x01

  enumerator BT_AUDIO_DIR_SOURCE = 0x02

define bt_audio_codec_qos_framing

  Codec QoS Framing.

  Values:

  enumerator BT_AUDIO_CODEC_QOS_FRAMING_UNFRAMED = 0x00

  enumerator BT_AUDIO_CODEC_QOS_FRAMING_FRAMED = 0x01
Codec QoS Preferred PHY.

Values:

enumerator BT_AUDIO_CODEC_QOS_1M = \texttt{BIT}(0)

enumerator BT_AUDIO_CODEC_QOS_2M = \texttt{BIT}(1)

enumerator BT_AUDIO_CODEC_QOS_CODED = \texttt{BIT}(2)

Functions

\texttt{int bt\_audio\_data\_parse(const uint8\_t ltv[], size\_t size, bool (*func)(struct bt\_data *data, void *user\_data), void *user\_data)}

Helper for parsing length-type-value data.

Parameters

- \texttt{ltv} – Length-type-value (LTV) encoded data.
- \texttt{size} – Size of the \texttt{ltv} data.
- \texttt{func} – Callback function which will be called for each element that's found in the data. The callback should return true to continue parsing, or false to stop parsing.
- \texttt{user\_data} – User data to be passed to the callback.

Return values

- \texttt{0} – if all entries were parsed.
- \texttt{-EINVAL} – if the data is incorrectly encoded
- \texttt{-ECANCELED} – if parsing was prematurely cancelled by the callback

\texttt{struct bt\_audio\_codec\_octets\_per\_codec\_frame}

\texttt{#include <audio.h>}

Public Members

\texttt{uint16\_t min}

Minimum number of octets supported per codec frame.

\texttt{uint16\_t max}

Maximum number of octets supported per codec frame.

\texttt{struct bt\_audio\_codec\_cap}

\texttt{#include <audio.h>} Codec capability structure.
Public Members

uint8_t path_id
    Data path ID.
    BT_ISO_DATA_PATH_HCI for HCI path, or any other value for vendor specific ID.

bool ctrlr_transcode
    Whether or not the local controller should transcode.
    This effectively sets the coding format for the ISO data path to
    BT_HCI_CODING_FORMAT_TRANSPARENT if false, else uses the
    bt_audio_codec_cfg::id.

uint8_t id
    Codec ID.

uint16_t cid
    Codec Company ID.

uint16_t vid
    Codec Company Vendor ID.

struct bt_audio_codec_cfg
    #include <audio.h> Codec specific configuration structure.

Public Members

uint8_t path_id
    Data path ID.
    BT_ISO_DATA_PATH_HCI for HCI path, or any other value for vendor specific ID.

bool ctrlr_transcode
    Whether or not the local controller should transcode.
    This effectively sets the coding format for the ISO data path to
    BT_HCI_CODING_FORMAT_TRANSPARENT if false, else uses the
    bt_audio_codec_cfg::id.

uint8_t id
    Codec ID.

uint16_t cid
    Codec Company ID.

uint16_t vid
    Codec Company Vendor ID.

struct bt_audio_codec_qos
    #include <audio.h> Codec QoS structure.
Public Members

uint8_t phy
    QoS PHY.

enum bt_audio_codec_qos_framing framing
    QoS Framing.

uint8_t rtn
    QoS Retransmission Number.

uint16_t sdu
    QoS SDU.

uint32_t interval
    QoS Frame Interval.

uint32_t pd
    QoS Presentation Delay in microseconds.
    Value range 0 to BT_AUDIO_PD_MAX.

struct bt_audio_codec_qos_pref
    #include <audio.h> Audio Stream Quality of Service Preference structure.

Public Members

bool unframed_supported
    Unframed PDUs supported.
    Unlike the other fields, this is not a preference but whether the codec supports unframed ISOAL PDUs.

uint8_t phy
    Preferred PHY.

uint8_t rtn
    Preferred Retransmission Number.

uint16_t latency
    Preferred Transport Latency.

uint32_t pd_min
    Minimum Presentation Delay in microseconds.
    Unlike the other fields, this is not a preference but a minimum requirement.
    Value range 0 to BT_AUDIO_PD_MAX, or BT_AUDIO_PD_PREF_NONE to indicate no preference.
uint32_t pd_max
    Maximum Presentation Delay.
    Unlike the other fields, this is not a preference but a maximum requirement.
    Value range 0 to BT_AUDIO_PD_MAX, or BT_AUDIO_PD_PREF_NONE to indicate no preference.

uint32_t pref_pd_min
    Preferred minimum Presentation Delay.
    Value range 0 to BT_AUDIO_PD_MAX.

uint32_t pref_pd_max
    Preferred maximum Presentation Delay.
    Value range 0 to BT_AUDIO_PD_MAX.

**group bt_audio_codec_cfg**
    Audio codec Config APIs.
    Functions to parse codec config data when formatted as LTV wrapped into Codec config parsing APIs.

**Functions**

int bt_audio_codec_cfg_freq_to_freq_hz(enum bt_audio_codec_cfg_freq freq)
    Convert assigned numbers frequency to frequency value.

    **Parameters**
    • freq – The assigned numbers frequency to convert.

    **Return values**
    • -EINVAL – if arguments are invalid.
    • The – converted frequency value in Hz.

int bt_audio_codec_cfg_freq_hz_to_freq(uint32_t freq_hz)
    Convert frequency value to assigned numbers frequency.

    **Parameters**
    • freq_hz – The frequency value to convert.

    **Return values**
    • -EINVAL – if arguments are invalid.
    • The – assigned numbers frequency (bt_audio_codec_cfg_freq).

int bt_audio_codec_cfg_get_freq(const struct bt_audio_codec_cfg *codec_cfg)
    Extract the frequency from a codec configuration.

    **Parameters**
    • codec_cfg – The codec configuration to extract data from.

    **Return values**
    • A – bt_audio_codec_cfg_freq value
    • -EINVAL – if arguments are invalid
Set the frequency of a codec configuration.

Parameters
- `codec_cfg` – The codec configuration to set data for.
- `freq` – The assigned numbers frequency to set.

Return values
- The `data_len` of `codec_cfg` on success
- `-EINVAL` – if arguments are invalid
- `-ENOMEM` – if the new value could not set or added due to memory

Convert assigned numbers frame duration to duration in microseconds.

Parameters
- `frame_dur` – The assigned numbers frame duration to convert.

Return values
- `-EINVAL` – if arguments are invalid.
- The converted frame duration value in microseconds.

Convert frame duration in microseconds to assigned numbers frame duration.

Parameters
- `frame_dur_us` – The frame duration in microseconds to convert.

Return values
- `-EINVAL` – if arguments are invalid.
- The assigned numbers frame duration (`bt_audio_codec_cfg_frame_dur`).

Extract frame duration from BT codec config.

Parameters
- `codec_cfg` – The codec configuration to extract data from.

Return values
- A `bt_audio_codec_cfg_frame_dur` value
- `-EINVAL` – if arguments are invalid
- `-ENODATA` – if not found
- `-EBADMSG` – if found value has invalid size or value

Set the frame duration of a codec configuration.

Parameters
• codec_cfg – The codec configuration to set data for.
• frame_dur – The assigned numbers frame duration to set.

Return values
• The – data_len of codec_cfg on success
• -EINVAL – if arguments are invalid
• -ENOMEM – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_get_chan_allocation(const struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_location *chan_allocation)
```

Extract channel allocation from BT codec config. The value returned is a bit field representing one or more audio locations as specified by `bt_audio_location`. Shall match one or more of the bits set in `BT_PAC_SNK_LOC/BT_PAC_SRC_LOC`.

Up to the configured `BT_AUDIO_CODEC_CAP_TYPE_CHAN_COUNT` number of channels can be present.

Parameters
• codec_cfg – The codec configuration to extract data from.
• chan_allocation – Pointer to the variable to store the extracted value in.

Return values
• 0 – if value is found and stored in the pointer provided
• -EINVAL – if arguments are invalid
• -ENODATA – if not found
• -EBADMSG – if found value has invalid size or value

```c
int bt_audio_codec_cfg_set_chan_allocation(struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_location chan_allocation)
```

Set the channel allocation of a codec configuration.

Parameters
• codec_cfg – The codec configuration to set data for.
• chan_allocation – The channel allocation to set.

Return values
• The – data_len of codec_cfg on success
• -EINVAL – if arguments are invalid
• -ENOMEM – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_get_octets_per_frame(const struct bt_audio_codec_cfg *codec_cfg)
```

Extract frame size in octets from BT codec config. The overall SDU size will be `octets_per_frame * blocks_per_sdu`.

The Bluetooth specifications are not clear about this value - it does not state that the codec shall use this SDU size only. A codec like LC3 supports variable bit-rate (per SDU) hence it might be allowed for an encoder to reduce the frame size below this value. Hence it is recommended to use the received SDU size and divide by `blocks_per_sdu` rather than relying on this `octets_per_sdu` value to be fixed.

Parameters
• codec_cfg – The codec configuration to extract data from.

Return values
• Frame – length in octets
• -EINVAL – if arguments are invalid
• -ENODATA – if not found
• -EBADMSG – if found value has invalid size or value

int bt_audio_codec_cfg_set_octets_per_frame(struct bt_audio_codec_cfg *codec_cfg,
                                          uint16_t octets_per_frame)

Set the octets per codec frame of a codec configuration.

Parameters
• codec_cfg – The codec configuration to set data for.
• octets_per_frame – The octets per codec frame to set.

Return values
• The – data_len of codec_cfg on success
• -EINVAL – if arguments are invalid
• -ENOMEM – if the new value could not set or added due to memory

int bt_audio_codec_cfg_get_frame_blocks_per_sdu(const struct bt_audio_codec_cfg
                                                  *codec_cfg, bool
                                                  fallback_to_default)

Extract number of audio frame blockss in each SDU from BT codec config.

The overall SDU size will be octets_per_frame * frame_blocks_per_sdu * number-of-channels.

If this value is not present a default value of 1 shall be used.

A frame block is one or more frames that represents data for the same period of time but for different channels. If the stream have two audio channels and this value is two there will be four frames in the SDU.

Parameters
• codec_cfg – The codec configuration to extract data from.
• fallback_to_default – If true this function will return the default value of 1 if the type is not found. In this case the function will only fail if a NULL pointer is provided.

Return values
• The – count of codec frames in each SDU if value is found else of fallback_to_default is true then the value 1 is returned if frames per sdu is not found.
• -EINVAL – if arguments are invalid
• -ENODATA – if not found
• -EBADMSG – if found value has invalid size or value

int bt_audio_codec_cfg_set_frame_blocks_per_sdu(struct bt_audio_codec_cfg
                                                 *codec_cfg, uint8_t frame_blocks)

Set the frame blocks per SDU of a codec configuration.

Parameters
• codec_cfg – The codec configuration to set data for.
- frame_blocks – The frame blocks per SDU to set.

Return values
- The – data_len of codec_cfg on success
- EINVAL – if arguments are invalid
- ENOMEM – if the new value could not set or added due to memory

int bt_audio_codecCfg_set_val(const struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_codec_cfg_type type, const uint8_t *data, size_t data_len)

Set or add a specific codec configuration value.

Parameters
- codec_cfg – [in] The codec data to set the value in.
- type – The type id to set
- data – Pointer to the data-pointer to set
- data_len – Length of data

Return values
- The – data_len of codec_cfg on success
- EINVAL – if arguments are invalid
- ENOMEM – if the new value could not set or added due to memory

int bt_audio_codecCfg_unset_val(struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_codec_cfg_type type)

Unset a specific codec configuration value.

The type and the value will be removed from the codec configuration.

Parameters
- codec_cfg – The codec data to set the value in.
- type – The type id to unset.

Return values
- The – data_len of codec_cfg on success
- EINVAL – if arguments are invalid
int bt_audio_codec_cfg_meta_get_val(const struct bt_audio_codec_cfg *codec_cfg, uint8_t type, const uint8_t **data)

Lookup a specific metadata value based on type.

**Parameters**
- `type` – [in] The type id to look for
- `data` – [out] Pointer to the data-pointer to update when item is found

**Return values**
- `Length` – of found data (may be 0)
- `-EINVAL` – if arguments are invalid
- `-ENODATA` – if not found

int bt_audio_codec_cfg_meta_set_val(struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_metadata_type type, const uint8_t *data, size_t data_len)

Set or add a specific codec configuration metadata value.

**Parameters**
- `codec_cfg` – The codec configuration to set the value in.
- `type` – The type id to set.
- `data` – Pointer to the data-pointer to set.
- `data_len` – Length of data.

**Return values**
- `The` – `meta_len` of `codec_cfg` on success
- `-EINVAL` – if arguments are invalid
- `-ENOMEM` – if the new value could not set or added due to memory

int bt_audio_codec_cfg_meta_unset_val(struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_metadata_type type)

Unset a specific codec configuration metadata value. The type and the value will be removed from the codec configuration metadata.

**Parameters**
- `codec_cfg` – The codec data to set the value in.
- `type` – The type id to unset.

**Return values**
- `The` – `meta_len` of `codec_cfg` on success
- `-EINVAL` – if arguments are invalid

int bt_audio_codec_cfg_meta_get_pref_context(const struct bt_audio_codec_cfg *codec_cfg)

Extract preferred contexts.

See `BT_AUDIO_METADATA_TYPE_PREF_CONTEXT` for more information about this value.

**Parameters**
- `codec_cfg` – The codec data to search in.
**Return values**

- The – preferred context type if positive or 0
- -EINVAL – if arguments are invalid
- -ENODATA – if not found
- -EBADMSG – if found value has invalid size

```c
int bt_audio_codec_cfg_meta_set_pref_context(struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_context ctx)
```

Set the preferred context of a codec configuration metadata.

**Parameters**

- codec_cfg – The codec configuration to set data for.
- ctx – The preferred context to set.

**Return values**

- The – data_len of codec_cfg on success
- -EINVAL – if arguments are invalid
- -ENOMEM – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_meta_get_stream_context(const struct bt_audio_codec_cfg *codec_cfg)
```

Extract stream contexts.

See `BT_AUDIO_METADATA_TYPE_STREAM_CONTEXT` for more information about this value.

**Parameters**

- codec_cfg – The codec data to search in.

**Return values**

- The – stream context type if positive or 0
- -EINVAL – if arguments are invalid
- -ENODATA – if not found
- -EBADMSG – if found value has invalid size

```c
int bt_audio_codec_cfg_meta_set_stream_context(struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_context ctx)
```

Set the stream context of a codec configuration metadata.

**Parameters**

- codec_cfg – The codec configuration to set data for.
- ctx – The stream context to set.

**Return values**

- The – data_len of codec_cfg on success
- -EINVAL – if arguments are invalid
- -ENOMEM – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_meta_get_program_info(const struct bt_audio_codec_cfg *codec_cfg)
```

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Extract program info.
See `BT_AUDIO_METADATA_TYPE_PROGRAM_INFO` for more information about this value.

Parameters
- `program_info` – [out] Pointer to the UTF-8 formatted program info.

Return values
- The `data_len` of `codec_cfg` on success
- `EINVAL` – if arguments are invalid
- `ENOMEM` – if not found

```c
int bt_audio_CODEC_CFG_META_SET_PROGRAM_INFO(struct bt_audio_CODEC_CFG *codec_cfg, const uint8_t *program_info, size_t program_info_len)
```

Set the program info of a codec configuration metadata.

Parameters
- `codec_cfg` – The codec configuration to set data for.
- `program_info` – The program info to set.
- `program_info_len` – The length of `program_info`.

Return values
- The `data_len` of `codec_cfg` on success
- `EINVAL` – if arguments are invalid
- `ENOMEM` – if the new value could not set or added due to memory

```c
int bt_audio_CODEC_CFG_META_GET_STREAM_LANG(const struct bt_audio_CODEC_CFG *codec_cfg)
```

Extract stream language.
See `BT_AUDIO_METADATA_TYPE_STREAM_LANG` for more information about this value.

Parameters
- `codec_cfg` – The codec data to search in.

Return values
- The stream language if positive or 0
- `EINVAL` – if arguments are invalid
- `ENOMEM` – if not found
- `EBADMSG` – if found value has invalid size

```c
int bt_audio_CODEC_CFG_META_SET_STREAM_LANG(struct bt_audio_CODEC_CFG *codec_cfg, uint32_t stream_lang)
```

Set the stream language of a codec configuration metadata.

Parameters
- `codec_cfg` – The codec configuration to set data for.
- `stream_lang` – The 24-bit stream language to set.

Return values
• The – data_len of codec cfg on success
• -EINVAL – if arguments are invalid
• -ENOMEM – if the new value could not set or added due to memory

int bt_audio_codec_cfg_meta_get_ccid_list(const struct bt_audio_codec_cfg *codec_cfg, const uint8_t **ccid_list)

Extract CCID list.
See BT_AUDIO_METADATA_TYPE_CCID_LIST for more information about this value.

Parameters
• codec_cfg – [in] The codec data to search in.
• ccid_list – [out] Pointer to the array containing 8-bit CCIDs.

Return values
• The – length of the ccid_list (may be 0)
• -EINVAL – if arguments are invalid
• -ENODATA – if not found

int bt_audio_codec_cfg_meta_set_ccid_list(struct bt_audio_codec_cfg *codec_cfg, const uint8_t *ccid_list, size_t ccid_list_len)

Set the CCID list of a codec configuration metadata.

Parameters
• codec_cfg – The codec configuration to set data for.
• ccid_list – The program info to set.
• ccid_list_len – The length of ccid_list.

Return values
• The – data_len of codec cfg on success
• -EINVAL – if arguments are invalid
• -ENOMEM – if the new value could not set or added due to memory

int bt_audio_codec_cfg_meta_get_parental_rating(const struct bt_audio_codec_cfg *codec_cfg)

Extract parental rating.
See BT_AUDIO_METADATA_TYPE_PARENTAL_RATING for more information about this value.

Parameters
• codec_cfg – The codec data to search in.

Return values
• The – parental rating if positive or 0
• -EINVAL – if arguments are invalid
• -ENODATA – if not found
• -EBADMSG – if found value has invalid size

int bt_audio_codec_cfg_meta_set_parental_rating(struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_parental_rating parental_rating)

Set the parental rating of a codec configuration metadata.
Parameters

- `codec_cfg` – The codec configuration to set data for.
- `parental_rating` – The parental rating to set.

Return values

- `The data_len of codec_cfg` on success
- `-EINVAL` – if arguments are invalid
- `-ENOMEM` – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_meta_get_program_info_uri(const struct bt_audio_codec_cfg *codec_cfg, const uint8_t **program_info_uri)
```

Extract program info URI.

See `BT_AUDIO_METADATA_TYPE_PROGRAM_INFO_URI` for more information about this value.

Parameters

- `program_info_uri` – [out] Pointer to the UTF-8 formatted program info URI.

Return values

- `The length of the ccid_list` (may be 0)
- `-EINVAL` – if arguments are invalid
- `-ENODATA` – if not found

```c
int bt_audio_codec_cfg_meta_set_program_info_uri(struct bt_audio_codec_cfg *codec_cfg, const uint8_t *program_info_uri, size_t program_info_uri_len)
```

Set the program info URI of a codec configuration metadata.

Parameters

- `codec_cfg` – The codec configuration to set data for.
- `program_info_uri` – The program info URI to set.
- `program_info_uri_len` – The length of `program_info_uri`.

Return values

- `The data_len of codec_cfg` on success
- `-EINVAL` – if arguments are invalid
- `-ENOMEM` – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_meta_get_audio_active_state(const struct bt_audio_codec_cfg *codec_cfg)
```

Extract audio active state.

See `BT_AUDIO_METADATA_TYPE_AUDIO_STATE` for more information about this value.

Parameters

- `codec_cfg` – The codec data to search in.

Return values
• The – preferred context type if positive or 0
• −EINVAL – if arguments are invalid
• −ENODATA – if not found
• −EBADMSG – if found value has invalid size

```c
int bt_audio_codec_cfg_meta_set_audio_active_state(struct bt_audio_codec_cfg *codec_cfg, enum bt_audio_active_state state)
```

Set the audio active state of a codec configuration metadata.

**Parameters**
- `codec_cfg` – The codec configuration to set data for.
- `state` – The audio active state to set.

**Return values**
- The – data_len of `codec_cfg` on success
- −EINVAL – if arguments are invalid
- −ENOMEM – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_meta_get_bcast_audio_immediate_rend_flag(const struct bt_audio_codec_cfg *codec_cfg)
```

Extract broadcast audio immediate rendering flag.

See [BT_AUDIO_METADATA_TYPE_BROADCAST_IMMEDIATE](#) for more information about this value.

**Parameters**
- `codec_cfg` – The codec data to search in.

**Return values**
- 0 – if the flag was found
- −EINVAL – if arguments are invalid
- −ENODATA – if not the flag was not found

```c
int bt_audio_codec_cfg_meta_set_bcast_audio_immediate_rend_flag(struct bt_audio_codec_cfg *codec_cfg)
```

Set the broadcast audio immediate rendering flag of a codec configuration metadata.

**Parameters**
- `codec_cfg` – The codec configuration to set data for.

**Return values**
- The – data_len of `codec_cfg` on success
- −EINVAL – if arguments are invalid
- −ENOMEM – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_meta_get_extended(const struct bt_audio_codec_cfg *codec_cfg, const uint8_t **extended_meta)
```

Extract extended metadata.

See [BT_AUDIO_METADATA_TYPE_EXTENDED](#) for more information about this value.

**Parameters**
- extended_meta – [out] Pointer to the extended metadata.

Return values
- The – length of the ccid_list (may be 0)
- EINVAL – if arguments are invalid
- ENODATA – if not found

```c
int bt_audio_codec_cfg_meta_set_extended(struct bt_audio_codec_cfg *codec_cfg, const uint8_t *extended_meta, size_t extended_meta_len)
```

Set the extended metadata of a codec configuration metadata.

Parameters
- codec_cfg – The codec configuration to set data for.
- extended_meta – The extended metadata to set.
- extended_meta_len – The length of extended_meta.

Return values
- The – data_len of codec_cfg on success
- EINVAL – if arguments are invalid
- ENOMEM – if the new value could not set or added due to memory

```c
int bt_audio_codec_cfg_meta_get_vendor(const struct bt_audio_codec_cfg *codec_cfg, const uint8_t **vendor_meta)
```

Extract vendor specific metadata.

See `BT_AUDIO_METADATA_TYPE_VENDOR` for more information about this value.

Parameters
- vendor_meta – [out] Pointer to the vendor specific metadata.

Return values
- The – length of the ccid_list (may be 0)
- EINVAL – if arguments are invalid
- ENODATA – if not found

```c
int bt_audio_codec_cfg_meta_set_vendor(struct bt_audio_codec_cfg *codec_cfg, const uint8_t *vendor_meta, size_t vendor_meta_len)
```

Set the vendor specific metadata of a codec configuration metadata.

Parameters
- codec_cfg – The codec configuration to set data for.
- vendor_meta – The vendor specific metadata to set.
- vendor_meta_len – The length of vendor_meta.

Return values
- The – data_len of codec_cfg on success
- EINVAL – if arguments are invalid
- ENOMEM – if the new value could not set or added due to memory
Basic Audio Profile

API Reference

Related code samples

Bluetooth: Broadcast Audio Assistant
Use LE Audio Broadcast Assistant functionality

typedef bool (*bt_bap_scan_delegator_state_func_t)(const struct bt_bap_scan_delegator_recv_state *recv_state, void *user_data)

Callback function for Scan Delegator receive state search functions.

Param recv_state
The receive state.

Param user_data
User data.

Retval true
to stop iterating. If this is used in the context of
bt_bap_scan_delegator_find_state(), the recv_state will be returned by
bt_bap_scan_delegator_find_state() whose user data is the parameter.

Retval false
to continue iterating

typedef void (*bt_bap_broadcast_assistant_write_cb)(struct bt_conn *conn, int err)

Callback function for writes.

Param conn
The connection to the peer device.
**Param err**  
Error value. 0 on success, GATT error on fail.

** Enums **

```c
enum bt_bap_pa_state
    Periodic advertising state reported by the Scan Delegator.
    Values:

    enumerator BT_BAP_PA_STATE_NOT_SYNCED = 0x00
        The periodic advertising has not been synchronized.

    enumerator BT_BAP_PA_STATE_INFO_REQ = 0x01
        Waiting for SyncInfo from Broadcast Assistant.

    enumerator BT_BAP_PA_STATE_SYNCED = 0x02
        Synchronized to periodic advertising.

    enumerator BT_BAP_PA_STATE_FAILED = 0x03
        Failed to synchronized to periodic advertising.

    enumerator BT_BAP_PA_STATE_NO_PAST = 0x04
        No periodic advertising sync transfer receiver from Broadcast Assistant.
```

```c
enum bt_bap_big_enc_state
    Broadcast Isochronous Group encryption state reported by the Scan Delegator.
    Values:

    enumerator BT_BAP_BIG_ENC_STATE_NO_ENC = 0x00
        The Broadcast Isochronous Group not encrypted.

    enumerator BT_BAP_BIG_ENC_STATE_BCODE_REQ = 0x01
        The Broadcast Isochronous Group broadcast code requested.

    enumerator BT_BAP_BIG_ENC_STATE_DEC = 0x02
        The Broadcast Isochronous Group decrypted.

    enumerator BT_BAP_BIG_ENC_STATE_BAD_CODE = 0x03
        The Broadcast Isochronous Group bad broadcast code.
```

```c
enum bt_bap_bass_att_err
    Broadcast Audio Scan Service (BASS) specific ATT error codes.
    Values:

    enumerator BT_BAP_BASS_ERR_OPCODE_NOT_SUPPORTED = 0x80
        Opcode not supported.
```
enumerator BT_BAP_BASS_ERR_INVALID_SRC_ID = 0x81
    Invalid source ID supplied.

enum bt_bap_ep_state
    Endpoint states.
    Values:
    enumerator BT_BAP_EP_STATE_IDLE = 0x00
        Audio Stream Endpoint Idle state.
    enumerator BT_BAP_EP_STATE_CODEC_CONFIGURED = 0x01
        Audio Stream Endpoint Codec Configured state.
    enumerator BT_BAP_EP_STATE_QOS_CONFIGURED = 0x02
        Audio Stream Endpoint QoS Configured state.
    enumerator BT_BAP_EP_STATE_ENABLING = 0x03
        Audio Stream Endpoint Enabling state.
    enumerator BT_BAP_EP_STATE_STREAMING = 0x04
        Audio Stream Endpoint Streaming state.
    enumerator BT_BAP_EP_STATE_DISABLING = 0x05
        Audio Stream Endpoint Disabling state.
    enumerator BT_BAP_EP_STATE_RELEASING = 0x06
        Audio Stream Endpoint Streaming state.

denum bt_bap_ascs_rsp_code
    Response Status Code.
    These are sent by the server to the client when a stream operation is requested.
    Values:
    enumerator BT_BAP_ASCS_RSP_CODE_SUCCESS = 0x00
        Server completed operation successfully.
    enumerator BT_BAP_ASCS_RSP_CODE_NOT_SUPPORTED = 0x01
        Server did not support operation by client.
    enumerator BT_BAP_ASCS_RSP_CODE_INVALID_LENGTH = 0x02
        Server rejected due to invalid operation length.
    enumerator BT_BAP_ASCS_RSP_CODE_INVALID_ASE = 0x03
        Invalid ASE ID.
    enumerator BT_BAP_ASCS_RSP_CODE_INVALID_ASE_STATE = 0x04
        Invalid ASE state.
enumerator BT_BAP_ASCS_RSP_CODE_INVALID_DIR = 0x05
   Invalid operation for direction.

enumerator BT_BAP_ASCS_RSP_CODE_CAP_UNSUPPORTED = 0x06
   Capabilities not supported by server.

enumerator BT_BAP_ASCS_RSP_CODE_CONF_UNSUPPORTED = 0x07
   Configuration parameters not supported by server.

enumerator BT_BAP_ASCS_RSP_CODE_CONF_REJECTED = 0x08
   Configuration parameters rejected by server.

enumerator BT_BAP_ASCS_RSP_CODE_CONF_INVALID = 0x09
   Invalid Configuration parameters.

enumerator BT_BAP_ASCS_RSP_CODE_METADATA_UNSUPPORTED = 0x0a
   Unsupported metadata.

enumerator BT_BAP_ASCS_RSP_CODE_METADATA_REJECTED = 0x0b
   Metadata rejected by server.

enumerator BT_BAP_ASCS_RSP_CODE_METADATA_INVALID = 0x0c
   Invalid metadata.

enumerator BT_BAP_ASCS_RSP_CODE_NO_MEM = 0x0d
   Server has insufficient resources.

enumerator BT_BAP_ASCS_RSP_CODE_UNSPECIFIED = 0x0e
   Unspecified error.

enum bt_bap_ascs_reason
Response Reasons.
These are used if the bt_bap_ascs_rsp_code value is
BT_BAP_ASCS_RSP_CODE_CONF_UNSUPPORTED, BT_BAP_ASCS_RSP_CODE_CONF_REJECTED
or BT_BAP_ASCS_RSP_CODE_CONF_INVALID.
Values:

enumerator BT_BAP_ASCS_REASON_NONE = 0x00
   No reason.

enumerator BT_BAP_ASCS_REASON_CODEC = 0x01
   Codec ID.

enumerator BT_BAP_ASCS_REASON_CODEC_DATA = 0x02
   Codec configuration.

enumerator BT_BAP_ASCS_REASON_INTERVAL = 0x03
   SDU interval.
enumerator BT_BAP_ASCS_REASON_FRAMING = 0x04
    Framing.
enumerator BT_BAP_ASCS_REASON_PHY = 0x05
    PHY.
enumerator BT_BAP_ASCS_REASON_SDU = 0x06
    Maximum SDU size.
enumerator BT_BAP_ASCS_REASON_RTN = 0x07
    RTN.
enumerator BT_BAP_ASCS_REASON_LATENCY = 0x08
    Max transport latency.
enumerator BT_BAP_ASCS_REASON_PD = 0x09
    Presentation delay.
enumerator BT_BAP_ASCS_REASON_CIS = 0x0a
    Invalid CIS mapping.

Functions

int bt_bap_ep_get_info(const struct bt_bap_ep *ep, struct bt_bap_ep_info *info)
Return structure holding information of audio stream endpoint.
Parameters
• ep – The audio stream endpoint object.
• info – The structure object to be filled with the info.
Returns
0 in case of success or negative value in case of error.

void bt_bap_stream_cb_register(struct bt_bap_stream *stream, struct bt_bap_stream_ops *ops)
Register Audio callbacks for a stream.
Parameters
• stream – Stream object.
• ops – Stream operations structure.

int bt_bap_stream_config(struct bt_conn *conn, struct bt_bap_stream *stream, struct bt_bap_ep *ep, struct bt_audio_codec_cfg *codec_cfg)
Configure Audio Stream.
This procedure is used by a client to configure a new stream using the remote endpoint, local capability and codec configuration.
Parameters
• conn – Connection object
• stream – Stream object being configured
• **ep** – Remote Audio Endpoint being configured
• **codec_cfg** – Codec configuration

**Returns**
Allocated Audio Stream object or NULL in case of error.

```
int bt_bap_stream_reconfig(struct bt_bap_stream *stream, struct bt_audio_codec_cfg *codec_cfg)
```

Reconfigure Audio Stream.
This procedure is used by a unicast client or unicast server to reconfigure a stream to use a different local codec configuration.
This can only be done for unicast streams.

**Parameters**
• **stream** – Stream object being reconfigured
• **codec_cfg** – Codec configuration

**Returns**
0 in case of success or negative value in case of error.

```
int bt_bap_stream_qos(struct bt_conn *conn, struct bt_bap_unicast_group *group)
```

Configure Audio Stream QoS.
This procedure is used by a client to configure the Quality of Service of streams in a unicast group. All streams in the group for the specified **conn** will have the Quality of Service configured. This shall only be used to configure unicast streams.

**Parameters**
• **conn** – Connection object
• **group** – Unicast group object

**Returns**
0 in case of success or negative value in case of error.

```
int bt_bap_stream_enable(struct bt_bap_stream *stream, const uint8_t meta[], size_t meta_len)
```

Enable Audio Stream.
This procedure is used by a client to enable a stream.
This shall only be called for unicast streams, as broadcast streams will always be enabled once created.

**Parameters**
• **stream** – Stream object
• **meta** – Metadata
• **meta_len** – Metadata length

**Returns**
0 in case of success or negative value in case of error.

```
int bt_bap_stream_metadata(struct bt_bap_stream *stream, const uint8_t meta[], size_t meta_len)
```

Change Audio Stream Metadata.
This procedure is used by a unicast client or unicast server to change the metadata of a stream.

**Parameters**
• **stream** – Stream object
• **meta** – Metadata
• **meta_len** – Metadata length

**Returns**
0 in case of success or negative value in case of error.

```c
int bt_bap_stream_disable(struct bt_bap_stream *stream)
```
Disable Audio Stream.

This procedure is used by a unicast client or unicast server to disable a stream. This shall only be called for unicast streams, as broadcast streams will always be enabled once created.

**Parameters**
• **stream** – Stream object

**Returns**
0 in case of success or negative value in case of error.

```c
int bt_bap_stream_start(struct bt_bap_stream *stream)
```
Start Audio Stream.

This procedure is used by a unicast client or unicast server to make a stream start streaming.

For the unicast client, this will connect the CIS for the stream before sending the start command.

For the unicast server, this will put a `BT_AUDIO_DIR_SINK` stream into the streaming state if the CIS is connected (initialized by the unicast client). If the CIS is not connected yet, the stream will go into the streaming state as soon as the CIS is connected. `BT_AUDIO_DIR_SOURCE` streams will go into the streaming state when the unicast client sends the Receiver Start Ready operation, which will trigger the `bt_bap_unicast_server_cb::start()` callback.

This shall only be called for unicast streams.

Broadcast sinks will always be started once synchronized, and broadcast source streams shall be started with `bt_bap_broadcast_source_start()`.

**Parameters**
• **stream** – Stream object

**Returns**
0 in case of success or negative value in case of error.

```c
int bt_bap_stream_stop(struct bt_bap_stream *stream)
```
Stop Audio Stream.

This procedure is used by a client to make a stream stop streaming.

This shall only be called for unicast streams. Broadcast sinks cannot be stopped. Broadcast sources shall be stopped with `bt_bap_broadcast_source_stop()`.

**Parameters**
• **stream** – Stream object

**Returns**
0 in case of success or negative value in case of error.
int bt_bap_stream_release(struct bt_bap_stream *stream)
    Release Audio Stream.

This procedure is used by a unicast client or unicast server to release a unicast stream.

Broadcast sink streams cannot be released, but can be deleted by
bt_bap_broadcast_sink_delete(). Broadcast source streams cannot be released,
but can be deleted by bt_bap_broadcast_source_delete().

Parameters
- **stream** – Stream object

Returns
0 in case of success or negative value in case of error.

int bt_bap_stream_send(struct bt_bap_stream *stream, struct net_buf *buf, uint16_t seq_num)
Send data to Audio stream without timestamp.
Send data from buffer to the stream.

**Note:** Support for sending must be supported, determined by CONFIG_BT_AUDIO_TX.

Parameters
- **stream** – Stream object.
- **buf** – Buffer containing data to be sent.
- **seq_num** – Packet Sequence number. This value shall be incremented for
each call to this function and at least once per SDU interval for a specific
channel.

Returns
Bytes sent in case of success or negative value in case of error.

int bt_bap_stream_send_ts(struct bt_bap_stream *stream, struct net_buf *buf, uint16_t seq_num, uint32_t ts)
Send data to Audio stream with timestamp.
Send data from buffer to the stream.

**Note:** Support for sending must be supported, determined by CONFIG_BT_AUDIO_TX.

Parameters
- **stream** – Stream object.
- **buf** – Buffer containing data to be sent.
- **seq_num** – Packet Sequence number. This value shall be incremented for
each call to this function and at least once per SDU interval for a specific
channel.
- **ts** – Timestamp of the SDU in microseconds (us). This value can be used
to transmit multiple SDUs in the same SDU interval in a CIG or BIG.

Returns
Bytes sent in case of success or negative value in case of error.
int bt_bap_stream_get_tx_sync(struct bt_bap_stream *stream, struct bt_iso_tx_info *info)
Get ISO transmission timing info for a Basic Audio Profile stream.

Reads timing information for transmitted ISO packet on an ISO channel. The HCI_LE_Read_ISO_TX_Sync HCI command is used to retrieve this information from the controller.

**Note:** An SDU must have already been successfully transmitted on the ISO channel for this function to return successfully. Support for sending must be supported, determined by CONFIG_BT_AUDIO_TX.

**Parameters**
- `info` – [out] Transmit info object.

**Return values**
- 0 – on success
- -EINVAL – if the stream is invalid, if the stream is not configured for sending or if it is not connected with a isochronous stream
- Any – return value from bt_iso_chan_get_tx_sync()

```c
void bt_bap_scan_delegator_register_cb(struct bt_bap_scan_delegator_cb *cb)
```
Register the callbacks for the Basic Audio Profile Scan Delegator.

**Parameters**
- `cb` – Pointer to the callback struct

```c
int bt_bap_scan_delegator_set_pa_state(uint8_t src_id, enum bt_bap_pa_state pa_state)
```
Set the periodic advertising sync state to syncing.

Set the periodic advertising sync state for a receive state to syncing, notifying Broadcast Assistants.

**Parameters**
- `src_id` – The source id used to identify the receive state.
- `pa_state` – The Periodic Advertising sync state to set. BT_BAP_PA_STATE_NOT_SYNCED and BT_BAP_PA_STATE_SYNCED is not necessary to provide, as they are handled internally.

**Returns**
- int Error value. 0 on success, errno on fail.

```c
int bt_bap_scan_delegator_set_bis_sync_state(uint8_t src_id, uint32_t
bis_synced[CONFIG_BT_BAP_BASS_MAX_SUBGROUPS])
```
Set the sync state of a receive state in the server.

**Parameters**
- `src_id` – The source id used to identify the receive state.
- `bis_synced` – Array of bitfields to set the BIS sync state for each subgroup.

**Returns**
- int Error value. 0 on success, ERRNO on fail.

6.1. Bluetooth
int bt_bap_scan_delegator_add_src(const struct bt_bap_scan_delegator_add_src_param *param)

Add a receive state source locally.
This will notify any connected clients about the new source. This allows them to modify and even remove it.
If CONFIG_BT_BAP_BROADCAST_SINK is enabled, any Broadcast Sink sources are autonomously added.

Parameters
- param – The parameters for adding the new source

Returns
int errno on failure, or source ID on success.

int bt_bap_scan_delegator_mod_src(const struct bt_bap_scan_delegator_mod_src_param *param)

Add a receive state source locally.
This will notify any connected clients about the new source. This allows them to modify and even remove it.
If CONFIG_BT_BAP_BROADCAST_SINK is enabled, any Broadcast Sink sources are autonomously modified.

Parameters
- param – The parameters for adding the new source

Returns
int errno on failure, or source ID on success.

int bt_bap_scan_delegator_rem_src(uint8_t src_id)

Remove a receive state source.
This will remove the receive state. If the receive state periodic advertising is synced, bt_bap_scan_delegator_cb.pa_sync_term_req() will be called.
If CONFIG_BT_BAP_BROADCAST_SINK is enabled, any Broadcast Sink sources are autonomously removed.

Parameters
- src_id – The source ID to remove

Returns
int Error value. 0 on success, errno on fail.

void bt_bap_scan_delegator_foreach_state(bt_bap_scan_delegator_state_func_t func, void *user_data)

Iterate through all existing receive states.

Parameters
- func – The callback function
- user_data – User specified data that sent to the callback function

const struct bt_bap_scan_delegator_recv_state *bt_bap_scan_delegator_find_state(bt_bap_scan_delegator_state_func_t func, void *user_data)

Find and return a receive state based on a compare function.

Parameters
- func – The compare callback function
• **user_data** – User specified data that sent to the callback function

**Returns**

The first receive state where the `func` returned true, or NULL

```c
int bt_bap_broadcast_assistant_discover(struct bt_conn *conn)
```

Discover Broadcast Audio Scan Service on the server.

**Warning:** Only one connection can be active at any time; discovering for a new connection, will delete all previous data.

**Parameters**

• `conn` – The connection

**Returns**

int Error value. 0 on success, GATT error or ERRNO on fail.

```c
int bt_bap_broadcast_assistant_scan_start(struct bt_conn *conn, bool start_scan)
```

Scan start for BISes for a remote server.

This will let the Broadcast Audio Scan Service server know that this device is actively scanning for broadcast sources. The function can optionally also start scanning, if the caller does not want to start scanning itself.

Scan results, if `start_scan` is true, is sent to the `bt_bap_broadcast_assistant_scan_cb` callback.

**Parameters**

• `conn` – Connection to the Broadcast Audio Scan Service server. Used to let the server know that we are scanning.

• `start_scan` – Start scanning if true. If false, the application should enable scan itself.

**Returns**

int Error value. 0 on success, GATT error or ERRNO on fail.

```c
int bt_bap_broadcast_assistant_scan_stop(struct bt_conn *conn)
```

Stop remote scanning for BISes for a server.

**Parameters**

• `conn` – Connection to the server.

**Returns**

int Error value. 0 on success, GATT error or ERRNO on fail.

```c
void bt_bap_broadcast_assistant_register_cb(struct bt_bap_broadcast_assistant_cb *cb)
```

Registers the callbacks used by Broadcast Audio Scan Service client.

```c
int bt_bap_broadcast_assistant_add_src(struct bt_conn *conn, const struct bt_bap_broadcast_assistant_add_src_param *param)
```

Add a source on the server.

**Parameters**

• `conn` – Connection to the server.

• `param` – Parameter struct.

**Returns**

Error value. 0 on success, GATT error or ERRNO on fail.
int bt_bap_broadcast_assistant_mod_src(struct bt_conn *conn, const struct bt_bap_broadcast_assistant_mod_src_param *param)

Modify a source on the server.

**Parameters**
- conn – Connection to the server.
- param – Parameter struct.

**Returns**
Error value. 0 on success, GATT error or ERRNO on fail.

int bt_bap_broadcast_assistant_set_broadcast_code(struct bt_conn *conn, uint8_t src_id, const uint8_t broadcast_code[BT_AUDIO_BROADCAST_CODE_SIZE])

Set a broadcast code to the specified receive state.

**Parameters**
- conn – Connection to the server.
- src_id – Source ID of the receive state.
- broadcast_code – The broadcast code.

**Returns**
Error value. 0 on success, GATT error or ERRNO on fail.

int bt_bap_broadcast_assistant_rem_src(struct bt_conn *conn, uint8_t src_id)

Remove a source from the server.

**Parameters**
- conn – Connection to the server.
- src_id – Source ID of the receive state.

**Returns**
Error value. 0 on success, GATT error or ERRNO on fail.

int bt_bap_broadcast_assistant_read_recv_state(struct bt_conn *conn, uint8_t idx)

Read the specified receive state from the server.

**Parameters**
- conn – Connection to the server.
- idx – The index of the receive start (0 up to the value from bt_bap_broadcast_assistant_discover_cb)

**Returns**
Error value. 0 on success, GATT error or ERRNO on fail.

struct bt_bap_ascs_rsp

#include <bap.h> Structure storing values of fields of ASE Control Point notification.

**Public Members**

enum bt_bap_ascs_rsp_code code

Value of the Response Code field.

The following response codes are accepted:
- **BT_BAP_ASCS_RSP_CODE_SUCCESS**
enum `bt_bap_ascs_reason` reason

Response reason.

If the Response Code is one of the following:
- `BT_BAP_ASCS_RSP_CODE_CAP_UNSUPPORTED`
- `BT_BAP_ASCS_RSP_CODE_CONF_REJECTED`
  all values from `bt_bap_ascs_reason` can be used.

If the Response Code is one of the following:
- `BT_BAP_ASCS_RSP_CODE_SUCCESS`
- `BT_BAP_ASCS_RSP_CODE_CAP_UNSUPPORTED`
- `BT_BAP_ASCS_RSP_CODE_NO_MEM`
- `BT_BAP_ASCS_RSP_CODE_UNSPECIFIED`
  only value `BT_BAP_ASCS_REASON_NONE` shall be used.

enum `bt_audio_metadata_type` metadata_type

Response metadata type.

If the Response Code is one of the following:
- `BT_BAP_ASCS_RSP_CODE_METADATA_UNSUPPORTED`
- `BT_BAP_ASCS_RSP_CODE_METADATA_REJECTED`
  the value of the Metadata Type shall be used.

union `bt_bap_ascs rsp`

Value of the Reason field.

The meaning of this value depend on the Response Code field.

struct `bt_bap_bass_subgroup`

`#include <bap.h>` Struct to hold subgroup specific information for the receive state.

**Public Members**

- `uint32_t bis_sync`
  BIS synced bitfield.

- `uint8_t metadata_len`
  Length of the metadata.

struct `bt_bap_scan_delegator_recv_state`

`#include <bap.h>` Represents the Broadcast Audio Scan Service receive state.

**Public Members**
uint8_t src_id
The source ID

bt_addr_le_t addr
The Bluetooth address.

uint8_t adv_sid
The advertising set ID.

enum bt_bap_pa_state pa_sync_state
The periodic advertising sync state.

enum bt_bap_big_enc_state encrypt_state
The broadcast isochronous group encryption state.

uint32_t broadcast_id
The 24-bit broadcast ID.

uint8_t bad_code[BT_AUDIO_BROADCAST_CODE_SIZE]
The bad broadcast code.
Only valid if encrypt_state is BT_BAP_BIG_ENC_STATE_BCODE_REQ

uint8_t num_subgroups
Number of subgroups.

struct bt_bap_bass_subgroup subgroups[CONFIG_BT_BAP_BASS_MAX_SUBGROUPS]
Subgroup specific information.

Public Members

void (*recv_state_updated)(struct bt_conn *conn, const struct
bt_bap_scan_delegator_recv_state *recv_state)
Receive state updated.

  Param conn
  Pointer to the connection to a remote device if the change was caused by
  it, otherwise NULL.

  Param recv_state
  Pointer to the receive state that was updated.

  Return
  0 in case of success or negative value in case of error.

int (*pa_sync_req)(struct bt_conn *conn, const struct
bt_bap_scan_delegator_recv_state *recv_state, bool past_avail, uint16_t pa_interval)
Periodic advertising sync request.
Request from peer device to synchronize with the periodic advertiser denoted by
the recv_state. To notify the Broadcast Assistant about any pending sync
Param conn
[in] Pointer to the connection requesting the periodic advertising sync.

Param recv_state
[in] Pointer to the receive state that is being requested for periodic advertising sync.

Param past_avail
[in] True if periodic advertising sync transfer is available.

Param pa_interval
[in] The periodic advertising interval.

Param past_sync
[ out] Set to true if syncing via periodic advertising sync transfer, false otherwise. If past_avail is false, this value is ignored.

Return
0 in case of accept, or other value to reject.

int (*pa_sync_term_req)(struct bt_conn *conn, const struct bt_bap_scan_delegator_recv_state *recv_state)
Periodic advertising sync termination request.

Request from peer device to terminate the periodic advertiser sync denoted by the recv_state.

Param conn
Pointer to the connection requesting the periodic advertising sync termination.

Param recv_state
Pointer to the receive state that is being requested for periodic advertising sync.

Return
0 in case of success or negative value in case of error.

void (*broadcast_code)(struct bt_conn *conn, const struct bt_bap_scan_delegator_recv_state *recv_state, const uint8_t broadcast_code[BT_AUDIO_BROADCAST_CODE_SIZE])
Broadcast code received.

Broadcast code received from a broadcast assistant

Param conn
Pointer to the connection providing the broadcast code.

Param recv_state
Pointer to the receive state the broadcast code is being provided for.

Param broadcast_code
The 16-octet broadcast code

int (*bis_sync_req)(struct bt_conn *conn, const struct bt_bap_scan_delegator_recv_state *recv_state, const uint32_t bis_sync_req[CONFIG_BT_BAP_BASS_MAX_SUBGROUPS])
Broadcast Isochronous Stream synchronize request.

Request from Broadcast Assistant device to modify the Broadcast Isochronous Stream states. The request shall be fulfilled with accordance to the bis_sync_req within reasonable time. The Broadcast Assistant may also request fewer, or none, indexes to be synchronized.

Param conn
[in] Pointer to the connection of the Broadcast Assistant requesting the sync.

Param recv_state
[in] Pointer to the receive state that is being requested for the sync.

Param bis_sync_req
Array of bitfields of which BIS indexes that is requested to sync for each subgroup by the Broadcast Assistant. A value of 0 indicates a request to terminate the BIG sync.

**Return**
0 in case of accept, or other value to reject.

```c
struct bt_bap_ep_info
#include <bap.h> Structure holding information of audio stream endpoint.
```

**Public Members**

```c
uint8_t id
The ID of the endpoint.
```

```c
enum bt_bap_ep_state state
The state of the endpoint.
```

```c
enum bt_audio_dir dir
Capabilities type.
```

```c
bool can_send
True if the stream associated with the endpoint is able to send data.
```

```c
struct bt_bap_ep *paired_ep
Pointer to paired endpoint if the endpoint is part of a bidirectional CIS, otherwise NULL.
```

```c
struct bt_bap_stream
#include <bap.h> Basic Audio Profile stream structure.
Streams represents a stream configuration of a Remote Endpoint and a Local Capability.
```

**Note:** Streams are unidirectional but can be paired with other streams to use a bidirectional connected isochronous stream.

**Public Members**

```c
struct bt_conn *conn
Connection reference.
```

```c
struct bt_bap_ep *ep
Endpoint reference.
```

```c
struct bt_audio_codec_cfg *codec_cfg
Codec Configuration.
```
struct bt_audio_codec_qos *qos
    QoS Configuration.

struct bt_bap_stream_ops *ops
    Audio stream operations.

void *group
    Unicast or Broadcast group - Used internally.

void *user_data
    Stream user data.

struct bt_bap_stream_ops
    #include <bap.h> Stream operation.

**Public Members**

void (*started)(struct bt_bap_stream *stream)
    Stream started callback.
    Started callback is called whenever an Audio Stream has been started and will be usable for streaming.
    **Param stream**
        Stream object that has been started.

void (*stopped)(struct bt_bap_stream *stream, uint8_t reason)
    Stream stopped callback.
    Stopped callback is called whenever an Audio Stream has been stopped.
    **Param stream**
        Stream object that has been stopped.
    **Param reason**
        BT_HCI_ERR_* reason for the disconnection.

void (*connected)(struct bt_bap_stream *stream)
    Isochronous channel connected callback.
    If this callback is provided it will be called whenever the isochronous channel for the stream has been connected. This does not mean that the stream is ready to be used, which is indicated by the bt_bap_stream_ops::started callback.
    If the stream shares an isochronous channel with another stream, then this callback may still be called, without the stream going into the started state.
    **Param stream**
        Stream object.

void (*disconnected)(struct bt_bap_stream *stream, uint8_t reason)
    Isochronous channel disconnected callback.
    If this callback is provided it will be called whenever the isochronous channel is disconnected, including when a connection gets rejected.
    If the stream shares an isochronous channel with another stream, then this callback may not be called, even if the stream is leaving the streaming state.


**Param stream**
Stream object.

**Param reason**
BT_HCI_ERR_* reason for the disconnection.

```c
struct bt_bap_scan_delelator_add_src_param
#include <bap.h>
```

**Public Members**

```c
struct bt_le_per_adv_sync *pa_sync
The periodic advertising sync.
```

```c
enum bt_bap_big_enc_state encrypt_state
The broadcast isochronous group encryption state.
```

```c
uint32_t broadcast_id
The 24-bit broadcast ID.
```

```c
uint8_t num_subgroups
Number of subgroups.
```

```c
struct bt_bap_bass_subgroup subgroups[CONFIG_BT_BAP_BASS_MAX_SUBGROUPS]
Subgroup specific information.
```

```c
struct bt_bap_scan_delelator_mod_src_param
#include <bap.h>
```

**Public Members**

```c
uint8_t src_id
The periodic advertising sync.
```

```c
enum bt_bap_big_enc_state encrypt_state
The broadcast isochronous group encryption state.
```

```c
uint32_t broadcast_id
The 24-bit broadcast ID.
```

```c
uint8_t num_subgroups
Number of subgroups.
```

```c
struct bt_bap_bass_subgroup subgroups[CONFIG_BT_BAP_BASS_MAX_SUBGROUPS]
Subgroup specific information.
```

If a subgroup's metadata_len is set to 0, the existing metadata for the subgroup will remain unchanged.

```c
struct bt_bap_broadcast_assistant_cb
#include <bap.h>
```
Public Members

void (*discover)(struct bt_conn *conn, int err, uint8_t recv_state_count)
Callback function for bt_bap_broadcast_assistant_discover.
   Param conn
       The connection that was used to discover Broadcast Audio Scan Service.
   Param err
       Error value. 0 on success, GATT error or ERRNO on fail.
   Param recv_state_count
       Number of receive states on the server.

void (*scan)(const struct bt_le_scan_recv_info *info, uint32_t broadcast_id)
Callback function for Broadcast Audio Scan Service client scan results.
Called when the scanner finds an advertiser that advertises the BT_UUID_BROADCAST_AUDIO UUID.
   Param info
       Advertiser information.
   Param broadcast_id
       24-bit broadcast ID.

void (*recv_state)(struct bt_conn *conn, int err, const struct bt_bap_scan_delegator_recv_state *state)
Callback function for when a receive state is read or updated.
Called whenever a receive state is read or updated.
   Param conn
       The connection to the Broadcast Audio Scan Service server.
   Param err
       Error value. 0 on success, GATT error on fail.
   Param state
       The receive state or NULL if the receive state is empty.

void (*recv_state_removed)(struct bt_conn *conn, int err, uint8_t src_id)
Callback function for when a receive state is removed.
   Param conn
       The connection to the Broadcast Audio Scan Service server.
   Param err
       Error value. 0 on success, GATT error on fail.
   Param src_id
       The receive state.

void (*scan_start)(struct bt_conn *conn, int err)
Callback function for bt_bap_broadcast_assistant_scan_start().
   Param conn
       The connection to the peer device.
   Param err
       Error value. 0 on success, GATT error on fail.

void (*scan_stop)(struct bt_conn *conn, int err)
Callback function for bt_bap_broadcast_assistant_scan_stop().
   Param conn
       The connection to the peer device.
   Param err
       Error value. 0 on success, GATT error on fail.
void (*add_src)(struct bt_conn *conn, int err)
  Callback function for \texttt{bt_bap_broadcast_assistant_add_src}().
  \textbf{Param conn}  
The connection to the peer device.
  \textbf{Param err}  
  Error value. 0 on success, GATT error on fail.

void (*mod_src)(struct bt_conn *conn, int err)
  Callback function for \texttt{bt_bap_broadcast_assistant_mod_src}().
  \textbf{Param conn}  
The connection to the peer device.
  \textbf{Param err}  
  Error value. 0 on success, GATT error on fail.

void (*broadcast_code)(struct bt_conn *conn, int err)
  Callback function for \texttt{bt_bap_broadcast_assistant_broadcast_code}().
  \textbf{Param conn}  
The connection to the peer device.
  \textbf{Param err}  
  Error value. 0 on success, GATT error on fail.

void (*rem_src)(struct bt_conn *conn, int err)
  Callback function for \texttt{bt_bap_broadcast_assistant_rem_src}().
  \textbf{Param conn}  
The connection to the peer device.
  \textbf{Param err}  
  Error value. 0 on success, GATT error on fail.

struct \texttt{bt_bap_broadcast_assistant_add_src_param}
  \#include <bap.h>  Parameters for adding a source to a Broadcast Audio Scan Service server.

\textbf{Public Members}

\texttt{bt_addr_le_t} \texttt{addr}  
Address of the advertiser.

\texttt{uint8_t} \texttt{adv_sid}  
SID of the advertising set.

\texttt{bool} \texttt{pa_sync}  
Whether to sync to periodic advertisements.

\texttt{uint32_t} \texttt{broadcast_id}  
24-bit broadcast ID

\texttt{uint16_t} \texttt{pa_interval}  
Periodic advertising interval in milliseconds.
  \texttt{BT\_BAP\_PA\_INTERVAL\_UNKNOWN} if unknown.
uint8_t num_subgroups
    Number of subgroups.

struct bt_bap_bass_subgroup *subgroups
    Pointer to array of subgroups.

struct bt_bap_broadcast_assistant_mod_src_param
    #include <bap.h> Parameters for modifying a source.

Public Members

uint8_t src_id
    Source ID of the receive state.

bool pa_sync
    Whether to sync to periodic advertisements.

uint16_t pa_interval
    Periodic advertising interval.
    BT_BAP_PA_INTERVAL_UNKNOWN if unknown.

uint8_t num_subgroups
    Number of subgroups.

struct bt_bap_bass_subgroup *subgroups
    Pointer to array of subgroups.

Functions

int bt_bap_unicast_group_create(struct bt_bap_unicast_group_param *param, struct bt_bap_unicast_group **unicast_group)

Create audio unicast group.
Create a new audio unicast group with one or more audio streams as a unicast client. Streams in a unicast group shall share the same interval, framing and latency (see bt_audio_codec_qos).

Parameters
    • param – [in] The unicast group create parameters.
    • unicast_group – [out] Pointer to the unicast group created.

Returns
    Zero on success or (negative) error code otherwise.

int bt_bap_unicast_group_add_streams(struct bt_bap_unicast_group *unicast_group, struct bt_bap_unicast_group_stream_pair_param params[], size_t num_param)
Add streams to a unicast group as a unicast client.

This function can be used to add additional streams to a bt_bap_unicast_group.

This can be called at any time before any of the streams in the group has been started (see `bt_bap_stream_ops.started()`). This can also be called after the streams have been stopped (see `bt_bap_stream_ops.stopped()`).

Once a stream has been added to a unicast group, it cannot be removed. To remove a stream from a group, the group must be deleted with `bt_bap_unicast_group_delete()`, but this will require all streams in the group to be released first.

### Parameters

- **unicast_group** – Pointer to the unicast group
- **params** – Array of stream parameters with streams being added to the group.
- **num_param** – Number of parameters in `params`.

### Returns

0 in case of success or negative value in case of error.

```c
int bt_bap_unicast_group_delete(struct bt_bap_unicast_group *unicast_group)
```

Delete audio unicast group.

Delete a audio unicast group as a client. All streams in the group shall be in the idle or configured state.

### Parameters

- **unicast_group** – Pointer to the unicast group to delete

### Returns

Zero on success or (negative) error code otherwise.

```c
int bt_bap_unicast_client_register_cb(const struct bt_bap_unicast_client_cb *cb)
```

Register unicast client callbacks.

Only one callback structure can be registered, and attempting to registering more than one will result in an error.

### Parameters

- **cb** – Unicast client callback structure.

### Returns

0 in case of success or negative value in case of error.

```c
int bt_bap_unicast_client_discover(struct bt_conn *conn, enum bt_audio_dir dir)
```

Discover remote capabilities and endpoints.

This procedure is used by a client to discover remote capabilities and endpoints and notifies via params callback.

### Parameters

- **conn** – Connection object
- **dir** – The type of remote endpoints and capabilities to discover.
Public Members

struct bt_bap_stream *stream
Pointer to a stream object.

struct bt_audio_codec_qos *qos
The QoS settings for the stream object.

struct bt_bap_unicast_group_stream_pair_param
#include <bap.h> Parameter struct for the unicast group functions.
Parameter struct for the bt_bap_unicast_group_create() and bt_bap_unicast_group_add_streams() functions.

Public Members

struct bt_bap_unicast_group_stream_param *rx_param
Pointer to a receiving stream parameters.

struct bt_bap_unicast_group_stream_param *tx_param
Pointer to a transmitting stream parameters.

struct bt_bap_unicast_group_param
#include <bap.h>

Public Members

size_t params_count
The number of parameters in params.

struct bt_bap_unicast_group_stream_pair_param *params
Array of stream parameters.

uint8_t packing
Unicast Group packing mode.
BT_ISO_PACKING_SEQUENTIAL or BT_ISO_PACKING_INTERLEAVED.

Note: This is a recommendation to the controller, which the controller may ignore.

struct bt_bap_unicast_client_cb
#include <bap.h> Unicast Client callback structure.

Public Members
void (*location)(struct bt_conn *conn, enum bt_audio_dir dir, enum bt_audio_location loc)

Remote Unicast Server Audio Locations.

This callback is called whenever the audio locations is read from the server or otherwise notified to the client.

**Param conn**
Connection to the remote unicast server.

**Param dir**
Direction of the location.

**Param loc**
The location bitfield value.

**Return**
0 in case of success or negative value in case of error.

void (*available_contexts)(struct bt_conn *conn, enum bt_audio_context snk_ctx, enum bt_audio_context src_ctx)

Remote Unicast Server Available Contexts.

This callback is called whenever the available contexts are read from the server or otherwise notified to the client.

**Param conn**
Connection to the remote unicast server.

**Param snk_ctx**
The sink context bitfield value.

**Param src_ctx**
The source context bitfield value.

**Return**
0 in case of success or negative value in case of error.

void (*config)(struct bt_bap_stream *stream, enum bt_bap_ascs_rsp_code rsp_code, enum bt_bap_ascs_reason reason)

Callback function for `bt_bap_stream_config()` and `bt_bap_stream_reconfig()`.

Called when the codec configure operation is completed on the server.

**Param stream**
Stream the operation was performed on.

**Param rsp_code**
Response code.

**Param reason**
Reason code.

void (*qos)(struct bt_bap_stream *stream, enum bt_bap_ascs_rsp_code rsp_code, enum bt_bap_ascs_reason reason)

Callback function for `bt_bap_stream_qos()`.

Called when the QoS configure operation is completed on the server. This will be called for each stream in the group that was being QoS configured.

**Param stream**
Stream the operation was performed on. May be NULL if there is no stream associated with the ASE ID sent by the server.

**Param rsp_code**
Response code.

**Param reason**
Reason code.

void (*enable)(struct bt_bap_stream *stream, enum bt_bap_ascs_rsp_code rsp_code, enum bt_bap_ascs_reason reason)
Callback function for `bt_bap_stream_enable()`.

Called when the enable operation is completed on the server.

- **Param stream**
  Stream the operation was performed on. May be NULL if there is no stream associated with the ASE ID sent by the server.

- **Param rsp_code**
  Response code.

- **Param reason**
  Reason code.

```c
void (*start)(struct bt_bap_stream *stream, enum bt_bap_ascs_rsp_code rsp_code, enum bt_bap_ascs_reason reason)
```

Callback function for `bt_bap_stream_start()`.

Called when the start operation is completed on the server. This will only be called if the stream supplied to `bt_bap_stream_start()` is for a `BT_AUDIO_DIR_SOURCE` endpoint.

- **Param stream**
  Stream the operation was performed on. May be NULL if there is no stream associated with the ASE ID sent by the server.

- **Param rsp_code**
  Response code.

- **Param reason**
  Reason code.

```c
void (*stop)(struct bt_bap_stream *stream, enum bt_bap_ascs_rsp_code rsp_code, enum bt_bap_ascs_reason reason)
```

Callback function for `bt_bap_stream_stop()`.

Called when the stop operation is completed on the server. This will only be called if the stream supplied to `bt_bap_stream_stop()` is for a `BT_AUDIO_DIR_SOURCE` endpoint.

- **Param stream**
  Stream the operation was performed on. May be NULL if there is no stream associated with the ASE ID sent by the server.

- **Param rsp_code**
  Response code.

- **Param reason**
  Reason code.

```c
void (*disable)(struct bt_bap_stream *stream, enum bt_bap_ascs_rsp_code rsp_code, enum bt_bap_ascs_reason reason)
```

Callback function for `bt_bap_stream_disable()`.

Called when the disable operation is completed on the server.

- **Param stream**
  Stream the operation was performed on. May be NULL if there is no stream associated with the ASE ID sent by the server.

- **Param rsp_code**
  Response code.

- **Param reason**
  Reason code.

```c
void (*metadata)(struct bt_bap_stream *stream, enum bt_bap_ascs_rsp_code rsp_code, enum bt_bap_ascs_reason reason)
```

Callback function for `bt_bap_stream_metadata()`.
Called when the metadata operation is completed on the server.

**Param stream**
Stream the operation was performed on. May be NULL if there is no stream associated with the ASE ID sent by the server.

**Param rsp_code**
Response code.

**Param reason**
Reason code.

```c
void (*release)(struct bt_bap_stream *stream, enum bt_bap_ascs_rsp_code rsp_code,
               enum bt_bap_ascs_reason reason)
```

Callback function for `bt_bap_stream_release()`.

Called when the release operation is completed on the server.

**Param stream**
Stream the operation was performed on. May be NULL if there is no stream associated with the ASE ID sent by the server.

**Param rsp_code**
Response code.

**Param reason**
Reason code.

```c
void (*pac_record)(struct bt_conn *conn, enum bt_audio_dir dir, const struct bt_audio_codec_cap *codec_cap)
```

Remote Published Audio Capability (PAC) record discovered.

Called when a PAC record has been discovered as part of the discovery procedure.

The codec is only valid while in the callback, so the values must be stored by the receiver if future use is wanted.

If discovery procedure has complete both codec and ep are set to NULL.

**Param conn**
Connection to the remote unicast server.

**Param dir**
The type of remote endpoints and capabilities discovered.

**Param codec_cap**
Remote capabilities.

```c
void (*endpoint)(struct bt_conn *conn, enum bt_audio_dir dir, struct bt_bap_ep *ep)
```

Remote Audio Stream Endoint (ASE) discovered.

Called when an ASE has been discovered as part of the discovery procedure.

If discovery procedure has complete both codec and ep are set to NULL.

**Param conn**
Connection to the remote unicast server.

**Param dir**
The type of remote endpoints and capabilities discovered.

**Param ep**
Remote endpoint.

```c
void (*discover)(struct bt_conn *conn, int err, enum bt_audio_dir dir)
```

BAP discovery callback function.

If discovery procedure has completed ep is set to NULL and `err` is 0.
If discovery procedure has complete both codec and ep are set to NULL.

**Param conn**
Connection to the remote unicast server.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param dir**
The type of remote endpoints and capabilities discovered.

```c
typedef void (*bt_bap_ep_func_t)(struct bt_bap_ep *ep, void *user_data)
```

The callback function called for each endpoint.

**Param ep**
The structure object with endpoint info.

**Param user_data**
Data to pass to the function.

### Functions

**int bt_bap_unicast_server_register_cb(const struct bt_bap_unicast_server_cb *cb)**

Register unicast server callbacks.

Only one callback structure can be registered, and attempting to registering more than one will result in an error.

**Parameters**

- **cb** – Unicast server callback structure.

**Returns**

0 in case of success or negative value in case of error.

**int bt_bap_unicast_server_unregister_cb(const struct bt_bap_unicast_server_cb *cb)**

Unregister unicast server callbacks.

May only unregister a callback structure that has previously been registered by `bt_bap_unicast_server_register_cb()`.

**Parameters**

- **cb** – Unicast server callback structure.

**Returns**

0 in case of success or negative value in case of error.

**void bt_bap_unicast_server_foreach_ep(struct bt_conn *conn, bt_bap_ep_func_t func, void *user_data)**

Iterate through all endpoints of the given connection.

**Parameters**

- **conn** – Connection object
- **func** – Function to call for each endpoint.
• user_data – Data to pass to the callback function.

```c
int bt_bap_unicast_server_config_ase(struct bt_conn *conn, struct bt_bap_stream *stream, struct bt_audio_codec_cfg *codec_cfg, const struct bt_audio_codec_qos_pref *qos_pref)
```

Initialize and configure a new ASE.

**Parameters**

- `conn` – Connection object
- `stream` – Configured stream object to be attached to the ASE
- `codec_cfg` – Codec configuration
- `qos_pref` – Audio Stream Quality of Service Preference

**Returns**

0 in case of success or negative value in case of error.

```c
struct bt_bap_unicast_server_cb
#include <bap.h> Unicast Server callback structure.
```

**Public Members**

```c
int (*config)(struct bt_conn *conn, const struct bt_bap_ep *ep, enum bt_audio_dir dir, const struct bt_audio_codec_cfg *codec_cfg, struct bt_bap_stream **stream, struct bt_audio_codec_qos_pref *pref, struct bt_bap_ascs_rsp *rsp)
```

Endpoint config request callback.

Config callback is called whenever an endpoint is requested to be configured

- **Param** `conn`  
  [in] Connection object.
- **Param** `ep`  
  [in] Local Audio Endpoint being configured.
- **Param** `dir`  
  [in] Direction of the endpoint.
- **Param** `codec_cfg`  
  [in] Codec configuration.
- **Param** `stream`  
  [out] Pointer to stream that will be configured for the endpoint.
- **Param** `pref`  
  [out] Pointer to a QoS preference object that shall be populated with values. Invalid values will reject the codec configuration request.
- **Param** `rsp`  
  [out] Object for the ASE operation response. Only used if the return value is non-zero.

**Return**

0 in case of success or negative value in case of error.

```c
int (*reconfig)(struct bt_bap_stream *stream, enum bt_audio_dir dir, const struct bt_audio_codec_cfg *codec_cfg, struct bt_audio_codec_qos_pref *pref, struct bt_bap_ascs_rsp *rsp)
```

Stream reconfig request callback.

Reconfig callback is called whenever an Audio Stream needs to be reconfigured with different codec configuration.

- **Param** `stream`  
  [in] Stream object being reconfigured.
Param dir
[in] Direction of the endpoint.

Param codec_cfg
[in] Codec configuration.

Param pref
[out] Pointer to a QoS preference object that shall be populated with values. Invalid values will reject the codec configuration request.

Param rsp
[out] Object for the ASE operation response. Only used if the return value is non-zero.

Return
0 in case of success or negative value in case of error.

int (*qos)(struct bt_bap_stream *stream, const struct bt_audio_codec_qos *qos, struct bt_bap_ascs_rsp *rsp)
Stream QoS request callback.
QoS callback is called whenever an Audio Stream Quality of Service needs to be configured.

Param stream
[in] Stream object being reconfigured.

Param qos
[in] Quality of Service configuration.

Param rsp
[out] Object for the ASE operation response. Only used if the return value is non-zero.

Return
0 in case of success or negative value in case of error.

int (*enable)(struct bt_bap_stream *stream, const uint8_t meta[], size_t meta_len, struct bt_bap_ascs_rsp *rsp)
Stream Enable request callback.
Enable callback is called whenever an Audio Stream is requested to be enabled to stream.

Param stream
[in] Stream object being enabled.

Param meta

Param meta_len
[in] Length of metadata.

Param rsp
[out] Object for the ASE operation response. Only used if the return value is non-zero.

Return
0 in case of success or negative value in case of error.

int (*start)(struct bt_bap_stream *stream, struct bt_bap_ascs_rsp *rsp)
Stream Start request callback.
Start callback is called whenever an Audio Stream is requested to start streaming.

Param stream
[in] Stream object.

Param rsp
[out] Object for the ASE operation response. Only used if the return value is non-zero.

Return
0 in case of success or negative value in case of error.
int (*metadata)(struct *stream, const uint8_t *, size_t meta_len, struct *rsp)

Stream Metadata update request callback.

Metadata callback is called whenever an Audio Stream is requested to update its metadata.

Param stream
    [in] Stream object.

Param meta

Param meta_len
    [in] Length of metadata.

Param rsp
    [out] Object for the ASE operation response. Only used if the return value is non-zero.

Return
    0 in case of success or negative value in case of error.

int (*disable)(struct *stream, struct *rsp)

Stream Disable request callback.

Disable callback is called whenever an Audio Stream is requested to disable the stream.

Param stream
    [in] Stream object being disabled.

Param rsp
    [out] Object for the ASE operation response. Only used if the return value is non-zero.

Return
    0 in case of success or negative value in case of error.

int (*stop)(struct *stream, struct *rsp)

Stream Stop callback.

Stop callback is called whenever an Audio Stream is requested to stop streaming.

Param stream
    [in] Stream object.

Param rsp
    [out] Object for the ASE operation response. Only used if the return value is non-zero.

Return
    0 in case of success or negative value in case of error.

int (*release)(struct *stream, struct *rsp)

Stream release callback.

Release callback is called whenever a new Audio Stream needs to be released and thus deallocated.

Param stream
    [in] Stream object.

Param rsp
    [out] Object for the ASE operation response. Only used if the return value is non-zero.

Return
    0 in case of success or negative value in case of error.


group bt_bap_broadcast

Chapter 6. Connectivity
BAP Broadcast APIs.

**Functions**

```c
const struct bt_bap_base *bt_bap_base_get_base_from_ad(const struct bt_data *ad)
```
Generate a pointer to a BASE from periodic advertising data.

**Parameters**
- `ad` – The periodic advertising data

**Return values**
- `NULL` – if the data does not contain a BASE
- `Pointer` – to a bt_bap_base structure

```c
int bt_bap_base_get_pres_delay(const struct bt_bap_base *base)
```
Get the presentation delay value of a BASE.

**Parameters**
- `base` – The BASE pointer

**Return values**
- `-EINVAL` – if arguments are invalid
- `The` – 24-bit presentation delay value

```c
int bt_bap_base_get_subgroup_count(const struct bt_bap_base *base)
```
Get the subgroup count of a BASE.

**Parameters**
- `base` – The BASE pointer

**Return values**
- `-EINVAL` – if arguments are invalid
- `The` – 8-bit subgroup count value

```c
int bt_bap_base_get_bis_indexes(const struct bt_bap_base *base, uint32_t *bis_indexes)
```
Get all BIS indexes of a BASE.

**Parameters**
- `base` – [in] The BASE pointer
- `bis_indexes` – [out] 32-bit BIS index bitfield that will be populated

**Return values**
- `-EINVAL` – if arguments are invalid
- `0` – on success

```c
int bt_bap_base_foreach_subgroup(const struct bt_bap_base *base, bool (*func)(const struct bt_bap_base_subgroup *subgroup, void *user_data), void *user_data)
```
Iterate on all subgroups in the BASE.

**Parameters**
- `base` – The BASE pointer
- `func` – Callback function. Return true to continue iterating, or false to stop.
• **user_data** – Userdata supplied to `func`

**Return values**

- `EINVAL` – if arguments are invalid
- `ECANCELED` – if iterating over the subgroups stopped prematurely by `func`
- `0` – if all subgroups were iterated

```c
int bt_bap_base_get_subgroup_codec_id(const struct bt_bap_base_subgroup *subgroup,
       struct bt_bap_base_codec_id *codec_id)
```

Get the codec ID of a subgroup.

**Parameters**

- `subgroup` – **[in]** The subgroup pointer
- `codec_id` – **[out]** Pointer to the struct where the results are placed

**Return values**

- `EINVAL` – if arguments are invalid
- `0` – on success

```c
int bt_bap_base_get_subgroup_codec_data(const struct bt_bap_base_subgroup
       *subgroup, uint8_t **data)
```

Get the codec configuration data of a subgroup.

**Parameters**

- `subgroup` – **[in]** The subgroup pointer
- `data` – **[out]** Pointer that will point to the resulting codec configuration data

**Return values**

- `EINVAL` – if arguments are invalid
- `0` – on success

```c
int bt_bap_base_get_subgroup_codec_meta(const struct bt_bap_base_subgroup
       *subgroup, uint8_t **meta)
```

Get the codec metadata of a subgroup.

**Parameters**

- `subgroup` – **[in]** The subgroup pointer
- `meta` – **[out]** Pointer that will point to the resulting codec metadata

**Return values**

- `EINVAL` – if arguments are invalid
- `0` – on success

```c
int bt_bap_base_subgroup_codec_to_codec_cfg(const struct bt_bap_base_subgroup
       *subgroup, struct bt_audio_codec_cfg
       *codec_cfg)
```

Store subgroup codec data in a *Codec config parsing APIs*.

**Parameters**

- `subgroup` – **[in]** The subgroup pointer
- `codec_cfg` – **[out]** Pointer to the struct where the results are placed

**Return values**
-EINVAL – if arguments are invalid
-ENOMEM – if the codec_cfg cannot store the subgroup codec data
0 – on success

int bt_bap_base_get_subgroup_bis_count(const struct bt_bap_base_subgroup *subgroup)

Get the BIS count of a subgroup.

**Parameters**
- subgroup – The subgroup pointer

**Return values**
-EINVAL – if arguments are invalid
The – 8-bit BIS count value

int bt_bap_base_subgroup_foreach_bis(const struct bt_bap_base_subgroup *subgroup, bool (*func)(const struct bt_bap_base_subgroup_bis *bis, void *user_data), void *user_data)

Iterate on all BIS in the subgroup.

**Parameters**
- subgroup – The subgroup pointer
- func – Callback function. Return true to continue iterating, or false to stop.
- user_data – Userdata supplied to func

**Return values**
-EINVAL – if arguments are invalid
-ECANCELED – if iterating over the subgroups stopped prematurely by func
0 – if all BIS were iterated

int bt_bap_base_subgroup_bis_codec_to_codec_cfg(const struct bt_bap_base_subgroup_bis *bis, struct bt_audio_codec_cfg *codec_cfg)

Store BIS codec configuration data in a Codec config parsing APIs.

This only sets the Codec config parsing APIs data and Codec config parsing APIs data_len, but is useful to use the BIS codec configuration data with the bt_audio_codec_cfg_* functions.

**Parameters**
- bis – [in] The BIS pointer
- codec_cfg – [out] Pointer to the struct where the results are placed

**Return values**
-EINVAL – if arguments are invalid
-ENOMEM – if the codec_cfg cannot store the subgroup codec data
0 – on success

#include <bap.h> Codec ID structure for a Broadcast Audio Source Endpoint (BASE)
Public Members

uint8_t id
    Codec ID.

uint16_t cid
    Codec Company ID.

uint16_t vid
    Codec Company Vendor ID.

struct bt_bap_base_subgroup_bis
    #include <bap.h> BIS structure for each BIS in a Broadcast Audio Source Endpoint (BASE) subgroup.

Public Members

uint8_t data_len
    Codec Specific Data length.

uint8_t *data
    Codec Specific Data.

group bt_bap_broadcast_sink
    BAP Broadcast Sink APIs.

Functions

int bt_bap_broadcast_sink_register_cb(struct bt_bap_broadcast_sink_cb *cb)
    Register Broadcast sink callbacks *.

    Parameters
    • cb – Broadcast sink callback structure.

int bt_bap_broadcast_sink_create(struct bt_le_per_adv_sync *pa_sync, uint32_t broadcast_id, struct bt_bap_broadcast_sink **sink)
    Create a Broadcast Sink from a periodic advertising sync.

    This should only be done after verifying that the periodic advertising sync is from a Broadcast Source.

    The created Broadcast Sink will need to be supplied to bt_bap_broadcast_sink_sync() in order to synchronize to the broadcast audio.

    bt_bap_broadcast_sink_cb.pa_synced() will be called with the Broadcast Sink object created if this is successful.

    Parameters
    • pa_sync – Pointer to the periodic advertising sync object.
    • broadcast_id – 24-bit broadcast ID.
    • sink – [out] Pointer to the Broadcast Sink created.
Returns

0 in case of success or_errno value in case of error.

```c
int bt_bap_broadcast_sink_sync(struct bt_bap_broadcast_sink *sink, uint32_t indexes_bitfield, struct bt_bap_stream *streams[], const uint8_t broadcast_code[16])
```

Sync to a broadcaster’s audio.

**Example:** The string “Broadcast Code” shall be `[42 72 6F 61 64 63 61 73 74 20 43 6F 64 65 00 00]`

**Parameters**

- `sink` – Pointer to the sink object from the base_recv callback.
- `indexes_bitfield` – Bitfield of the BIS index to sync to. To sync to e.g. BIS index 1 and 2, this should have the value of `BIT(1) | BIT(2)`. 
- `streams` – Stream object pointers to be used for the receiver. If multiple BIS indexes shall be synchronized, multiple streams shall be provided.
- `broadcast_code` – The 16-octet broadcast code. Shall be supplied if the broadcast is encrypted (see `bt_bap_broadcast_sink_cb::syncable`). If the value is a string or a the value is less than 16 octets, the remaining octets shall be 0.

**Returns**

0 in case of success or negative value in case of error.

```c
int bt_bap_broadcast_sink_stop(struct bt_bap_broadcast_sink *sink)
```

Stop an audio broadcast sink. The broadcast sink will stop receiving BIGInfo, and audio data can no longer be streamed.

**Parameters**

- `sink` – Pointer to the broadcast sink

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_bap_broadcast_sink_delete(struct bt_bap_broadcast_sink *sink)
```

Release a broadcast sink.

Once a broadcast sink has been allocated after the pa_synced callback, it can be deleted using this function. If the sink has synchronized to any broadcast audio streams, these must first be stopped using `bt_bap_stream_stop`.

**Parameters**

- `sink` – Pointer to the sink object to delete.

**Returns**

0 in case of success or negative value in case of error.

```c
struct bt_bap_broadcast_sink_cb
#include <bap.h> Broadcast Audio Sink callback structure.
```

**Public Members**
void (*base_recv)(struct bt_bap_broadcast_sink *sink, const struct bt_bap_base *base, size_t base_size)

Broadcast Audio Source Endpoint (BASE) received.

Callback for when we receive a BASE from a broadcaster after syncing to the broadcaster's periodic advertising.

**Param sink**
Pointer to the sink structure.

**Param base**
Broadcast Audio Source Endpoint (BASE).

**Param base_size**
Size of the base

void (*syncable)(struct bt_bap_broadcast_sink *sink, bool encrypted)

Broadcast sink is syncable.

Called whenever a broadcast sink is not synchronized to audio, but the audio is synchronizable. This is inferred when a BIGInfo report is received.

Once this callback has been called, it is possible to call `bt_bap_broadcast_sink_sync()` to synchronize to the audio stream(s).

**Param sink**
Pointer to the sink structure.

**Param encrypted**
Whether or not the broadcast is encrypted

### Functions

**int bt_bap_broadcast_source_create**(struct bt_bap_broadcast_source_param *param, struct bt_bap_broadcast_source **source)**

Create audio broadcast source.

Create a new audio broadcast source with one or more audio streams.

The broadcast source will be visible for scanners once this has been called, and the device will advertise audio announcements.

No audio data can be sent until `bt_bap_broadcast_source_start()` has been called and no audio information (BIGInfo) will be visible to scanners (see `bt_le_per_adv_sync_cb`).

**Parameters**

- **param** – [in] Pointer to parameters used to create the broadcast source.
- **source** – [out] Pointer to the broadcast source created

**Returns**

Zero on success or (negative) error code otherwise.

**int bt_bap_broadcast_source_reconfig**(struct bt_bap_broadcast_source *source, struct bt_bap_broadcast_source_param *param)**

Reconfigure audio broadcast source.

Reconfigure an audio broadcast source with a new codec and codec quality of service parameters. This can only be done when the source is stopped.
Since this may modify the Broadcast Audio Source Endpoint (BASE), `bt_bap_broadcast_source_get_base()` should be called after this to get the new BASE information.

If the `param.params_count` is smaller than the number of subgroups that have been created in the Broadcast Source, only the first `param.params_count` subgroups are updated. If a stream exist in a subgroup not part of `param`, then that stream is left as is (i.e. it is not removed; the only way to remove a stream from a Broadcast Source is to recreate the Broadcast Source).

**Parameters**

- `source` – Pointer to the broadcast source
- `param` – Pointer to parameters used to reconfigure the broadcast source.

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_bap_broadcast_source_update_metadata(struct bt_bap_broadcast_source *source, const uint8_t *meta[], size_t meta_len)
```

Modify the metadata of an audio broadcast source.

Modify the metadata an audio broadcast source. This can only be done when the source is started. To update the metadata in the stopped state, use `bt_bap_broadcast_source_reconfig()`.

**Parameters**

- `source` – Pointer to the broadcast source.
- `meta` – Metadata.
- `meta_len` – Length of metadata.

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_bap_broadcast_source_start(struct bt_bap_broadcast_source *source, struct bt_le_ext_adv *adv)
```

Start audio broadcast source.

Start an audio broadcast source with one or more audio streams. The broadcast source will start advertising BIGInfo, and audio data can be streamed.

**Parameters**

- `source` – Pointer to the broadcast source
- `adv` – Pointer to an extended advertising set with periodic advertising configured.

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_bap_broadcast_source_stop(struct bt_bap_broadcast_source *source)
```

Stop audio broadcast source.

Stop an audio broadcast source. The broadcast source will stop advertising BIGInfo, and audio data can no longer be streamed.

**Parameters**

- `source` – Pointer to the broadcast source

**Returns**

Zero on success or (negative) error code otherwise.
int bt_bap_broadcast_source_delete(struct bt_bap_broadcast_source *source)
Delete audio broadcast source.

Delete an audio broadcast source. The broadcast source will stop advertising entirely, and the source can no longer be used.

Parameters

• source – Pointer to the broadcast source

Returns

Zero on success or (negative) error code otherwise.

int bt_bap_broadcast_source_get_id(struct bt_bap_broadcast_source *source, uint32_t *const broadcast_id)

Get the broadcast ID of a broadcast source.

This will return the 3-octet broadcast ID that should be advertised in the extended advertising data with BT_UUID_BROADCAST_AUDIO_VAL as BT_DATA_SVC_DATA16. See table 3.14 in the Basic Audio Profile v1.0.1 for the structure.

Parameters

• source – [in] Pointer to the broadcast source.

• broadcast_id – [out] Pointer to the 3-octet broadcast ID.

Returns

Zero on success or (negative) error code otherwise.

int bt_bap_broadcast_source_get_base(struct bt_bap_broadcast_source *source, struct net_buf_simple *base_buf)

Get the Broadcast Audio Stream Endpoint of a broadcast source.

This will encode the BASE of a broadcast source into a buffer, that can be used for advertisement. The encoded BASE will thus be encoded as little-endian. The BASE shall be put into the periodic advertising data (see bt_le_per_adv_set_data()).

See table 3.15 in the Basic Audio Profile v1.0.1 for the structure.

Parameters

• source – Pointer to the broadcast source.

• base_buf – Pointer to a buffer where the BASE will be inserted.

Returns

Zero on success or (negative) error code otherwise.

struct bt_bap_broadcast_source_stream_param
#include <bap.h> Broadcast Source stream parameters.

Public Members

struct bt_bap_stream *stream
Audio stream.

struct bt_bap_broadcast_source_subgroup_param
#include <bap.h> Broadcast Source subgroup parameters.
Public Members

size_t params_count
   The number of parameters in stream_params.

struct bt_bap_broadcast_source_stream_param *params
   Array of stream parameters.

struct bt_audio_codec_cfg *codec_cfg
   Subgroup Codec configuration.

struct bt_bap_broadcast_source_param
   #include <bap.h> Broadcast Source create parameters.

Public Members

size_t params_count
   The number of parameters in subgroup_params.

struct bt_bap_broadcast_source_subgroup_param *params
   Array of stream parameters.

struct bt_audio_codec_qos *qos
   Quality of Service configuration.

uint8_t packing
   Broadcast Source packing mode.
   BT_ISO_PACKING_SEQUENTIAL or BT_ISO_PACKING_INTERLEAVED.

   Note: This is a recommendation to the controller, which the controller may ignore.

bool encryption
   Whether or not to encrypt the streams.

uint8_t broadcast_code[BT_AUDIO_BROADCAST_CODE_SIZE]
   Broadcast code.
   If the value is a string or a the value is less than 16 octets, the remaining octets
   shall be 0.
   Example: The string “Broadcast Code” shall be [42 72 6F 61 64 63 61 73 74 20 43 6F 64 65 00 00]

Common Audio Profile

API Reference

6.1. Bluetooth

1663
**group bt_cap**

Common Audio Profile (CAP)

[Experimental] Users should note that the APIs can change as a part of ongoing development.

**Enums**

**enum bt_cap_set_type**

Type of CAP set.

*Values:*

- enumerator **BT_CAP_SET_TYPE_AD_HOC**
  The set is an ad-hoc set.

- enumerator **BT_CAP_SET_TYPE_CSIP**
  The set is a CSIP Coordinated Set.

**Functions**

**int bt_cap_acceptor_register**(const struct *bt_csip_set_member_register_param* *param, struct *bt_csip_set_member_svc_inst** *svc_inst*)

Register the Common Audio Service.

This will register and enable the service and make it discoverable by clients. This will also register a Coordinated Set Identification Service instance.

This shall only be done as a server, and requires **BT_CAP_ACCEPTOR_SET_MEMBER**. If **BT_CAP_ACCEPTOR_SET_MEMBER** is not enabled, the Common Audio Service will be statically registered.

**Parameters**

- *param – [in]* Coordinated Set Identification Service register parameters.
- *svc_inst – [out]* Pointer to the registered Coordinated Set Identification Service.

**Returns**

0 if success, errno on failure.

**int bt_cap_initiator_unicast_discover**(struct *bt_conn* *conn*)

Discovers audio support on a remote device.

This will discover the Common Audio Service (CAS) on the remote device, to verify if the remote device supports the Common Audio Profile.

**Parameters**

- *conn – Connection to a remote server.*

**Return values**

- 0 – Success
- -EINVAL – conn is NULL
- -ENOTCONN – conn is not connected
- -ENOMEM – Could not allocated memory for the request
void bt_cap_stream_ops_register(struct bt_cap_stream *stream, struct bt_bap_stream_ops *ops)

Register Audio operations for a Common Audio Profile stream.

Parameters
- `stream` – Stream object.
- `ops` – Stream operations structure.

int bt_cap_stream_send(struct bt_cap_stream *stream, struct net_buf *buf, uint16_t seq_num)

Send data to Common Audio Profile stream without timestamp.

See `bt_bap_stream_send()` for more information

Note: Support for sending must be supported, determined by `CONFIG_BT_AUDIO_TX`.

Parameters
- `stream` – Stream object.
- `buf` – Buffer containing data to be sent.
- `seq_num` – Packet Sequence number. This value shall be incremented for each call to this function and at least once per SDU interval for a specific channel.

Return values
- `-EINVAL` – if stream object is NULL
- Any – return value from `bt_bap_stream_send()`

int bt_cap_stream_send_ts(struct bt_cap_stream *stream, struct net_buf *buf, uint16_t seq_num, uint32_t ts)

Send data to Common Audio Profile stream with timestamp.

See `bt_bap_stream_send()` for more information

Note: Support for sending must be supported, determined by `CONFIG_BT_AUDIO_TX`.

Parameters
- `stream` – Stream object.
- `buf` – Buffer containing data to be sent.
- `seq_num` – Packet Sequence number. This value shall be incremented for each call to this function and at least once per SDU interval for a specific channel.
- `ts` – Timestamp of the SDU in microseconds (us). This value can be used to transmit multiple SDUs in the same SDU interval in a CIG or BIG.

Return values
- `-EINVAL` – if stream object is NULL
- Any – return value from `bt_bap_stream_send()`
int bt_cap_stream_get_tx_sync(struct bt_cap_stream *stream, struct bt_iso_tx_info *info)
Get ISO transmission timing info for a Common Audio Profile stream.

See bt_bap_stream_get_tx_sync() for more information

**Note:** Support for sending must be supported, determined by CONFIG_BT_AUDIO_TX.

### Parameters
- **stream** – [in] Stream object.
- **info** – [out] Transmit info object.

### Return values
- **-EINVAL** – if stream object is NULL
- **Any** – return value from bt_bap_stream_get_tx_sync()

### Parameters
- **cb** – The callback structure. Shall remain static.

### Returns
0 on success or negative error value on failure.

int bt_cap_initiator_register_cb(const struct bt_cap_initiator_cb *cb)
Register Common Audio Profile Initiator callbacks.

### Parameters
- **cb** – The callback structure. Shall remain static.

### Returns
0 on success or negative error value on failure.

### Parameters
- **param** – Parameters to start the audio streams.

### Returns
0 on success or negative error value on failure.

int bt_cap_initiator_unicast_audio_update(const struct bt_cap_unicast_audio_update_param *param)

Update unicast audio streams.
This will update the metadata of one or more streams.

**Note:** CONFIG_BT_CAP_INITIATOR and CONFIG_BT_BAP_UNICAST_CLIENT must be enabled for this function to be enabled.

### Parameters
- **param** – Update parameters.
Returns
0 on success or negative error value on failure.

`int bt_cap_initiator_unicast_audio_stop(const struct bt_cap_unicast_audio_stop_param *param)`

Stop unicast audio streams.
This will stop one or more streams.

Note: CONFIG_BT_CAP_INITIATOR and CONFIG_BT_BAP_UNICAST_CLIENT must be enabled for this function to be enabled.

Parameters
- `param` – Stop parameters.

Returns
0 on success or negative error value on failure.

`int bt_cap_initiator_unicast_audio_cancel(void)`

Cancel any current Common Audio Profile procedure.
This will stop the current procedure from continuing and making it possible to run a new Common Audio Profile procedure.

It is recommended to do this if any existing procedure takes longer time than expected, which could indicate a missing response from the Common Audio Profile Acceptor.

This does not send any requests to any Common Audio Profile Acceptors involved with the current procedure, and thus notifications from the Common Audio Profile Acceptors may arrive after this has been called. It is thus recommended to either only use this if a procedure has stalled, or wait a short while before starting any new Common Audio Profile procedure after this has been called to avoid getting notifications from the cancelled procedure. The wait time depends on the connection interval, the number of devices in the previous procedure and the behavior of the Common Audio Profile Acceptors.

The respective callbacks of the procedure will be called as part of this with the connection pointer set to 0 and the err value set to -ECANCELED.

Return values
- 0 – on success
- -EALREADY – if no procedure is active

`int bt_cap_initiator_broadcast_audio_create(const struct bt_cap_initiator_broadcast_create_param *param, struct bt_cap_broadcast_source **broadcast_source)`

Create a Common Audio Profile broadcast source.
Create a new audio broadcast source with one or more audio streams.

Note: CONFIG_BT_CAP_INITIATOR and CONFIG_BT_BAP_BROADCAST_SOURCE must be enabled for this function to be enabled.

Parameters
- `param` – [in] Parameters to start the audio streams.
• **broadcast_source** – [out] Pointer to the broadcast source created.

**Returns**
0 on success or negative error value on failure.

```c
int bt_cap_initiator_broadcast_audio_start(struct bt_cap_broadcast_source *broadcast_source, struct bt_le_ext_adv *adv)
```

Start Common Audio Profile broadcast source.

The broadcast source will be visible for scanners once this has been called, and the device will advertise audio announcements.

This will allow the streams in the broadcast source to send audio by calling `bt_bap_stream_send()`.

**Note:** `CONFIG_BT_CAP_INITIATOR` and `CONFIG_BT_BAP_BROADCAST_SOURCE` must be enabled for this function to be enabled.

**Parameters**
- **broadcast_source** – Pointer to the broadcast source.
- **adv** – Pointer to an extended advertising set with periodic advertising configured.

**Returns**
0 on success or negative error value on failure.

```c
int bt_cap_initiator_broadcast_audio_update(struct bt_cap_broadcast_source *broadcast_source, const uint8_t meta[], size_t meta_len)
```

Update broadcast audio streams for a Common Audio Profile broadcast source.

**Note:** `CONFIG_BT_CAP_INITIATOR` and `CONFIG_BT_BAP_BROADCAST_SOURCE` must be enabled for this function to be enabled.

**Parameters**
- **broadcast_source** – The broadcast source to update.
- **meta** – The new metadata. The metadata shall contain a list of CCIDs as well as a non-0 context bitfield.
- **meta_len** – The length of `meta`.

**Returns**
0 on success or negative error value on failure.

```c
int bt_cap_initiator_broadcast_audio_stop(struct bt_cap_broadcast_source *broadcast_source)
```

Stop broadcast audio streams for a Common Audio Profile broadcast source.

**Note:** `CONFIG_BT_CAP_INITIATOR` and `CONFIG_BT_BAP_BROADCAST_SOURCE` must be enabled for this function to be enabled.

**Parameters**
• **broadcast_source** – The broadcast source to stop. The audio streams in this will be stopped and reset.

**Returns**

0 on success or negative error value on failure.

```c
int bt_cap_initiator_broadcast_audio_delete(struct bt_cap_broadcast_source *broadcast_source)
```

Delete Common Audio Profile broadcast source.

This can only be done after the broadcast source has been stopped by calling `bt_cap_initiator_broadcast_audio_stop()` and after the `bt_bap_stream_ops.stopped()` callback has been called for all streams in the broadcast source.

**Note:** `CONFIG_BT_CAP_INITIATOR` and `CONFIG_BT_BAP_BROADCAST_SOURCE` must be enabled for this function to be enabled.

**Parameters**

• **broadcast_source** – [in] Pointer to the broadcast source.

**Returns**

0 on success or negative error value on failure.

```c
int bt_cap_initiator_broadcast_get_id(const struct bt_cap_broadcast_source *broadcast_source, uint32_t *const broadcast_id)
```

Get the broadcast ID of a Common Audio Profile broadcast source.

This will return the 3-octet broadcast ID that should be advertised in the extended advertising data with `BT_UUID_BROADCAST_AUDIO_VAL` as `BT_DATA_SVC_DATA16`.

See table 3.14 in the Basic Audio Profile v1.0.1 for the structure.

**Parameters**

• **broadcast_source** – [in] Pointer to the broadcast source.

• **broadcast_id** – [out] Pointer to the 3-octet broadcast ID.

**Returns**

int 0 if on success, errno on error.

```c
int bt_cap_initiator_broadcast_get_base(struct bt_cap_broadcast_source *broadcast_source, struct net_buf_simple *base_buf)
```

Get the Broadcast Audio Stream Endpoint of a Common Audio Profile broadcast source.

This will encode the BASE of a broadcast source into a buffer, that can be used for advertisement. The encoded BASE will thus be encoded as little-endian. The BASE shall be put into the periodic advertising data (see `bt_le_per_adv_set_data()`).

See table 3.15 in the Basic Audio Profile v1.0.1 for the structure.

**Parameters**

• **broadcast_source** – Pointer to the broadcast source.

• **base_buf** – Pointer to a buffer where the BASE will be inserted.

**Returns**

int 0 if on success, errno on error.
int bt_cap_initiator_unicast_to_broadcast(
    const struct bt_cap_unicast_to_broadcast_param *param, struct bt_cap_broadcast_source **source)

Hands over the data streams in a unicast group to a broadcast source.
The streams in the unicast group will be stopped and the unicast group will be deleted.
This can only be done for source streams.

Note: CONFIG_BT_CAP_INITIATOR, CONFIG_BT_BAP_UNICAST_CLIENT and CONFIG_BT_BAP_BROADCAST_SOURCE must be enabled for this function to be enabled.

Parameters
- param – The parameters for the handover.
- source – The resulting broadcast source.

Returns
0 on success or negative error value on failure.

int bt_cap_initiator_broadcast_to_unicast(
    const struct bt_cap_broadcast_to_unicast_param *param, struct bt_bap_unicast_group **unicast_group)

Hands over the data streams in a broadcast source to a unicast group.
The streams in the broadcast source will be stopped and the broadcast source will be deleted.

Note: CONFIG_BT_CAP_INITIATOR, CONFIG_BT_BAP_UNICAST_CLIENT and CONFIG_BT_BAP_BROADCAST_SOURCE must be enabled for this function to be enabled.

Parameters
- unicast_group – [out] The resulting broadcast source.

Returns
0 on success or negative error value on failure.

int bt_cap_commander_register_cb(const struct bt_cap_commander_cb *cb)

Register Common Audio Profile Commander callbacks.

Parameters
- cb – The callback structure. Shall remain static.

Return values
- 0 – Success
- -EINVAL – cb is NULL
- -EALREADY – Callbacks are already registered

int bt_cap_commander_unregister_cb(const struct bt_cap_commander_cb *cb)

Unregister Common Audio Profile Commander callbacks.

Parameters
• cb – The callback structure that was previously registered.

**Return values**

• 0 – Success
• -EINVAL – cb is NULL or cb was not registered

```c
int bt_cap_commander_discover(struct bt_conn *conn)
```

Discovers audio support on a remote device.

This will discover the Common Audio Service (CAS) on the remote device, to verify if the remote device supports the Common Audio Profile.

**Note:** `CONFIG_BT_CAP_COMMANDER` must be enabled for this function. If `CONFIG_BT_CAP_INITIATOR` is also enabled, it does not matter if `bt_cap_commander_discover()` or `bt_cap_initiator_unicast_discover()` is used.

**Parameters**

• conn – Connection to a remote server.

**Return values**

• 0 – Success
• -EINVAL – conn is NULL
• -ENOTCONN – conn is not connected
• -ENOMEM – Could not allocated memory for the request
• -EBUSY – Already doing discovery for conn

```c
int bt_cap_commander_cancel(void)
```

Cancel any current Common Audio Profile commander procedure.

This will stop the current procedure from continuing and making it possible to run a new Common Audio Profile procedure.

It is recommended to do this if any existing procedure takes longer time than expected, which could indicate a missing response from the Common Audio Profile Acceptor.

This does not send any requests to any Common Audio Profile Acceptors involved with the current procedure, and thus notifications from the Common Audio Profile Acceptors may arrive after this has been called. It is thus recommended to either only use this if a procedure has stalled, or wait a short while before starting any new Common Audio Profile procedure after this has been called to avoid getting notifications from the cancelled procedure. The wait time depends on the connection interval, the number of devices in the previous procedure and the behavior of the Common Audio Profile Acceptors.

The respective callbacks of the procedure will be called as part of this with the connection pointer set to NULL and the err value set to -ECANCELED.

**Return values**

• 0 – on success
• -EALREADY – if no procedure is active

```c
int bt_cap_commander_broadcast_reception_start(const struct bt_cap_commander_broadcast_reception_start_param *param)
```

Starts the reception of broadcast audio on one or more remote Common Audio Profile Acceptors.

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Parameters

• param – The parameters to start the broadcast audio

Returns

0 on success or negative error value on failure.

int bt_cap_commander_broadcast_reception_stop(const struct

bt_cap_commander_broadcast_reception_stop_param

*param)

Stops the reception of broadcast audio on one or more remote Common Audio Profile Acceptors.

Parameters

• param – The parameters to stop the broadcast audio

Returns

0 on success or negative error value on failure.

int bt_cap_commander_change_volume(const struct

bt_cap_commander_change_volume_param

*param)

Change the volume on one or more Common Audio Profile Acceptors.

Parameters

• param – The parameters for the volume change

Returns

0 on success or negative error value on failure.

int bt_cap_commander_change_volume_offset(const struct

bt_cap_commander_change_volume_offset_param

*param)

Change the volume offset on one or more Common Audio Profile Acceptors.

Parameters

• param – The parameters for the volume offset change

Returns

0 on success or negative error value on failure.

int bt_cap_commander_change_volume_mute_state(const struct

bt_cap_commander_change_volume_mute_state_param

*param)

Change the volume mute state on one or more Common Audio Profile Acceptors.

Parameters

• param – The parameters for the volume mute state change

Returns

0 on success or negative error value on failure.

int bt_cap_commander_change_microphone_mute_state(const struct

bt_cap_commander_change_microphone_mute_state_param

*param)

Change the microphone mute state on one or more Common Audio Profile Acceptors.

Parameters

• param – The parameters for the microphone mute state change

Returns

0 on success or negative error value on failure.
int bt_cap_commander_change_microphone_gain_setting(const struct bt_cap_commander_change_microphone_gain_setting_param *param)

Change the microphone gain setting on one or more Common Audio Profile Acceptors.

**Parameters**

- **param** – The parameters for the microphone gain setting change

**Returns**

0 on success or negative error value on failure.

struct bt_cap_initiator_cb

```c
#include <cap.h>
```

Callback structure for CAP procedures.

union bt_cap_set_member

```c
#include <cap.h>
```

Represents a Common Audio Set member that are either in a Coordinated or ad-hoc set.

**Public Members**

struct bt_conn *member

Connection pointer if the type is BT_CAP_SET_TYPE_AD_HOC.

struct bt_csip_set_coordinator_csis_inst *csip

CSIP Coordinated Set struct used if type is BT_CAP_SET_TYPE_CSIP.

struct bt_cap_stream

```c
#include <cap.h>
```

**Public Members**

union bt_cap_set_member member

Coordinated or ad-hoc set member.

struct bt_cap_stream *stream

Stream for the member.

struct bt_bap_ep *ep

Endpoint reference for the stream.

struct bt_audio_codec_cfg *codec_cfg

Codec configuration.

The `codec_cfg.meta` shall include a list of CCIDs (`BT_AUDIO_METADATA_TYPE_CCID_LIST`) as well as a non-0 stream context (`BT_AUDIO_METADATA_TYPE_STREAM_CONTEXT`) bitfield.
struct bt_cap_unicast_audio_start_param
#include <cap.h> Parameters for the bt_cap_initiator_unicast_audio_start() function.

Public Members

denum bt_cap_set_type type
    The type of the set.

d type
    The number of parameters in stream_params.

struct bt_cap_unicast_audio_start_stream_param *stream_params
    Array of stream parameters.

struct bt_cap_unicast_audio_update_stream_param
#include <cap.h> Stream specific parameters for the bt_cap_initiator_unicast_audio_update() function.

Public Members

struct bt_cap_stream *stream
    Stream to update.

d size_t meta_len
    The length of meta.

uint8_t *meta
    The new metadata.
    The metadata shall a list of CCIDs as well as a non-0 context bitfield.

struct bt_cap_unicast_audio_update_param
#include <cap.h> Parameters for the bt_cap_initiator_unicast_audio_update() function.

Public Members

denum bt_cap_set_type type
    The type of the set.

d type
    The number of parameters in stream_params.

struct bt_cap_unicast_audio_update_stream_param *stream_params
    Array of stream parameters.

struct bt_cap_unicast_audio_stop_param
#include <cap.h> Parameters for the bt_cap_initiator_unicast_audio_stop() function.
Public Members

enum bt_cap_set_type type
    The type of the set.

size_t count
    The number of streams in streams.

struct bt_cap_stream **streams
    Array of streams to stop.

struct bt_cap_initiator_broadcast_stream_param
   #include <cap.h>

Public Members

struct bt_cap_stream *stream
    Audio stream.

size_t data_len
    The length of the p data array.
    The BIS specific data may be omitted and this set to 0.

uint8_t *data
    BIS Codec Specific Configuration.

struct bt_cap_initiator_broadcast_subgroup_param
   #include <cap.h>

Public Members

size_t stream_count
    The number of parameters in stream_params.

struct bt_cap_initiator_broadcast_stream_param *stream_params
    Array of stream parameters.

struct bt_audio_codec_cfg *codec_cfg
    Subgroup Codec configuration.

struct bt_cap_initiator_broadcast_create_param
   #include <cap.h>

6.1. Bluetooth
Public Members

size_t subgroup_count
The number of parameters in subgroup_params.

struct bt_cap_initiator_broadcast_subgroup_param *subgroup_params
Array of stream parameters.

struct bt_audio_codec_qos *qos
Quality of Service configuration.

uint8_t packing
Broadcast Source packing mode.
BT_ISO_PACKING_SEQUENTIAL or BT_ISO_PACKING_INTERLEAVED.

Note: This is a recommendation to the controller, which the controller may ignore.

bool encryption
Whether or not to encrypt the streams.

uint8_t broadcast_code[BT_AUDIO_BROADCAST_CODE_SIZE]
16-octet broadcast code.
Only valid if encrypt is true.
If the value is a string or a the value is less than 16 octets, the remaining octets shall be 0.
Example: The string “Broadcast Code” shall be [42 72 6F 61 64 63 61 73 74 20 43 6F 64 65 00 00]

struct bt_cap_unicast_to_broadcast_param
#include <cap.h>

Public Members

struct bt_bap_unicast_group *unicast_group
The source unicast group with the streams.

bool encrypt
Whether or not to encrypt the streams.
If set to true, then the broadcast code in broadcast_code will be used to encrypt the streams.

uint8_t broadcast_code[BT_ISO_BROADCAST_CODE_SIZE]
16-octet broadcast code.
Only valid if encrypt is true.
If the value is a string or a the value is less than 16 octets, the remaining octets shall be 0.
Example: The string “Broadcast Code” shall be [42 72 6F 61 64 63 61 73 74 20 43 6F 64 65 00 00]

```c
struct bt_cap_broadcast_to_unicast_param
#include <cap.h>
```

**Public Members**

```c
struct bt_cap_broadcast_source *broadcast_source
    The source broadcast source with the streams.
    The broadcast source will be stopped and deleted.

enum bt_cap_set_type type
    The type of the set.

size_t count
    The number of set members in members.
    This value shall match the number of streams in the broadcast_source.

union bt_cap_set_member **members
    Coordinated or ad-hoc set members.
```

```c
struct bt_cap_commander_cb
#include <cap.h> Callback structure for CAP procedures.
```

**Public Members**

```c
void (*discovery_complete)(struct bt_conn *conn, int err, const struct bt_csip_set_coordinator_csis_inst *csis_inst)
    Callback for bt_cap_initiator_unicast_discover().
    Param conn
        The connection pointer supplied to bt_cap_initiator_unicast_discover().
    Param err
        0 if Common Audio Service was found else -ENODATA.
    Param csis_inst
        The Coordinated Set Identification Service if Common Audio Service was found and includes a Coordinated Set Identification Service. NULL on error or if remote device does not include Coordinated Set Identification Service.
```

```c
struct bt_cap_commander_broadcast_reception_start_member_param
#include <cap.h>
```

**Public Members**

```c
union bt_cap_set_member member
    Coordinated or ad-hoc set member.
```

6.1. Bluetooth
bt_addr_le_t addr
Address of the advertiser.

uint8_t adv_sid
SID of the advertising set.

uint16_t pa_interval
Periodic advertising interval in milliseconds.
BT_BAP_PA_INTERVAL_UNKNOWN if unknown.

uint32_t broadcast_id
24-bit broadcast ID

struct bt_bap_bass_subgroup *subgroups
Pointer to array of subgroups.
At least one bit in one of the subgroups bis_sync parameters shall be set.

size_t num_subgroups
Number of subgroups.

struct bt_cap_commander_broadcast_reception_start_param
#include <cap.h> Parameters for starting broadcast reception

Public Members

enum bt_cap_set_type type
The type of the set.

struct bt_cap_commander_broadcast_reception_start_member_param *param
The set of devices for this procedure.

size_t count
The number of parameters in param.

struct bt_cap_commander_broadcast_reception_stop_param
#include <cap.h> Parameters for stopping broadcast reception

Public Members

enum bt_cap_set_type type
The type of the set.

union bt_cap_set_member *members
Coordinated or ad-hoc set member.
size_t count
   The number of members in members.

struct bt_cap_commander_change_volume_param
   \#include <cap.h> Parameters for changing absolute volume

Public Members

eenum bt_cap_set_type type
   The type of the set.

union bt_cap_set_member *members
   Coordinated or ad-hoc set member.

size_t count
   The number of members in members.

uint8_t volume
   The absolute volume to set.

struct bt_cap_commander_change_volume_offset_member_param
   \#include <cap.h>

Public Members

union bt_cap_set_member member
   Coordinated or ad-hoc set member.

int16_t offset
   The offset to set.
   Value shall be between BT_VOCS_MIN_OFFSET and BT_VOCS_MAX_OFFSET

struct bt_cap_commander_change_volume_offset_param
   \#include <cap.h> Parameters for changing volume offset.

Public Members

eenum bt_cap_set_type type
   The type of the set.

struct bt_cap_commander_change_volume_offset_member_param *param
   The set of devices for this procedure.

size_t count
   The number of parameters in param.
struct bt_cap_commander_change_volume_mute_state_param
#include <cap.h> Parameters for changing volume mute state.

Public Members

denum bt_cap_set_type type
   The type of the set.

union bt_cap_set_member *members
   Coordinated or ad-hoc set member.

size_t count
   The number of members in members.

bool mute
   The volume mute state to set.
   true to mute, and false to unmute

struct bt_cap_commander_change_microphone_mute_state_param
#include <cap.h> Parameters for changing microphone mute state.

Public Members

denum bt_cap_set_type type
   The type of the set.

union bt_cap_set_member *members
   Coordinated or ad-hoc set member.

size_t count
   The number of members in members.

bool mute
   The microphone mute state to set.
   true to mute, and false to unmute

struct bt_cap_commander_change_microphone_gain_setting_member_param
#include <cap.h>

Public Members

union bt_cap_set_member member
   Coordinated or ad-hoc set member.
int8_t gain
The microphone gain setting to set.

struct bt_cap_commander_change_microphone_gain_setting_param
#include <cap.h> Parameters for changing microphone mute state.

Public Members

enum bt_cap_set_type type
The type of the set.

struct bt_cap_commander_change_microphone_gain_setting_member_param *param
The set of devices for this procedure.

size_t count
The number of parameters in param.

Connection Management

The Zephyr Bluetooth stack uses an abstraction called bt_conn to represent connections to other devices. The internals of this struct are not exposed to the application, but a limited amount of information (such as the remote address) can be acquired using the bt_conn_get_info() API. Connection objects are reference counted, and the application is expected to use the bt_conn_ref() API whenever storing a connection pointer for a longer period of time, since this ensures that the object remains valid (even if the connection would get disconnected). Similarly the bt_conn_unref() API is to be used when releasing a reference to a connection.

An application may track connections by registering a bt_conn_cb struct using the bt_conn_cb_register() or BT_CONN_CB_DEFINE APIs. This struct lets the application define callbacks for connection & disconnection events, as well as other events related to a connection such as a change in the security level or the connection parameters. When acting as a central the application will also get hold of the connection object through the return value of the bt_conn_le_create() API.

API Reference

group bt_conn
Connection management.

Defines

BT_LE_CONN_PARAM_INIT(int_min, int_max, lat, to)
Initialize connection parameters.

Parameters

• int_min – Minimum Connection Interval (N * 1.25 ms)
• int_max – Maximum Connection Interval (N * 1.25 ms)
• lat – Connection Latency
• to – Supervision Timeout (N * 10 ms)
BT_LE_CONN_PARAM(int_min, int_max, lat, to)
Helper to declare connection parameters inline.

**Parameters**
- **int_min** – Minimum Connection Interval (N * 1.25 ms)
- **int_max** – Maximum Connection Interval (N * 1.25 ms)
- **lat** – Connection Latency
- **to** – Supervision Timeout (N * 10 ms)

**BT_LE_CONN_PARAM_DEFAULT**
Default LE connection parameters: Connection Interval: 30-50 ms Latency: 0 Timeout: 4 s.

**BT_CONN_LE_PHY_PARAM_INIT(_pref_tx_phy, _pref_rx_phy)**
Initialize PHY parameters.

**Parameters**
- **_pref_tx_phy** – Bitmask of preferred transmit PHYs.
- **_pref_rx_phy** – Bitmask of preferred receive PHYs.

**BT_CONN_LE_PHY_PARAM(_pref_tx_phy, _pref_rx_phy)**
Helper to declare PHY parameters inline.

**Parameters**
- **_pref_tx_phy** – Bitmask of preferred transmit PHYs.
- **_pref_rx_phy** – Bitmask of preferred receive PHYs.

**BT_CONN_LE_PHY_PARAM_1M**
Only LE 1M PHY.

**BT_CONN_LE_PHY_PARAM_2M**
Only LE 2M PHY.

**BT_CONN_LE_PHY_PARAM_CODED**
Only LE Coded PHY.

**BT_CONN_LE_PHY_PARAM_ALL**
All LE PHYs.

**BT_CONN_LE_DATA_LEN_PARAM_INIT(_tx_max_len, _tx_max_time)**
Initialize transmit data length parameters.

**Parameters**
- **_tx_max_len** – Maximum Link Layer transmission payload size in bytes.
- **_tx_max_time** – Maximum Link Layer transmission payload time in us.

**BT_CONN_LE_DATA_LEN_PARAM(_tx_max_len, _tx_max_time)**
Helper to declare transmit data length parameters inline.

**Parameters**
- **_tx_max_len** – Maximum Link Layer transmission payload size in bytes.
- **_tx_max_time** – Maximum Link Layer transmission payload time in us.
**BT_LE_DATA_LEN_PARAM_DEFAULT**
Default LE data length parameters.

**BT_LE_DATA_LEN_PARAM_MAX**
Maximum LE data length parameters.

**BT_CONN_INTERVAL_TO_MS(interval)**
Convert connection interval to milliseconds.
Multiply by 1.25 to get milliseconds.
Note that this may be inaccurate, as something like 7.5 ms cannot be accurately presented with integers.

**BT_CONN_INTERVAL_TO_US(interval)**
Convert connection interval to microseconds.
Multiply by 1250 to get microseconds.

**BT_CONN_ROLE_MASTER**
Connection role (central or peripheral)

**BT_CONN_ROLE_SLAVE**

**BT_CONN_LE_CREATE_PARAM_INIT(_options, _interval, _window)**
Initialize create connection parameters.

**Parameters**
- `_options` – Create connection options.
- `_interval` – Create connection scan interval (N * 0.625 ms).
- `_window` – Create connection scan window (N * 0.625 ms).

**BT_CONN_LE_CREATE_PARAM(_options, _interval, _window)**
Helper to declare create connection parameters inline.

**Parameters**
- `_options` – Create connection options.
- `_interval` – Create connection scan interval (N * 0.625 ms).
- `_window` – Create connection scan window (N * 0.625 ms).

**BT_CONN_LE_CREATE_CONN**
Default LE create connection parameters.
Scan continuously by setting scan interval equal to scan window.

**BT_CONN_LE_CREATE_CONN_AUTO**
Default LE create connection using filter accept list parameters.
Scan window: 30 ms. Scan interval: 60 ms.

**BT_CONN_CB_DEFINE(_name)**
Register a callback structure for connection events.

**Parameters**
- `_name` – Name of callback structure.

---

6.1. Bluetooth
BT_PASSKEY_INVALID
Special passkey value that can be used to disable a previously set fixed passkey.

BT_BR_CONN_PARAM_INIT(role_switch)
Initialize BR/EDR connection parameters.

Parameters
• role_switch – True if role switch is allowed

BT_BR_CONN_PARAM(role_switch)
Helper to declare BR/EDR connection parameters inline.

Parameters
• role_switch – True if role switch is allowed

BT_BR_CONN_PARAM_DEFAULT
Default BR/EDR connection parameters: Role switch allowed.

Enums

Connection PHY options.
Values:

enumerator BT_CONN_LE_PHY_OPT_NONE = 0
Convenience value when no options are specified.

enumerator BT_CONN_LE_PHY_OPT_CODED_S2 = BIT(0)
LE Coded using S=2 coding preferred when transmitting.

enumerator BT_CONN_LE_PHY_OPT_CODED_S8 = BIT(1)
LE Coded using S=8 coding preferred when transmitting.

enum bt_conn_type
Connection Type.
Values:

enumerator BT_CONN_TYPE_LE = BIT(0)
LE Connection Type.

enumerator BT_CONN_TYPE_BR = BIT(1)
BR/EDR Connection Type.

enumerator BT_CONN_TYPE_SCO = BIT(2)
SCO Connection Type.

enumerator BT_CONN_TYPE_ISO = BIT(3)
ISO Connection Type.
enumerator BT_CONN_TYPE_ALL = BT_CONN_TYPE_LE | BT_CONN_TYPE_BR | BT_CONN_TYPE_SCO | BT_CONN_TYPE_ISO
All Connection Type.

Values:

enumerator BT_CONN_ROLE_CENTRAL = 0
enumerator BT_CONN_ROLE_PERIPHERAL = 1

def bt_conn_state

Values:

enumerator BT_CONN_STATE_DISCONNECTED
Channel disconnected.
enumerator BT_CONN_STATE_CONNECTING
Channel in connecting state.
enumerator BT_CONN_STATE_CONNECTED
Channel connected and ready for upper layer traffic on it.
enumerator BT_CONN_STATE_DISCONNECTING
Channel in disconnecting state.

def bt_security_t

Security level.

Values:

enumerator BT_SECURITY_L0
Level 0: Only for BR/EDR special cases, like SDP.
enumerator BT_SECURITY_L1
Level 1: No encryption and no authentication.
enumerator BT_SECURITY_L2
Level 2: Encryption and no authentication (no MITM).
enumerator BT_SECURITY_L3
Level 3: Encryption and authentication (MITM).
enumerator BT_SECURITY_L4
Level 4: Authenticated Secure Connections and 128-bit key.
enumerator BT_SECURITY_FORCE_PAIR = BIT(7)
Bit to force new pairing procedure, bit-wise OR with requested security level.
enum bt_security_flag
    Security Info Flags.
    Values:

    enumerator BT_SECURITY_FLAG_SC = BIT(0)
        Paired with Secure Connections.

    enumerator BT_SECURITY_FLAG_OOB = BIT(1)
        Paired with Out of Band method.

enum bt_conn_le_tx_power_phy
    Values:

    enumerator BT_CONN_LE_TX_POWER_PHY_NONE
        Convenience macro for when no PHY is set.

    enumerator BT_CONN_LE_TX_POWER_PHY_1M
        LE 1M PHY.

    enumerator BT_CONN_LE_TX_POWER_PHY_2M
        LE 2M PHY.

    enumerator BT_CONN_LE_TX_POWER_PHY_CODED_S8
        LE Coded PHY using S=8 coding.

    enumerator BT_CONN_LE_TX_POWER_PHY_CODED_S2
        LE Coded PHY using S=2 coding.

enum bt_conn_auth_keypress
    Passkey Keypress Notification type.
    The numeric values are the same as in the Core specification for Pairing Keypress Notification PDU.
    Values:

    enumerator BT_CONN_AUTH_KEYPRESS_ENTRY_STARTED = 0x00

    enumerator BT_CONN_AUTH_KEYPRESS_DIGIT_ENTERED = 0x01

    enumerator BT_CONN_AUTH_KEYPRESS_DIGIT_ERASED = 0x02

    enumerator BT_CONN_AUTH_KEYPRESS_CLEARED = 0x03

    enumerator BT_CONN_AUTH_KEYPRESS_ENTRY_COMPLETED = 0x04

    Values:
enumerator BT_CONN_LE_OPT_NONE = 0
Convenience value when no options are specified.

enumerator BT_CONN_LE_OPT_CODED = BIT(0)
Enable LE Coded PHY.
Enable scanning on the LE Coded PHY.

enumerator BT_CONN_LE_OPT_NO_1M = BIT(1)
Disable LE 1M PHY.
Disable scanning on the LE 1M PHY.
@note Requires @ref BT_CONN_LE_OPT_CODED.

enum bt_security_err
Values:

enumerator BT_SECURITY_ERR_SUCCESS
Security procedure successful.

enumerator BT_SECURITY_ERR_AUTH_FAIL
Authentication failed.

enumerator BT_SECURITY_ERR_PIN_OR_KEY_MISSING
PIN or encryption key is missing.

enumerator BT_SECURITY_ERR_OOB_NOT_AVAILABLE
OOB data is not available.

enumerator BT_SECURITY_ERR_AUTH_REQUIREMENT
The requested security level could not be reached.

enumerator BT_SECURITY_ERR_PAIR_NOT_SUPPORTED
Pairing is not supported.

enumerator BT_SECURITY_ERR_PAIR_NOT_ALLOWED
Pairing is not allowed.

enumerator BT_SECURITY_ERR_INVALID_PARAM
Invalid parameters.

enumerator BT_SECURITY_ERR_KEY_REJECTED
Distributed Key Rejected.

enumerator BT_SECURITY_ERR_UNSPECIFIED
Pairing failed but the exact reason could not be specified.

6.1. Bluetooth
Functions

struct bt_conn *bt_conn_ref(struct bt_conn *conn)
Increment a connection's reference count.
Increment the reference count of a connection object.

Note: Will return NULL if the reference count is zero.

Parameters

• conn – Connection object.

Returns
Connection object with incremented reference count, or NULL if the reference count is zero.

void bt_conn_unref(struct bt_conn *conn)
Decrement a connection's reference count.
Decrement the reference count of a connection object.

Parameters

• conn – Connection object.

void bt_conn_foreach(enum bt_conn_type type, void (*func)(struct bt_conn *conn, void *data), void *data)
Iterate through all bt_conn objects.
Iterates through all bt_conn objects that are alive in the Host allocator.
To find established connections, combine this with bt_conn_get_info. Check that bt_conn_info::state is BT_CONN_STATE_CONNECTED.

Thread safety: This API is thread safe, but it does not guarantee a sequentially-consistent view for objects allocated during the current invocation of this API. E.g. If preempted while allocations A then B then C happen then results may include A and C but miss B.

Parameters

• type – Connection Type
• func – Function to call for each connection.
• data – Data to pass to the callback function.

struct bt_conn *bt_conn_lookup_addr_le(uint8_t id, const bt_addr_le_t *peer)
Look up an existing connection by address.
Look up an existing connection based on the remote address.
The caller gets a new reference to the connection object which must be released with bt_conn_unref() once done using the object.

Parameters

• id – Local identity (in most cases BT_ID_DEFAULT).
• peer – Remote address.

Returns
Connection object or NULL if not found.
const bt_addr_le_t *bt_conn_get_dst(const struct bt_conn *conn)
Get destination (peer) address of a connection.

**Parameters**
- conn – Connection object.

**Returns**
Destination address.

uint8_t bt_conn_index(const struct bt_conn *conn)
Get array index of a connection.

This function is used to map bt_conn to index of an array of connections. The array has CONFIG_BT_MAX_CONN elements.

**Parameters**
- conn – Connection object.

**Returns**
Index of the connection object. The range of the returned value is 0..CONFIG_BT_MAX_CONN-1

int bt_conn_get_info(const struct bt_conn *conn, struct bt_conn_info *info)
Get connection info.

**Parameters**
- conn – Connection object.
- info – Connection info object.

**Returns**
Zero on success or (negative) error code on failure.

int bt_conn_get_remote_info(struct bt_conn *conn, struct bt_conn_remote_info *remote_info)
Get connection info for the remote device.

**Note:** In order to retrieve the remote version (version, manufacturer and subversion) CONFIG_BT_REMOTE_VERSION must be enabled

**Note:** The remote information is exchanged directly after the connection has been established. The application can be notified about when the remote information is available through the remote_info_available callback.

**Parameters**
- conn – Connection object.
- remote_info – Connection remote info object.

**Returns**
Zero on success or (negative) error code on failure.

**Returns**
-EBUSY The remote information is not yet available.

int bt_conn_le_get_tx_power_level(struct bt_conn *conn, struct bt_conn_le_tx_power *tx_power_level)
Get connection transmit power level.
Parameters

• conn – Connection object.
• tx_power_level – Transmit power level descriptor.

Returns

Zero on success or (negative) error code on failure.

Returns

-ENOBUFS HCI command buffer is not available.

int bt_conn_le_enhanced_get_tx_power_level(struct bt_conn *conn, struct bt_conn_le_tx_power *tx_power)

Get local enhanced connection transmit power level.

Parameters

• conn – Connection object.
• tx_power – Transmit power level descriptor.

Return values

-ENOBUFS – HCI command buffer is not available.

Returns

Zero on success or (negative) error code on failure.

int bt_conn_le_get_remote_tx_power_level(struct bt_conn *conn, enum bt_conn_le_tx_power_phy phy)

Get remote (peer) transmit power level.

Parameters

• conn – Connection object.
• phy – PHY information.

Return values

-ENOBUFS – HCI command buffer is not available.

Returns

Zero on success or (negative) error code on failure.

int bt_conn_le_set_tx_power_report_enable(struct bt_conn *conn, bool local_enable, bool remote_enable)

Enable transmit power reporting.

Parameters

• conn – Connection object.
• local_enable – Enable/disable reporting for local.
• remote_enable – Enable/disable reporting for remote.

Return values

-ENOBUFS – HCI command buffer is not available.

Returns

Zero on success or (negative) error code on failure.

int bt_conn_le_param_update(struct bt_conn *conn, const struct bt_le_conn_param *param)

Update the connection parameters.

If the local device is in the peripheral role then updating the connection parameters will be delayed. This delay can be configured by through the CONFIG_BT_CONN_PARAM_UPDATE_TIMEOUT option.
Parameters
- `conn` – Connection object.
- `param` – Updated connection parameters.

Returns
Zero on success or (negative) error code on failure.

```c
int bt_conn_le_data_len_update(struct bt_conn *conn, const struct bt_conn_le_data_len_param *param)
```

Update the connection transmit data length parameters.

Parameters
- `conn` – Connection object.
- `param` – Updated data length parameters.

Returns
Zero on success or (negative) error code on failure.

```c
int bt_conn_le_phy_update(struct bt_conn *conn, const struct bt_conn_le_phy_param *param)
```

Update the connection PHY parameters.

Update the preferred transmit and receive PHYs of the connection. Use `BT_GAP_LE_PHY_NONE` to indicate no preference.

Parameters
- `conn` – Connection object.
- `param` – Updated connection parameters.

Returns
Zero on success or (negative) error code on failure.

```c
int bt_conn_disconnect(struct bt_conn *conn, uint8_t reason)
```

Disconnect from a remote device or cancel pending connection.

Disconnect an active connection with the specified reason code or cancel pending outgoing connection.

The disconnect reason for a normal disconnect should be: `BT_HCI_ERR_REMOTE_USER_TERM_CONN`.

The following disconnect reasons are accepted:
- `BT_HCI_ERR_AUTH_FAIL`
- `BT_HCI_ERR_REMOTE_USER_TERM_CONN`
- `BT_HCI_ERR_REMOTE_LOW_RESOURCES`
- `BT_HCI_ERR_REMOTE_POWER_OFF`
- `BT_HCI_ERR_UNSUPP_REMOTE_FEATURE`
- `BT_HCI_ERR_PAIRING_NOT_SUPPORTED`
- `BT_HCI_ERR_UNACCEPT_CONN_PARAM`

Parameters
- `conn` – Connection to disconnect.
- `reason` – Reason code for the disconnection.

Returns
Zero on success or (negative) error code on failure.
int bt_conn_le_create(const bt_addr_le_t *peer, const struct bt_conn_le_create_param *create_param, const struct bt_le_conn_param *conn_param, struct bt_conn **conn)

Initiate an LE connection to a remote device.
Allows initiate new LE link to remote peer using its address.
The caller gets a new reference to the connection object which must be released with bt_conn_unref() once done using the object.
This uses the General Connection Establishment procedure.
The application must disable explicit scanning before initiating a new LE connection.

Parameters
• peer – [in] Remote address.
• create_param – [in] Create connection parameters.
• conn_param – [in] Initial connection parameters.
• conn – [out] Valid connection object on success.

Returns
Zero on success or (negative) error code on failure.

int bt_conn_le_create_synced(const struct bt_le_ext_adv *adv, const struct bt_conn_le_create_synced_param *synced_param, const struct bt_le_conn_param *conn_param, struct bt_conn **conn)

Create a connection to a synced device.
Initiate a connection to a synced device from a Periodic Advertising with Responses (PAwR) train.
The caller gets a new reference to the connection object which must be released with bt_conn_unref() once done using the object.
This uses the Periodic Advertising Connection Procedure.

Parameters
• adv – [in] The advertising set the PAwR advertiser belongs to.
• synced_param – [in] Create connection parameters.
• conn_param – [in] Initial connection parameters.
• conn – [out] Valid connection object on success.

Returns
Zero on success or (negative) error code on failure.

int bt_conn_le_create_auto(const struct bt_conn_le_create_param *create_param, const struct bt_le_conn_param *conn_param)

Automatically connect to remote devices in the filter accept list.
This uses the Auto Connection Establishment procedure. The procedure will continue until a single connection is established or the procedure is stopped through bt_conn_create_auto_stop. To establish connections to all devices in the the filter accept list the procedure should be started again in the connected callback after a new connection has been established.

Parameters
• create_param – Create connection parameters
• conn_param – Initial connection parameters.
Returns
Zero on success or (negative) error code on failure.

Returns
-ENOMEM No free connection object available.

int bt_conn_create_auto_stop(void)
Stop automatic connect creation.

Returns
Zero on success or (negative) error code on failure.

int bt_le_set_auto_conn(const bt_addr_le_t *addr, const struct bt_le_conn_param *param)
Automatically connect to remote device if it's in range.

This function enables/disables automatic connection initiation. Every time the device loses the connection with peer, this connection will be re-established if connectable advertisement from peer is received.

Note: Auto connect is disabled during explicit scanning.

Parameters
• addr – Remote Bluetooth address.
• param – If non-NULL, auto connect is enabled with the given parameters. If NULL, auto connect is disabled.

Returns
Zero on success or error code otherwise.

int bt_conn_set_security(struct bt_conn *conn, bt_security_t sec)
Set security level for a connection.

This function enable security (encryption) for a connection. If the device has bond information for the peer with sufficiently strong key encryption will be enabled. If the connection is already encrypted with sufficiently strong key this function does nothing.

If the device has no bond information for the peer and is not already paired then the pairing procedure will be initiated. Note that sec has no effect on the security level selected for the pairing process. The selection is instead controlled by the values of the registered bt_conn_auth_cb. If the device has bond information or is already paired and the keys are too weak then the pairing procedure will be initiated.

This function may return an error if the required level of security defined using sec is not possible to achieve due to local or remote device limitation (e.g., input output capabilities), or if the maximum number of paired devices has been reached.

This function may return an error if the pairing procedure has already been initiated by the local device or the peer device.

Note: When CONFIG_BT_SMP_SC_ONLY is enabled then the security level will always be level 4.

Note: When CONFIG_BT_SMP_OOB_LEGACY_PAIR_ONLY is enabled then the security level will always be level 3.
When BT_SECURITY_FORCE_PAIR within sec is enabled then the pairing procedure will always be initiated.

Parameters
- conn – Connection object.
- sec – Requested minimum security level.

Returns
0 on success or negative error

bt_security_t bt_conn_get_security(const struct bt_conn *conn)
Get security level for a connection.

Returns
Connection security level

uint8_t bt_conn_enc_key_size(const struct bt_conn *conn)
Get encryption key size.
This function gets encryption key size. If there is no security (encryption) enabled 0 will be returned.

Parameters
- conn – Existing connection object.

Returns
Encryption key size.

void bt_conn_cb_register(struct bt_conn_cb *cb)
Register connection callbacks.

Register callbacks to monitor the state of connections.

Parameters
- cb – Callback struct. Must point to memory that remains valid.

int bt_conn_cb_unregister(struct bt_conn_cb *cb)
Unregister connection callbacks.

Unregister the state of connections callbacks.

Parameters
- cb – Callback struct point to memory that remains valid.

Return values
- 0 – Success
- -EINVAL – If cb is NULL
- -ENOENT – if cb was not registered

void bt_set_bondable(bool enable)
Enable/disable bonding.
Set/clear the Bonding flag in the Authentication Requirements of SMP Pairing Request/Response data. The initial value of this flag depends on BT_BONDABLE Kconfig setting. For the vast majority of applications calling this function shouldn’t be needed.

Parameters
- enable – Value allowing/disallowing to be bondable.
int bt_conn_set_bondable(struct bt_conn *conn, bool enable)
Set/clear the bonding flag for a given connection.

Set/clear the Bonding flag in the Authentication Requirements of SMP Pairing Request/Response data for a given connection.

The bonding flag for a given connection cannot be set/cleared if security procedures in the SMP module have already started. This function can be called only once per connection.

If the bonding flag is not set/cleared for a given connection, the value will depend on global configuration which is set using bt_set_bondable. The default value of the global configuration is defined using CONFIG_BT_BONDABLE Kconfig option.

**Parameters**
- conn – Connection object.
- enable – Value allowing/disallowing to be bondable.

void bt_le_oob_set_sc_flag(bool enable)
Allow/disallow remote LE SC OOB data to be used for pairing.

Set/clear the OOB data flag for LE SC SMP Pairing Request/Response data.

**Parameters**
- enable – Value allowing/disallowing remote LE SC OOB data.

void bt_le_oob_set_legacy_flag(bool enable)
Allow/disallow remote legacy OOB data to be used for pairing.

Set/clear the OOB data flag for legacy SMP Pairing Request/Response data.

**Parameters**
- enable – Value allowing/disallowing remote legacy OOB data.

int bt_le_oob_set_legacy_tk(struct bt_conn *conn, const uint8_t *tk)
Set OOB Temporary Key to be used for pairing.

This function allows to set OOB data for the LE legacy pairing procedure. The function should only be called in response to the oob_data_request() callback provided that the legacy method is user pairing.

**Parameters**
- conn – Connection object
- tk – Pointer to 16 byte long TK array

**Returns**
Zero on success or -EINVAL if NULL

int bt_le_oob_set_sc_data(struct bt_conn *conn, const struct bt_le_oob_sc_data *oobd_local, const struct bt_le_oob_sc_data *oobd_remote)
Set OOB data during LE Secure Connections (SC) pairing procedure.

This function allows to set OOB data during the LE SC pairing procedure. The function should only be called in response to the oob_data_request() callback provided that LE SC method is used for pairing.

The user should submit OOB data according to the information received in the callback. This may yield three different configurations: with only local OOB data present, with only remote OOB data present or with both local and remote OOB data present.

**Parameters**
- conn – Connection object
• **oobd_local** – Local OOB data or NULL if not present
• **oobd_remote** – Remote OOB data or NULL if not present

**Returns**
Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_le_oob_get_sc_data( struct bt_conn *conn, const struct bt_le_oob_sc_data **oobd_local, const struct bt_le_oob_sc_data **oobd_remote)
```

Get OOB data used for LE Secure Connections (SC) pairing procedure. This function allows to get OOB data during the LE SC pairing procedure that were set by the `bt_le_oob_set_sc_data()` API.

**Note:** The OOB data will only be available as long as the connection object associated with it is valid.

**Parameters**
- **conn** – Connection object
- **oobd_local** – Local OOB data or NULL if not set
- **oobd_remote** – Remote OOB data or NULL if not set

**Returns**
Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_passkey_set( unsigned int passkey)
```

Set a fixed passkey to be used for pairing. This API is only available when the CONFIG_BT_FIXED_PASSKEY configuration option has been enabled.

Sets a fixed passkey to be used for pairing. If set, the pairing_confirm() callback will be called for all incoming pairings.

**Parameters**
- **passkey** – A valid passkey (0 - 999999) or BT_PASSKEY_INVALID to disable a previously set fixed passkey.

**Returns**
0 on success or a negative error code on failure.

```c
int bt_conn_auth_cb_register( const struct bt_conn_auth_cb *cb)
```

Register authentication callbacks.

Register callbacks to handle authenticated pairing. Passing NULL unregisters a previous callbacks structure.

**Parameters**
- **cb** – Callback struct.

**Returns**
Zero on success or negative error code otherwise

```c
int bt_conn_auth_cb_overlay( struct bt_conn *conn, const struct bt_conn_auth_cb *cb)
```

Overlay authentication callbacks used for a given connection.

This function can be used only for Bluetooth LE connections. The CONFIG_BT_SMP must be enabled for this function.
The authentication callbacks for a given connection cannot be overlaid if security procedures in the SMP module have already started. This function can be called only once per connection.

**Parameters**

- `conn` – Connection object.
- `cb` – Callback struct.

**Returns**

Zero on success or negative error code otherwise

```c
int bt_conn_auth_info_cb_register(struct bt_conn_auth_info_cb *cb)
```

Register callbacks to get authenticated pairing information. Multiple registrations can be done.

**Parameters**

- `cb` – Callback struct.

**Returns**

Zero on success or negative error code otherwise

```c
int bt_conn_auth_info_cb_unregister(struct bt_conn_auth_info_cb *cb)
```

Unregister callbacks to stop getting authenticated pairing information.

**Parameters**

- `cb` – Callback struct.

**Returns**

Zero on success or negative error code otherwise

```c
int bt_conn_auth_passkey_entry(struct bt_conn *conn, unsigned int passkey)
```

Reply with entered passkey.

This function should be called only after `passkey_entry` callback from `bt_conn_auth_cb` structure was called.

**Parameters**

- `conn` – Connection object.
- `passkey` – Entered passkey.

**Returns**

Zero on success or negative error code otherwise

```c
int bt_conn_auth_keypress_notify(struct bt_conn *conn, enum bt_conn_auth_keypress type)
```

Send Passkey Keypress Notification during pairing.

This function may be called only after `passkey_entry` callback from `bt_conn_auth_cb` structure was called.

Requires `CONFIG_BT_PASSKEY_KEYPRESS`.

**See also:**

`bt_conn_auth_keypress`.

**Parameters**

- `conn` – Destination for the notification.
- type – What keypress event type to send.

**Return values**
- 0 – Success
- -EINVAL – Improper use of the API.
- -ENOMEM – Failed to allocate.
- -ENOBUFS – Failed to allocate.

```c
int bt_conn_auth_cancel(struct bt_conn *conn)
```
Cancel ongoing authenticated pairing.
This function allows to cancel ongoing authenticated pairing.

**Parameters**
- conn – Connection object.

**Returns**
Zero on success or negative error code otherwise

```c
int bt_conn_auth_passkey_confirm(struct bt_conn *conn)
```
Reply if passkey was confirmed to match by user.
This function should be called only after passkey_confirm callback from
`bt_conn_auth_cb` structure was called.

**Parameters**
- conn – Connection object.

**Returns**
Zero on success or negative error code otherwise

```c
int bt_conn_auth_pairing_confirm(struct bt_conn *conn)
```
Reply if incoming pairing was confirmed by user.
This function should be called only after pairing_confirm callback from
`bt_conn_auth_cb` structure was called if user confirmed incoming pairing.

**Parameters**
- conn – Connection object.

**Returns**
Zero on success or negative error code otherwise

```c
int bt_conn_auth_pincode_entry(struct bt_conn *conn, const char *pin)
```
Reply with entered PIN code.
This function should be called only after PIN code callback from `bt_conn_auth_cb` structure was called. It's for legacy 2.0 devices.

**Parameters**
- conn – Connection object.
- pin – Entered PIN code.

**Returns**
Zero on success or negative error code otherwise

```c
struct bt_conn *bt_conn_create_br(const bt_addr_t *peer, const struct bt_br_conn_param *param)
```
Initiate an BR/EDR connection to a remote device.
Allows initiate new BR/EDR link to remote peer using its address.
The caller gets a new reference to the connection object which must be released with 
bt_conn_unref() once done using the object.

**Parameters**

- **peer** – Remote address.
- **param** – Initial connection parameters.

**Returns**

Valid connection object on success or NULL otherwise.

```c
struct bt_conn *bt_conn_create_sco(const bt_addr_t *peer)
```

Initiate an SCO connection to a remote device.

Allows initiate new SCO link to remote peer using its address.

The caller gets a new reference to the connection object which must be released with 
bt_conn_unref() once done using the object.

**Parameters**

- **peer** – Remote address.

**Returns**

Valid connection object on success or NULL otherwise.

```c
struct bt_conn *bt_conn_create_sco(const bt_addr_t *peer)
```

**Public Members**

```c
tuint8_t rx_phy
```

Connection transmit PHY.

```c
struct bt_conn_le_phy_info
```

**Public Members**

```c
uint16_t options
```

Connection PHY options.

```c
uint8_t pref_tx_phy
```

Bitmask of preferred transmit PHYS.

```c
uint8_t pref_rx_phy
```

Bitmask of preferred receive PHYS.

```c
struct bt_conn_le_data_len_info
```

**Public Members**

```c
#include <conn.h> Connection data length information for LE connections.
```

6.1. Bluetooth
Public Members

uint16_t tx_max_len
  Maximum Link Layer transmission payload size in bytes.

uint16_t tx_max_time
  Maximum Link Layer transmission payload time in us.

uint16_t rx_max_len
  Maximum Link Layer reception payload size in bytes.

uint16_t rx_max_time
  Maximum Link Layer reception payload time in us.

struct bt_conn_le_data_len_param
  #include <conn.h> Connection data length parameters for LE connections.

Public Members

uint16_t tx_max_len
  Maximum Link Layer transmission payload size in bytes.

uint16_t tx_max_time
  Maximum Link Layer transmission payload time in us.

struct bt_conn_le_info
  #include <conn.h> LE Connection Info Structure.

Public Members

const bt_addr_le_t *src
  Source (Local) Identity Address.

const bt_addr_le_t *dst
  Destination (Remote) Identity Address or remote Resolvable Private Address (RPA) before identity has been resolved.

const bt_addr_le_t *local
  Local device address used during connection setup.

const bt_addr_le_t *remote
  Remote device address used during connection setup.

uint16_t interval
  Connection interval.
uint16_t latency
   Connection peripheral latency.

uint16_t timeout
   Connection supervision timeout.

struct bt_conn_br_info
   #include <conn.h> BR/EDR Connection Info Structure.

   Public Members

   const bt_addr_t *dst
      Destination (Remote) BR/EDR address.

struct bt_security_info
   #include <conn.h> Security Info Structure.

   Public Members

   bt_security_t level
      Security Level.

   uint8_t enc_key_size
      Encryption Key Size.

   enum bt_security_flag flags
      Flags.

struct bt_conn_info
   #include <conn.h> Connection Info Structure.

   Public Members

   enum bt_conn_type type
      Connection Type.

   uint8_t role
      Connection Role.

   uint8_t id
      Which local identity the connection was created with.

struct bt_conn_le_info le
   LE Connection specific Info.
struct *bt_conn_br_info* \texttt{br}
BR/EDR Connection specific Info.

union *bt_conn_info*
Connection Type specific Info.

enum *bt_conn_state* \texttt{state}
Connection state.

struct *bt_security_info* \texttt{security}
Security specific info.

struct *bt_conn_le_remote_info*  
\texttt{#include <conn.h>} LE Connection Remote Info Structure.

**Public Members**

const uint8_t *features
Remote LE feature set (bitmask).

struct *bt_conn_br_remote_info*  
\texttt{#include <conn.h>} BR/EDR Connection Remote Info structure.

**Public Members**

const uint8_t *features
Remote feature set (pages of bitmasks).

uint8_t num_pages  
Number of pages in the remote feature set.

struct *bt_conn_remote_info*  
\texttt{#include <conn.h>} Connection Remote Info Structure.

**Note:** The version, manufacturer and subversion fields will only contain valid data if \texttt{CONFIG_BT_REMOTE_VERSION} is enabled.

**Public Members**

uint8_t type
Connection Type.

uint8_t version
Remote Link Layer version.
`uint16_t manufacturer`  
Remote manufacturer identifier.

`uint16_t subversion`  
Per-manufacturer unique revision.

`struct bt_conn_le_remote_info le`  
LE connection remote info.

`struct bt_conn_br_remote_info br`  
BR/EDR connection remote info.

`struct bt_conn_le_tx_power`  
`#include <conn.h>` LE Transmit Power Level Structure.

**Public Members**

`uint8_t phy`  
Input: 1M, 2M, Coded S2 or Coded S8.

`int8_t current_level`  
Output: current transmit power level.

`int8_t max_level`  
Output: maximum transmit power level.

`struct bt_conn_le_tx_power_report`  
`#include <conn.h>` LE Transmit Power Reporting Structure.

**Public Members**

`uint8_t reason`  
Reason for Transmit power reporting, as documented in Core Spec.  
Version 5.4 Vol. 4, Part E, 7.7.65.33.

`enum bt_conn_le_tx_power_phy phy`  
Phy of Transmit power reporting.

`int8_t tx_power_level`  
Transmit power level.

- 0XX - Transmit power level  
  - Range: -127 to 20  
  - Units: dBm
- 0x7E - Remote device is not managing power levels on this PHY.
- 0x7F - Transmit power level is not available
uint8_t tx_power_level_flag
    Bit 0: Transmit power level is at minimum level.
    Bit 1: Transmit power level is at maximum level.

int8_t delta
    Change in transmit power level.
    - 0xXX - Change in transmit power level (positive indicates increased power, negative indicates decreased power, zero indicates unchanged) Units: dB
    - 0x7F - Change is not available or is out of range.

struct bt_conn_le_create_param
    #include <conn.h>

Public Members

uint32_t options
    Bit-field of create connection options.

uint16_t interval
    Scan interval (N * 0.625 ms)

uint16_t window
    Scan window (N * 0.625 ms)

uint16_t interval_coded
    Scan interval LE Coded PHY (N * 0.625 MS)
    Set zero to use same as LE 1M PHY scan interval

uint16_t window_coded
    Scan window LE Coded PHY (N * 0.625 MS)
    Set zero to use same as LE 1M PHY scan window.

uint16_t timeout
    Connection initiation timeout (N * 10 MS)
    Set zero to use the default CONFIG_BT_CREATE_CONN_TIMEOUT timeout.

Note: Unused in bt_conn_le_create_auto

struct bt_conn_le_create_synced_param
    #include <conn.h>

Public Members

const bt_addr_le_t *peer

Remote address.

The peer must be synchronized to the PAwR train.

uint8_t subevent

The subevent where the connection will be initiated.

struct bt_conn_cb

#include <conn.h> Connection callback structure.

This structure is used for tracking the state of a connection. It is registered with the help of the bt_conn_cb_register() API. It’s permissible to register multiple instances of this bt_conn_cb type, in case different modules of an application are interested in tracking the connection state. If a callback is not of interest for an instance, it may be set to NULL and will as a consequence not be used for that instance.

Public Members

void (*connected)(struct bt_conn *conn, uint8_t err)

A new connection has been established.

This callback notifies the application of a new connection. In case the err parameter is non-zero it means that the connection establishment failed.

err can mean either of the following:

- BT_HCI_ERR_UNKNOWN_CONN_ID Creating the connection started by bt_conn_le_create was canceled either by the user through bt_conn_disconnect or by the timeout in the host through bt_conn_le_create_param timeout parameter, which defaults to CONFIG_BT_CREATE_CONN_TIMEOUT seconds.
- BT_HCI_ERR_ADV_TIMEOUT High duty cycle directed connectable advertiser started by bt_le_adv_start failed to be connected within the timeout.

**Note:** If the connection was established from an advertising set then the advertising set cannot be restarted directly from this callback. Instead use the connected callback of the advertising set.

**Param conn**
New connection object.

**Param err**
HCI error. Zero for success, non-zero otherwise.

void (*disconnected)(struct bt_conn *conn, uint8_t reason)

A connection has been disconnected.

This callback notifies the application that a connection has been disconnected.

When this callback is called the stack still has one reference to the connection object. If the application in this callback tries to start either a connectable advertiser or create a new connection this might fail because there are no free connection objects available. To avoid this issue it is recommended to either start connectable advertise or create a new connection using k_work_submit or increase CONFIG_BT_MAX_CONN.

**Param conn**
Connection object.
Param reason
BT_HCI_ERR_ reason for the disconnection.

void (*recycled)(void)
A connection object has been returned to the pool.
This callback notifies the application that it might be able to allocate a connection
object. No guarantee, first come, first serve.
Use this to e.g. re-start connectable advertising or scanning.
Treat this callback as an ISR, as it originates from bt_conn_unref which is used by
the BT stack. Making Bluetooth API calls in this context is error-prone and strongly
discouraged.

bool (*le_param_req)(struct bt_conn *conn, struct bt_le_conn_param *param)
LE connection parameter update request.
This callback notifies the application that a remote device is requesting to update
the connection parameters. The application accepts the parameters by returning
true, or rejects them by returning false. Before accepting, the application may also
adjust the parameters to better suit its needs.
It is recommended for an application to have just one of these callbacks for sim-
Plicity. However, if an application registers multiple it needs to manage the poten-
tially different requirements for each callback. Each callback gets the parameters
as returned by previous callbacks, i.e. they are not necessarily the same ones as
the remote originally sent.
If the application does not have this callback then the default is to accept the pa-
rameters.

Param conn
Connection object.

Param param
Proposed connection parameters.

Return
true to accept the parameters, or false to reject them.

void (*le_param_updated)(struct bt_conn *conn, uint16_t interval, uint16_t latency,
uint16_t timeout)
The parameters for an LE connection have been updated.
This callback notifies the application that the connection parameters for an LE
connection have been updated.

Param conn
Connection object.

Param interval
Connection interval.

Param latency
Connection latency.

Param timeout
Connection supervision timeout.

void (*identity_resolved)(struct bt_conn *conn, const bt_addr_le_t *rpa, const
bt_addr_le_t *identity)
Remote Identity Address has been resolved.
This callback notifies the application that a remote Identity Address has been re-

Param conn
Connection object.

Param rpa
Resolvable Private Address.

Param identity
Identity Address.

```c
void (*security_changed)(struct bt_conn *conn, bt_security_t level, enum bt_security_err err)
```

The security level of a connection has changed.
This callback notifies the application that the security of a connection has changed.
The security level of the connection can either have been increased or remain unchanged. An increased security level means that the pairing procedure has been performed or the bond information from a previous connection has been applied. If the security level remains unchanged this means that the encryption key has been refreshed for the connection.

Param conn
Connection object.

Param level
New security level of the connection.

Param err

```c
void (*remote_info_available)(struct bt_conn *conn, struct bt_conn_remote_info *remote_info)
```

Remote information procedures has completed.
This callback notifies the application that the remote information has been retrieved from the remote peer.

Param conn
Connection object.

Param remote_info
Connection information of remote device.

```c
void (*le_phy_updated)(struct bt_conn *conn, struct bt_conn_le_phy_info *param)
```

The PHY of the connection has changed.
This callback notifies the application that the PHY of the connection has changed.

Param conn
Connection object.

Param info
Connection LE PHY information.

```c
void (*le_data_len_updated)(struct bt_conn *conn, struct bt_conn_le_data_len_info *info)
```

The data length parameters of the connection has changed.
This callback notifies the application that the maximum Link Layer payload length or transmission time has changed.

Param conn
Connection object.

Param info
Connection data length information.

struct bt_conn_oob_info
#include <conn.h> Info Structure for OOB pairing.
Public Types

Type of OOB pairing method.

Values:

enumerator BT_CONN_OOB_LE_LEGACY
    LE legacy pairing.

enumerator BT_CONN_OOB_LE_SC
    LE SC pairing.

Public Members

enum bt_conn_oob_info type
    Type of OOB pairing method.

enum bt_conn_oob_info oob_config
    OOB data configuration.

struct bt_conn_oob_info lesc
    LE Secure Connections OOB pairing parameters.

struct bt_conn_pairing_feat
    #include <conn.h> Pairing request and pairing response info structure.
    This structure is the same for both smp_pairing_req and smp_pairing_rsp and a subset
    of the packet data, except for the initial Code octet. It is documented in Core Spec. Vol.
    3, Part H, 3.5.1 and 3.5.2.

Public Members

uint8_t io_capability
    IO Capability, Core Spec.
    Vol 3, Part H, 3.5.1, Table 3.4

uint8_t oob_data_flag
    OOB data flag, Core Spec.
    Vol 3, Part H, 3.5.1, Table 3.5

uint8_t auth_req
    AuthReq, Core Spec.
    Vol 3, Part H, 3.5.1, Fig. 3.3

uint8_t max_enc_key_size
    Maximum Encryption Key Size, Core Spec.
    Vol 3, Part H, 3.5.1
uint8_t init_key_dist
    Initiator Key Distribution/Generation, Core Spec.
    Vol 3, Part H, 3.6.1, Fig. 3.11

uint8_t resp_key_dist
    Responder Key Distribution/Generation, Core Spec.
    Vol 3, Part H 3.6.1, Fig. 3.11

struct bt_conn_auth_cb
    #include <conn.h> Authenticated pairing callback structure.

Public Members

enum bt_security_err (*pairing_accept)(struct bt_conn *conn, const struct bt_conn_pairing_feat *const feat)

    Query to proceed incoming pairing or not.
    On any incoming pairing req/rsp this callback will be called for the application to
decide whether to allow for the pairing to continue.
The pairing info received from the peer is passed to assist making the decision.
As this callback is synchronous the application should return a response value
immediately. Otherwise it may affect the timing during pairing. Hence, this infor-
mation should not be conveyed to the user to take action.
The remaining callbacks are not affected by this, but do notice that other callbacks
can be called during the pairing. Eg. if pairing_confirm is registered both will be
called for Just-Works pairings.
This callback may be unregistered in which case pairing continues as if the Kconfig
flag was not set.
This callback is not called for BR/EDR Secure Simple Pairing (SSP).
    
Param conn
    Connection where pairing is initiated.
Param feat
    Pairing req/rsp info.

void (*passkey_display)(struct bt_conn *conn, unsigned int passkey)

    Display a passkey to the user.
    When called the application is expected to display the given passkey to the user,
with the expectation that the passkey will then be entered on the peer device. The
passkey will be in the range of 0 - 999999, and is expected to be padded with zeroes
so that six digits are always shown. E.g. the value 37 should be shown as 000037.
This callback may be set to NULL, which means that the local device lacks the abil-
ity do display a passkey. If set to non-NULL the cancel callback must also be pro-
vided, since this is the only way the application can find out that it should stop
displaying the passkey.
    
Param conn
    Connection where pairing is currently active.
Param passkey
    Passkey to show to the user.
void (*passkey_entry)(struct bt_conn *conn)

Request the user to enter a passkey.

When called the user is expected to enter a passkey. The passkey must be in the range of 0 - 999999, and should be expected to be zero-padded, as that's how the peer device will typically be showing it (e.g. 37 would be shown as 000037).

Once the user has entered the passkey its value should be given to the stack using the `bt_conn_auth_passkey_entry()` API.

This callback may be set to NULL, which means that the local device lacks the ability to enter a passkey. If set to non-NULL the cancel callback must also be provided, since this is the only way the application can find out that it should stop requesting the user to enter a passkey.

**Param conn**
Connection where pairing is currently active.

void (*passkey_confirm)(struct bt_conn *conn, unsigned int passkey)

Request the user to confirm a passkey.

When called the user is expected to confirm that the given passkey is also shown on the peer device. The passkey will be in the range of 0 - 999999, and should be zero-padded to always be six digits (e.g. 37 would be shown as 000037).

Once the user has confirmed the passkey to match, the `bt_conn_auth_passkey_confirm()` API should be called. If the user concluded that the passkey doesn't match the `bt_conn_auth_cancel()` API should be called.

This callback may be set to NULL, which means that the local device lacks the ability to confirm a passkey. If set to non-NULL the cancel callback must also be provided, since this is the only way the application can find out that it should stop requesting the user to confirm a passkey.

**Param conn**
Connection where pairing is currently active.

**Param passkey**
Passkey to be confirmed.

void (*oob_data_request)(struct bt_conn *conn, struct bt_conn_oob_info *info)

Request the user to provide Out of Band (OOB) data.

When called the user is expected to provide OOB data. The required data are indicated by the information structure.

For LE Secure Connections OOB pairing, the user should provide local OOB data, remote OOB data or both depending on their availability. Their value should be given to the stack using the `bt_le_oob_set_sc_data()` API.

This callback must be set to non-NULL in order to support OOB pairing.

**Param conn**
Connection where pairing is currently active.

**Param info**
OOB pairing information.

void (*cancel)(struct bt_conn *conn)

Cancel the ongoing user request.

This callback will be called to notify the application that it should cancel any previous user request (passkey display, entry or confirmation).

This may be set to NULL, but must always be provided whenever the passkey_display, passkey_entry passkey_confirm or pairing_confirm callback has
been provided.

**Param conn**
Connection where pairing is currently active.

```c
typedef struct {
    void (*pairing_confirm)(struct bt_conn *conn);
    void (*pincode_entry)(struct bt_conn *conn, bool highsec);
    void (*pairing_complete)(struct bt_conn *conn, bool bonded);
    void (*pairing_failed)(struct bt_conn *conn, enum bt_security_err reason);
} bt_conn_auth_info_cb;
```

```c
#include <conn.h>
```

**Public Members**

void (*pairing_complete)(struct bt_conn *conn, bool bonded)

- notify that pairing procedure was complete.

This callback notifies the application that the pairing procedure has been completed.

**Param conn**
Connection object.

**Param bonded**
Bond information has been distributed during the pairing procedure.

```c
#include "conn.h"
```

6.1. Bluetooth
Param reason
Pairing failed reason

```c
void (*bond_deleted)(uint8_t id, const bt_addr_le_t *peer)
```
Notify that bond has been deleted.
This callback notifies the application that the bond information for the remote peer has been deleted

**Param id**
Which local identity had the bond.

**Param peer**
Remote address.

```c
sys_snode_t node
```
Internally used field for list handling.

```c
struct bt_br_conn_param
```

Include `<conn.h>` Connection parameters for BR/EDR connections.

### Bluetooth Controller

**API Reference**

**group bt_ctrl**
Bluetooth Controller.

**Functions**

```c
void bt_ctlr_set_public_addr(const uint8_t *addr)
```
Set public address for controller.
Should be called before `bt_enable()`.

**Parameters**

- `addr` – Public address

### Bluetooth Coordinated Sets

**API Reference**

**group bt_gatt_csip**

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Coordinated Set Identification Profile (CSIP)

- [Experimental] Users should note that the APIs can change as a part of ongoing development.
Defines

**BT_CSIP_SET_COORDINATOR_DISCOVER_TIMER_VALUE**
Recommended timer for member discovery.

**BT_CSIP_SET_COORDINATOR_MAX_CSIS_INSTANCES**

**BT_CSIP_READ_SIRK_REQ_RSP_ACCEPT**
Accept the request to read the SIRK as plaintext.

**BT_CSIP_READ_SIRK_REQ_RSP_ACCEPT_ENC**
Accept the request to read the SIRK, but return encrypted SIRK.

**BT_CSIP_READ_SIRK_REQ_RSP_REJECT**
Reject the request to read the SIRK.

**BT_CSIP_READ_SIRK_REQ_RSP_OOB_ONLY**
SIRK is available only via an OOB procedure.

**BT_CSIP_SET_SIRK_SIZE**
Size of the Set Identification Resolving Key (SIRK)

**BT_CSIP_RSI_SIZE**
Size of the Resolvable Set Identifier (RSI)

**BT_CSIP_ERROR_LOCK_DENIED**
Service is already locked.

**BT_CSIP_ERROR_LOCK_RELEASE_DENIED**
Service is not locked.

**BT_CSIP_ERROR_LOCK_INVAL_VALUE**
Invalid lock value.

**BT_CSIP_ERROR_SIRK_OOB_ONLY**
SIRK only available out-of-band.

**BT_CSIP_ERROR_LOCK_ALREADY_GRANTED**
Client is already owner of the lock.

**BT_CSIP_DATA_RSI(_rsi)**
Helper to declare *bt_data* array including RSI.
This macro is mainly for creating an array of struct *bt_data* elements which is then passed to e.g. *bt_le_ext_adv_start()*.  

**Parameters**
- _rsi – Pointer to the RSI value
typedef void (*bt_csip_set_coordinator_discover_cb)(struct bt_conn *conn, const struct \nbt_csip_set_coordinator_set_member *member, int err, size_t set_count)
Callback for discovering Coordinated Set Identification Services.

Param conn
  Pointer to the remote device.

Param member
  Pointer to the set member.

Param err
  0 on success, or an errno value on error.

Param set_count
  Number of sets on the member.

typedef void (*bt_csip_set_coordinator_lock_set_cb)(int err)
Callback for locking a set across one or more devices.

Param err
  0 on success, or an errno value on error.

typedef void (*bt_csip_set_coordinator_lock_changed_cb)(struct \nbtparam csis_inst *inst, bool locked)
Callback when the lock value on a set of a connected device changes.

Param inst
  The Coordinated Set Identification Service instance that was changed.

Param locked
  Whether the lock is locked or release.

Return
  int Return 0 on success, or an errno value on error.

typedef void (*bt_csip_set_coordinator_ordered_access_cb_t)(const struct \nbtparam set_info *set_info, int err, bool locked, struct \nbtparam set_member *member)
Callback for bt_csip_set_coordinator_ordered_access()
If any of the set members supplied to bt_csip_set_coordinator_ordered_access() is in \nthe locked state, this will be called with locked true and member will be the locked \nmember, and the ordered access procedure is cancelled. Likewise, if any error occurs, \nthe procedure will also be aborted.

Param set_info
  Pointer to the a specific set_info struct.

Param err
  Error value. 0 on success, GATT error or errno on fail.

Param locked
  Whether the lock is locked or release.

Param member
  The locked member if locked is true, otherwise NULL.

typedef bool (*bt_csip_set_coordinator_ordered_access_t)(const struct \nbtparam set_info *set_info, struct bt_csip_set_coordinator_set_member *members[], size_t count)
Callback function definition for `bt_csip_set_coordinator_ordered_access()

**Param set_info**
Pointer to the a specific set_info struct.

**Param members**
Array of members ordered by rank. The procedure shall be done on the members in ascending order.

**Param count**
Number of members in members.

**Return**
true if the procedures can be successfully done, or false to stop the procedure.

**Functions**

```c
void *bt_csip_set_member_svc_decl_get(const struct bt_csip_set_member_svc_inst *svc_inst)
```

Get the service declaration attribute.

The first service attribute can be included in any other GATT service.

**Parameters**

- **svc_inst** – Pointer to the Coordinated Set Identification Service.

**Returns**
The first CSIS attribute instance.

```c
int bt_csip_set_member_register(const struct bt_csip_set_member_register_param *param, struct bt_csip_set_member_svc_inst **svc_inst)
```

Register a Coordinated Set Identification Service instance.

This will register and enable the service and make it discoverable by clients.

This shall only be done as a server.

**Parameters**

- **param** – Coordinated Set Identification Service register parameters.
- **svc_inst** – [out] Pointer to the registered Coordinated Set Identification Service.

**Returns**
0 if success, errno on failure.

```c
int bt_csip_set_member_unregister(struct bt_csip_set_member_svc_inst *svc_inst)
```

Unregister a Coordinated Set Identification Service instance.

This will unregister and disable the service instance.

**Parameters**

- **svc_inst** – Pointer to the registered Coordinated Set Identification Service.

**Returns**
0 if success, errno on failure.
void bt_csip_set_member_print_sirk(const struct bt_csip_set_member_svc_inst *svc_inst)

Print the SIRK to the debug output.

Parameters
• svc_inst – Pointer to the Coordinated Set Identification Service.

int bt_csip_set_member_generate_rsi(const struct bt_csip_set_member_svc_inst *svc_inst, uint8_t rsi[6])

Generate the Resolvable Set Identifier (RSI) value.
This will generate RSI for given svc_inst instance.

Parameters
• svc_inst – Pointer to the Coordinated Set Identification Service.
• rsi – Pointer to the 6-octet newly generated RSI data in little-endian.

Returns
int 0 if on success, errno on error.

int bt_csip_set_member_lock(struct bt_csip_set_member_svc_inst *svc_inst, bool lock, bool force)

Locks a specific Coordinated Set Identification Service instance on the server.

Parameters
• svc_inst – Pointer to the Coordinated Set Identification Service.
• lock – If true lock the set, if false release the set.
• force – This argument only have meaning when lock is false (release) and will force release the lock, regardless of who took the lock.

Returns
0 on success, GATT error on error.

int bt_csip_set_coordinator_discover(struct bt_conn *conn)

Initialise the csip_set_coordinator instance for a connection.
This will do a discovery on the device and prepare the instance for following commands.

Parameters
• conn – Pointer to remote device to perform discovery on.

Returns
int Return 0 on success, or an errno value on error.

bool bt_csip_set_coordinator_is_set_member(const uint8_t set_sirk[16], struct bt_data *data)

Check if advertising data indicates a set member.

Parameters
• set_sirk – The SIRK of the set to check against
• data – The advertising data

Returns
true if the advertising data indicates a set member; false otherwise

int bt_csip_set_coordinator_register_cb(struct bt_csip_set_coordinator_cb *cb)

Registers callbacks for csip_set_coordinator.

Parameters
cb – Pointer to the callback structure.

**Returns**
Return 0 on success, or an errno value on error.

```c
int bt_csip_set_coordinator_ordered_access(const struct bt_csip_set_coordinator_set_member *members[], uint8_t count, const struct bt_csip_set_coordinator_set_info *set_info, bt_csip_set_coordinator_ordered_access_t cb)
```

Access Coordinated Set devices in an ordered manner as a client.

This function will read the lock state of all devices and if all devices are in the unlocked state, then cb will be called with the same members as provided by members, but where the members are ordered by rank (if present). Once this procedure is finished or an error occurs, bt_csip_set_coordinator_cb::ordered_access will be called.

This procedure only works if all the members have the lock characteristic, and all either has rank = 0 or unique ranks.

If any of the members are in the locked state, the procedure will be cancelled.

This can only be done on members that are bonded.

**Parameters**
- members – Array of set members to access.
- count – Number of set members in members.
- set_info – Pointer to the a specific set_info struct, as a member may be part of multiple sets.
- cb – The callback function to be called for each member.

```c
int bt_csip_set_coordinator_lock(const struct bt_csip_set_coordinator_set_member **members, uint8_t count, const struct bt_csip_set_coordinator_set_info *set_info)
```

Lock an array of set members.

The members will be locked starting from lowest rank going up.

TODO: If locking fails, the already locked members will not be unlocked.

**Parameters**
- members – Array of set members to lock.
- count – Number of set members in members.
- set_info – Pointer to the a specific set_info struct, as a member may be part of multiple sets.

**Returns**
Return 0 on success, or an errno value on error.

```c
int bt_csip_set_coordinator_release(const struct bt_csip_set_coordinator_set_member **members, uint8_t count, const struct bt_csip_set_coordinator_set_info *set_info)
```

Release an array of set members.

The members will be released starting from highest rank going down.

**Parameters**
- members – Array of set members to lock.
- count – Number of set members in members.
• set_info – Pointer to the a specific set_info struct, as a member may be part of multiple sets.

**Returns**
Return 0 on success, or an errno value on error.

```c
struct bt_csip_set_member_cb
#include <csip.h> Callback structure for the Coordinated Set Identification Service.
```

**Public Members**

```c
void (*lock_changed)(struct bt_conn *conn, struct bt_csip_set_member_svc_inst *svc_inst, bool locked)
Callback whenever the lock changes on the server.
Param conn
The connection to the client that changed the lock. NULL if server changed it, either by calling `bt_csip_set_member_lock()` or by timeout.
Param svc_inst
Pointer to the Coordinated Set Identification Service.
Param locked
Whether the lock was locked or released.
```

```c
uint8_t (*sirk_read_req)(struct bt_conn *conn, struct bt_csip_set_member_svc_inst *svc_inst)
Request from a peer device to read the sirk.
If this callback is not set, all clients will be allowed to read the SIRK unencrypted.
Param conn
The connection to the client that requested to read the SIRK.
Param svc_inst
Pointer to the Coordinated Set Identification Service.
Return
A BT_CSIP_READ_SIRK_REQ_RSP_* response code.
```

```c
struct bt_csip_set_member_register_param
#include <csip.h> Register structure for Coordinated Set Identification Service.
```

**Public Members**

```c
uint8_t set_size
Size of the set.
If set to 0, the set size characteristic won’t be initialized.
```

```c
uint8_t set_sirk[16]
The unique Set Identity Resolving Key (SIRK)
This shall be unique between different sets, and shall be the same for each set member for each set.
```

```c
bool lockable
Boolean to set whether the set is lockable by clients.
Setting this to false will disable the lock characteristic.
```
uint8_t rank
   Rank of this device in this set.
   If the lockable parameter is set to true, this shall be > 0 and <= to the set_size.
   If the lockable parameter is set to false, this may be set to 0 to disable the rank
   characteristic.

struct bt_csip_set_member_cb *cb
   Pointer to the callback structure.

struct bt_csip_set_coordinator_set_info
   #include <csip.h> Information about a specific set.

Public Members

uint8_t set_sirk[16]
   The 16 octet set Identity Resolving Key (SIRK)
   The Set SIRK may not be exposed by the server over Bluetooth, and may require
   an out-of-band solution.

uint8_t set_size
   The size of the set.
   Will be 0 if not exposed by the server.

uint8_t rank
   The rank of the set on the remote device.
   Will be 0 if not exposed by the server.

bool lockable
   Whether or not the set can be locked on this device.

struct bt_csip_set_coordinator_csis_inst
   #include <csip.h> Struct representing a coordinated set instance on a remote device.
   The values in this struct will be populated during discovery of sets
   (bt_csip_set_coordinator_discover()).

Public Members

void *svc_inst
   Internally used pointer value.

struct bt_csip_set_coordinator_set_member
   #include <csip.h> Struct representing a remote device as a set member.
Public Members

struct bt_csip_set_coordinator_csis_inst insts[0]
   Array of Coordinated Set Identification Service instances for the remote device.

struct bt_csip_set_coordinator_cb
#include <csip.h>

Cryptography

API Reference
group bt_crypto
Cryptography.

Functions

int bt_rand(void *buf, size_t len)
   Generate random data.
   A random number generation helper which utilizes the Bluetooth controller's own RNG.

   Parameters
   • buf – Buffer to insert the random data
   • len – Length of random data to generate

   Returns
   Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error

int bt_encrypt_le(const uint8_t key[16], const uint8_t plaintext[16], uint8_t enc_data[16])
   AES encrypt little-endian data.
   An AES encrypt helper is used to request the Bluetooth controller's own hardware to encrypt the plaintext using the key and returns the encrypted data.

   Parameters
   • key – 128 bit LS byte first key for the encryption of the plaintext
   • plaintext – 128 bit LS byte first plaintext data block to be encrypted
   • enc_data – 128 bit LS byte first encrypted data block

   Returns
   Zero on success or error code otherwise.

int bt_encrypt_be(const uint8_t key[16], const uint8_t plaintext[16], uint8_t enc_data[16])
   AES encrypt big-endian data.
   An AES encrypt helper is used to request the Bluetooth controller's own hardware to encrypt the plaintext using the key and returns the encrypted data.

   Parameters
   • key – 128 bit MS byte first key for the encryption of the plaintext
   • plaintext – 128 bit MS byte first plaintext data block to be encrypted
• `enc_data` – 128 bit MS byte first encrypted data block

**Returns**
Zero on success or error code otherwise.

```c
int bt_ccm_decrypt(const uint8_t key[16], uint8_t nonce[13], const uint8_t *enc_data,
                   size_t len, const uint8_t *aad, size_t aad_len, uint8_t *plaintext, size_t
                   mic_size)
```

Decrypt big-endian data with AES-CCM.


Assumes that the MIC follows directly after the encrypted data.

**Parameters**

- `key` – 128 bit MS byte first key
- `nonce` – 13 byte MS byte first nonce
- `enc_data` – Encrypted data
- `len` – Length of the encrypted data
- `aad` – Additional authenticated data
- `aad_len` – Additional authenticated data length
- `plaintext` – Plaintext buffer to place result in
- `mic_size` – Size of the trailing MIC (in bytes)

**Return values**

- `0` – Successfully decrypted the data.
- `-EINVAL` – Invalid parameters.
- `-EBADMSG` – Authentication failed.

```c
int bt_ccm_encrypt(const uint8_t key[16], uint8_t nonce[13], const uint8_t *plaintext,
                    size_t len, const uint8_t *aad, size_t aad_len, uint8_t *enc_data, size_t
                    mic_size)
```

Encrypt big-endian data with AES-CCM.

Encrypts and generates a MIC from `plaintext` with AES-CCM, as described in [https://tools.ietf.org/html/rfc3610](https://tools.ietf.org/html/rfc3610).

Places the MIC directly after the encrypted data.

**Parameters**

- `key` – 128 bit MS byte first key
- `nonce` – 13 byte MS byte first nonce
- `plaintext` – Plaintext buffer to encrypt
- `len` – Length of the encrypted data
- `aad` – Additional authenticated data
- `aad_len` – Additional authenticated data length
- `enc_data` – Buffer to place encrypted data in
- `mic_size` – Size of the trailing MIC (in bytes)

**Return values**

- `0` – Successfully encrypted the data.

6.1. Bluetooth
Data Buffers

API Reference

group bt_buf

Data buffers.

Defines

BT_BUF_RESERVE

BT_BUF_SIZE(size)
Helper to include reserved HCI data in buffer calculations.

BT_BUF_ACL_SIZE(size)
Helper to calculate needed buffer size for HCI ACL packets.

BT_BUF_EVT_SIZE(size)
Helper to calculate needed buffer size for HCI Event packets.

BT_BUF_CMD_SIZE(size)
Helper to calculate needed buffer size for HCI Command packets.

BT_BUF_ISO_SIZE(size)
Helper to calculate needed buffer size for HCI ISO packets.

BT_BUF_ACL_RX_SIZE
Data size needed for HCI ACL RX buffers.

BT_BUF_EVT_RX_SIZE
Data size needed for HCI Event RX buffers.

BT_BUF_ISO_RX_SIZE

BT_BUF_ISO_RX_COUNT

BT_BUF_RX_SIZE
Data size needed for HCI ACL, HCI ISO or Event RX buffers.

BT_BUF_RX_COUNT
Buffer count needed for HCI ACL, HCI ISO or Event RX buffers.

BT_BUF_CMD_TX_SIZE
Data size needed for HCI Command buffers.

Enums
enum bt_buf_type
    Possible types of buffers passed around the Bluetooth stack.
    
    Values:
    
    enumerator BT_BUF_CMD
        HCI command.
    
    enumerator BT_BUF_EVT
        HCI event.
    
    enumerator BT_BUF_ACL_OUT
        Outgoing ACL data.
    
    enumerator BT_BUF_ACL_IN
        Incoming ACL data.
    
    enumerator BT_BUF_ISO_OUT
        Outgoing ISO data.
    
    enumerator BT_BUF_ISO_IN
        Incoming ISO data.
    
    enumerator BT_BUF_H4
        H:4 data.

Functions

struct net_buf *bt_buf_get_rx(enum bt_buf_type type, k_timeout_t timeout)
    Allocate a buffer for incoming data.
    This will set the buffer type so bt_buf_set_type() does not need to be explicitly called before bt_recv_prio().

    Parameters

    • type – Type of buffer. Only BT_BUF_EVT, BT_BUF_ACL_IN and BT_BUF_ISO_IN are allowed.
    • timeout – Non-negative waiting period to obtain a buffer or one of the special values K_NO_WAIT and K_FOREVER.

    Returns

    A new buffer.

struct net_buf *bt_buf_get_tx(enum bt_buf_type type, k_timeout_t timeout, const void *data, size_t size)
    Allocate a buffer for outgoing data.
    This will set the buffer type so bt_buf_set_type() does not need to be explicitly called before bt_send().

    Parameters

    • type – Type of buffer. Only BT_BUF_CMD, BT_BUF_ACL_OUT or BT_BUF_H4, when operating on H:4 mode, are allowed.
• **timeout** – Non-negative waiting period to obtain a buffer or one of the special values K_NO_WAIT and K_FOREVER.
• **data** – Initial data to append to buffer.
• **size** – Initial data size.

**Returns**
A new buffer.

```c
struct net_buf *bt_buf_get_evt(uint8_t evt, bool discardable, k_timeout_t timeout)
```
Allocate a buffer for an HCI Event.
This will set the buffer type so *bt_buf_set_type()* does not need to be explicitly called before *bt_recv_prio()* or *bt_recv()*.

**Parameters**
• **evt** – HCI event code
• **discardable** – Whether the driver considers the event discardable.
• **timeout** – Non-negative waiting period to obtain a buffer or one of the special values K_NO_WAIT and K_FOREVER.

**Returns**
A new buffer.

```c
static inline void bt_buf_set_type(struct net_buf *buf, enum bt_buf_type type)
```
Set the buffer type.

**Parameters**
• **buf** – Bluetooth buffer
• **type** – The BT_* type to set the buffer to

```c
static inline enum bt_buf_type bt_buf_get_type(struct net_buf *buf)
```
Get the buffer type.

**Parameters**
• **buf** – Bluetooth buffer

**Returns**
The BT_* type to of the buffer

```c
struct bt_buf_data
#include <buf.h> This is a base type for bt_buf user data.
```

**Generic Access Profile (GAP)**

**API Reference**

group **bt_gap**
Generic Access Profile (GAP)

**Defines**
**BT_ID_DEFAULT**

Convenience macro for specifying the default identity.

This helps make the code more readable, especially when only one identity is supported.

**BT_DATA_SERIALIZED_SIZE(data_len)**

Bluetooth data serialized size.

Get the size of a serialized `bt_data` given its data length.

Size of ‘AD Structure’->’Length’ field, equal to 1. Size of ‘AD Structure’->’Data’->’AD Type’ field, equal to 1. Size of ‘AD Structure’->’Data’->’AD Data’ field, equal to `data_len`.

See Core Specification Version 5.4 Vol. 3 Part C, 11, Figure 11.1.

**BT_DATA(_type, _data, _data_len)**

Helper to declare elements of `bt_data` arrays.

This macro is mainly for creating an array of struct `bt_data` elements which is then passed to e.g. `bt_le_adv_start()`.

**Parameters**

- `_type` – Type of advertising data field
- `_data` – Pointer to the data field payload
- `_data_len` – Number of bytes behind the `_data` pointer

**BT_DATA_BYTES(_type, _bytes...)**

Helper to declare elements of `bt_data` arrays.

This macro is mainly for creating an array of struct `bt_data` elements which is then passed to e.g. `bt_le_adv_start()`.

**Parameters**

- `_type` – Type of advertising data field
- `_bytes` – Variable number of single-byte parameters

**BT_LE_ADV_PARAM_INIT(_options, _int_min, _int_max, _peer)**

Initialize advertising parameters.

**Parameters**

- `_options` – Advertising Options
- `_int_min` – Minimum advertising interval
- `_int_max` – Maximum advertising interval
- `_peer` – Peer address, set to NULL for undirected advertising or address of peer for directed advertising.

**BT_LE_ADV_PARAM(_options, _int_min, _int_max, _peer)**

Helper to declare advertising parameters inline.

**Parameters**

- `_options` – Advertising Options
- `_int_min` – Minimum advertising interval
- `_int_max` – Maximum advertising interval
- `_peer` – Peer address, set to NULL for undirected advertising or address of peer for directed advertising.
BT_LE_ADV_CONN_DIR(_peer)

BT_LE_ADV_CONN

BT_LE_ADV_CONN_NAME

BT_LE_ADV_CONN_NAME_AD

BT_LE_ADV_CONN_DIR_LOW_DUTY(_peer)

BT_LE_ADV_NCONN
    Non-connectable advertising with private address.

BT_LE_ADV_NCONN_NAME
    Non-connectable advertising with BT_LE_ADV_OPT_USE_NAME.

BT_LE_ADV_NCONN_IDENTITY
    Non-connectable advertising with BT_LE_ADV_OPT_USE_IDENTITY.

BT_LE_EXT_ADV_CONN_NAME
    Connectable extended advertising with BT_LE_ADV_OPT_USE_NAME.

BT_LE_EXT_ADV_SCAN_NAME
    Scannable extended advertising with BT_LE_ADV_OPT_USE_NAME.

BT_LE_EXT_ADV_NCONN
    Non-connectable extended advertising with private address.

BT_LE_EXT_ADV_NCONN_NAME
    Non-connectable extended advertising with BT_LE_ADV_OPT_USE_NAME.

BT_LE_EXT_ADV_NCONN_IDENTITY
    Non-connectable extended advertising with BT_LE_ADV_OPT_USE_IDENTITY.

BT_LE_EXT_ADV_CODED_NCONN
    Non-connectable extended advertising on coded PHY with private address.

BT_LE_EXT_ADV_CODED_NCONN_NAME
    Non-connectable extended advertising on coded PHY with BT_LE_ADV_OPT_USE_NAME.

BT_LE_EXT_ADV_CODED_NCONN_IDENTITY
    Non-connectable extended advertising on coded PHY with BT_LE_ADV_OPT_USE_IDENTITY.

BT_LE_EXT_ADV_START_PARAM_INIT(_timeout, _n_evts)
    Helper to initialize extended advertising start parameters inline.

    Parameters

    • _timeout – Advertiser timeout
    • _n_evts – Number of advertising events
BT_LE_EXT_ADV_START_PARAM(_timeout, _n_evts)
   Helper to declare extended advertising start parameters inline.
   **Parameters**
   - _timeout – Advertiser timeout
   - _n_evts – Number of advertising events

BT_LE_EXT_ADV_START_DEFAULT

BT_LE_PER_ADV_PARAM_INIT(_int_min, _int_max, _options)
   Helper to declare periodic advertising parameters inline.
   **Parameters**
   - _int_min – Minimum periodic advertising interval
   - _int_max – Maximum periodic advertising interval
   - _options – Periodic advertising properties bitfield.

BT_LE_PER_ADV_PARAM(_int_min, _int_max, _options)
   Helper to declare periodic advertising parameters inline.
   **Parameters**
   - _int_min – Minimum periodic advertising interval
   - _int_max – Maximum periodic advertising interval
   - _options – Periodic advertising properties bitfield.

BT_LE_PER_ADV_DEFAULT

BT_LE_SCAN_OPT_FILTER_WHITELIST

BT_LE_SCAN_PARAM_INIT(_type, _options, _interval, _window)
   Initialize scan parameters.
   **Parameters**
   - _type – Scan Type, BT_LE_SCAN_TYPE_ACTIVE or BT_LE_SCAN_TYPE_PASSIVE.
   - _options – Scan options
   - _interval – Scan Interval (N * 0.625 ms)
   - _window – Scan Window (N * 0.625 ms)

BT_LE_SCAN_PARAM(_type, _options, _interval, _window)
   Helper to declare scan parameters inline.
   **Parameters**
   - _type – Scan Type, BT_LE_SCAN_TYPE_ACTIVE or BT_LE_SCAN_TYPE_PASSIVE.
   - _options – Scan options
   - _interval – Scan Interval (N * 0.625 ms)
   - _window – Scan Window (N * 0.625 ms)

BT_LE_SCAN_ACTIVE
   Helper macro to enable active scanning to discover new devices.

6.1. Bluetooth
### BT_LE_SCAN_PASSIVE

Helper macro to enable passive scanning to discover new devices.

This macro should be used if information required for device identification (e.g., UUID) are known to be placed in Advertising Data.

### BT_LE_SCAN_CODED_ACTIVE

Helper macro to enable active scanning to discover new devices.

Include scanning on Coded PHY in addition to 1M PHY.

### BT_LE_SCAN_CODED_PASSIVE

Helper macro to enable passive scanning to discover new devices.

Include scanning on Coded PHY in addition to 1M PHY.

This macro should be used if information required for device identification (e.g., UUID) are known to be placed in Advertising Data.

### Typedefs

typedef void (*bt_ready_cb_t)(int err)

Callback for notifying that Bluetooth has been enabled.

**Param err**
zero on success or (negative) error code otherwise.

typedef void bt_le_scan_cb_t(const bt_addr_le_t *addr, int8_t rssi, uint8_t adv_type, struct net_buf_simple *buf)

Callback type for reporting LE scan results.

A function of this type is given to the `bt_le_scan_start()` function and will be called for any discovered LE device.

**Param addr**
Advertiser LE address and type.

**Param rssi**
Strength of advertiser signal.

**Param adv_type**
Type of advertising response from advertiser. Uses the `BT_GAP_ADV_TYPE_*` values.

**Param buf**
Buffer containing advertiser data.

typedef void bt_br_discovery_cb_t(struct bt_br_discovery_result *results, size_t count)

Callback type for reporting BR/EDR discovery (inquiry) results.

A callback of this type is given to the `bt_br_discovery_start()` function and will be called at the end of the discovery with information about found devices populated in the results array.

**Param results**
Storage used for discovery results

**Param count**
Number of valid discovery results.
Enums

Advertising options.

**Values:**

- **enumerator BT_LE_ADV_OPT_NONE = 0**
  Convenience value when no options are specified.

- **enumerator BT_LE_ADV_OPT_CONNECTABLE = BIT(0)**
  Advertise as connectable.
  Advertise as connectable. If not connectable then the type of advertising is determined by providing scan response data. The advertiser address is determined by the type of advertising and/or enabling privacy CONFIG_BT_PRIVACY.

- **enumerator BT_LE_ADV_OPT_ONE_TIME = BIT(1)**
  Advertise one time.
  Don’t try to resume connectable advertising after a connection. This option is only meaningful when used together with BT_LE_ADV_OPT_CONNECTABLE. If set the advertising will be stopped when `bt_le_adv_stop()` is called or when an incoming (peripheral) connection happens. If this option is not set the stack will take care of keeping advertising enabled even as connections occur. If Advertising directed or the advertiser was started with `bt_le_ext_adv_start` then this behavior is the default behavior and this flag has no effect.

- **enumerator BT_LE_ADV_OPT_USE_IDENTITY = BIT(2)**
  Advertise using identity address.
  Advertise using the identity address as the advertiser address.

  **Note:** The address used for advertising will not be the same as returned by `bt_le_oob_get_local`, instead `bt_id_get` should be used to get the LE address.

  **Warning:** This will compromise the privacy of the device, so care must be taken when using this option.

- **enumerator BT_LE_ADV_OPT_USE_NAME = BIT(3)**
  Advertise using GAP device name.
  Include the GAP device name automatically when advertising.
  By default the GAP device name is put at the end of the scan response data. When advertising using @ref BT_LE_ADV_OPT_EXT_ADV and not @ref BT_LE_ADV_OPT_SCANNABLE then it will be put at the end of the advertising data. If the GAP device name does not fit into advertising data it will be converted to a shortened name if possible. @ref BT_LE_ADV_OPT_FORCE_NAME_IN_AD can be used to force the device name to appear in the advertising data of an advert with scan response data.
The application can set the device name itself by including the following in the advertising data.

```c
@code
BT_DATA(BT_DATA_NAME_COMPLETE, name, sizeof(name) - 1)
@endcode
```

**enumerator** `BT_LE_ADV_OPT_DIR_MODE_LOW_DUTY = BIT(4)`
Low duty cycle directed advertising.
Use low duty directed advertising mode, otherwise high duty mode will be used.

**enumerator** `BT_LE_ADV_OPT_DIR_ADDR_RPA = BIT(5)`
Directed advertising to privacy-enabled peer.
Enable use of Resolvable Private Address (RPA) as the target address in directed advertisements. This is required if the remote device is privacy-enabled and supports address resolution of the target address in directed advertisement. It is the responsibility of the application to check that the remote device supports address resolution of directed advertisements by reading its Central Address Resolution characteristic.

**enumerator** `BT_LE_ADV_OPT_FILTER.Scan_REQ = BIT(6)`
Use filter accept list to filter devices that can request scan response data.

**enumerator** `BT_LE_ADV_OPT_FILTER_CONN = BIT(7)`
Use filter accept list to filter devices that can connect.

**enumerator** `BT_LE_ADV_OPT_NOTIFY_SCAN_REQ = BIT(8)`
Notify the application when a scan response data has been sent to an active scanner.

**enumerator** `BT_LE_ADV_OPT_SCANNABLE = BIT(9)`
Support scan response data.
When used together with `BT_LE_ADV_OPT_EXT_ADV` then this option cannot be used together with the `BT_LE_ADV_OPT_CONNECTABLE` option. When used together with `BT_LE_ADV_OPT_EXT_ADV` then scan response data must be set.

**enumerator** `BT_LE_ADV_OPT_EXT_ADV = BIT(10)`
Advertise with extended advertising.
This options enables extended advertising in the advertising set. In extended advertising the advertising set will send a small header packet on the three primary advertising channels. This small header points to the advertising data packet that will be sent on one of the 37 secondary advertising channels. The advertiser will send primary advertising on LE 1M PHY, and secondary advertising on LE 2M PHY. Connections will be established on LE 2M PHY.
Without this option the advertiser will send advertising data on the three primary advertising channels.

**Note:** Enabling this option requires extended advertising support in the peer devices scanning for advertisement packets.
Note: This cannot be used with `bt_le_adv_start()`.

enumerator `BT_LE_ADV_OPT_NO_2M = BIT(11)`
Disable use of LE 2M PHY on the secondary advertising channel.
Disabling the use of LE 2M PHY could be necessary if scanners don’t support the LE 2M PHY. The advertiser will send primary advertising on LE 1M PHY, and secondary advertising on LE 1M PHY. Connections will be established on LE 1M PHY.

Note: Cannot be set if `BT_LE_ADV_OPT_CODED` is set.

Note: Requires `BT_LE_ADV_OPT_EXT_ADV`.

enumerator `BT_LE_ADV_OPT_CODED = BIT(12)`
Advertise on the LE Coded PHY (Long Range).
The advertiser will send both primary and secondary advertising on the LE Coded PHY. This gives the advertiser increased range with the trade-off of lower data rate and higher power consumption. Connections will be established on LE Coded PHY.

Note: Requires `BT_LE_ADV_OPT_EXT_ADV`.

enumerator `BT_LE_ADV_OPT_ANONYMOUS = BIT(13)`
Advertise without a device address (identity or RPA).

Note: Requires `BT_LE_ADV_OPT_EXT_ADV`.

enumerator `BT_LE_ADV_OPT_USE_TX_POWER = BIT(14)`
Advertise with transmit power.

Note: Requires `BT_LE_ADV_OPT_EXT_ADV`.

enumerator `BT_LE_ADV_OPT_DISABLE_CHAN_37 = BIT(15)`
Disable advertising on channel index 37.

enumerator `BT_LE_ADV_OPT_DISABLE_CHAN_38 = BIT(16)`
Disable advertising on channel index 38.

enumerator `BT_LE_ADV_OPT_DISABLE_CHAN_39 = BIT(17)`
Disable advertising on channel index 39.

enumerator `BT_LE_ADV_OPT_FORCE_NAME_IN_AD = BIT(18)`
Put GAP device name into advert data.
Will place the GAP device name into the advertising data rather than the scan response data.

6.1. Bluetooth
**Note:** Requires `BT_LE_ADV_OPT_USE_NAME`.

enumerator `BT_LE_ADV_OPT_USE_NRPA` = `BIT(19)`
Advertise using a Non-Resolvable Private Address.
A new NRPA is set when updating the advertising parameters.
This is an advanced feature; most users will want to enable `CONFIG_BT_EXT_ADV` instead.

**Note:** Not implemented when `CONFIG_BT_PRIVACY`.

**Note:** Mutually exclusive with `BT_LE_ADV_OPT_USE_IDENTITY`.

Periodic Advertising options.

*Values:*

enumerator `BT_LE_PER_ADV_OPT_NONE` = 0
Convenience value when no options are specified.

enumerator `BT_LE_PER_ADV_OPT_USE_TX_POWER` = `BIT(1)`
Advertise with transmit power.

**Note:** Requires `BT_LE_ADV_OPT_EXT_ADV`.

enumerator `BT_LE_PER_ADV_OPT_INCLUDE_ADI` = `BIT(2)`
Advertise with included AdvDataInfo (ADI).

**Note:** Requires `BT_LE_ADV_OPT_EXT_ADV`.

Periodic advertising sync options.

*Values:*

enumerator `BT_LE_PER_ADV_SYNC_OPT_NONE` = 0
Convenience value when no options are specified.

enumerator `BT_LE_PER_ADV_SYNC_OPT_USE_PER_ADV_LIST` = `BIT(0)`
Use the periodic advertising list to sync with advertiser.
When this option is set, the address and SID of the parameters are ignored.

enumerator `BT_LE_PER_ADV_SYNC_OPT_REPORTING_INITIALLY_DISABLED` = `BIT(1)`
Disables periodic advertising reports.
No advertisement reports will be handled until enabled.
enumerator BT_LE_PER_ADV_SYNC_OPT_FILTER_DUPLICATE = \textit{BIT}(2)
Filter duplicate Periodic Advertising reports.

enumerator BT_LE_PER_ADV_SYNC_OPT_DONT_SYNC_AOA = \textit{BIT}(3)
Sync with Angle of Arrival (AoA) constant tone extension.

enumerator BT_LE_PER_ADV_SYNC_OPT_DONT_SYNC_AOD_1US = \textit{BIT}(4)
Sync with Angle of Departure (AoD) 1 us constant tone extension.

enumerator BT_LE_PER_ADV_SYNC_OPT_DONT_SYNC_AOD_2US = \textit{BIT}(5)
Sync with Angle of Departure (AoD) 2 us constant tone extension.

enumerator BT_LE_PER_ADV_SYNC_OPT_SYNC_ONLY_CONST_TONE_EXT = \textit{BIT}(6)
Do not sync to packets without a constant tone extension.

Periodic Advertising Sync Transfer options.
\textit{Values}:

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_NONE = 0
Convenience value when no options are specified.

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_SYNC_NO_AOA = \textit{BIT}(0)
No Angle of Arrival (AoA)
Do not sync with Angle of Arrival (AoA) constant tone extension

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_SYNC_NO_AOD_1US = \textit{BIT}(1)
No Angle of Departure (AoD) 1 us.
Do not sync with Angle of Departure (AoD) 1 us constant tone extension

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_SYNC_NO_AOD_2US = \textit{BIT}(2)
No Angle of Departure (AoD) 2.
Do not sync with Angle of Departure (AoD) 2 us constant tone extension

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_SYNC_ONLY_CTE = \textit{BIT}(3)
Only sync to packets with constant tone extension.

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_REPORTING_INITIALLY_DISABLED = \textit{BIT}(4)
Sync to received PAST packets but don’t generate sync reports.
This option must not be set at the same time as \textit{BT_LE_PER_ADV_SYNC_TRANSFER_OPT_FILTER_DUPLICATES}.

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_FILTER_DUPLICATES = \textit{BIT}(5)
Sync to received PAST packets and generate sync reports with duplicate filtering.
This option must not be set at the same time as \textit{BT_LE_PER_ADV_SYNC_TRANSFER_OPT_REPORTING_INITIALLY_DISABLED}.
Values:

enumerator BT_LE_SCAN_OPT_NONE = 0
   Convenience value when no options are specified.

enumerator BT_LE_SCAN_OPT_FILTER_DUPLICATE = BIT(0)
   Filter duplicates.

enumerator BT_LE_SCAN_OPT_FILTER_ACCEPT_LIST = BIT(1)
   Filter using filter accept list.

enumerator BT_LE_SCAN_OPT_CODED = BIT(2)
   Enable scan on coded PHY (Long Range).

enumerator BT_LE_SCAN_OPT_NO_1M = BIT(3)
   Disable scan on 1M phy.

Note: Requires BT_LE_SCAN_OPT_CODED.

Values:

everenumerator BT_LE_SCAN_TYPE_PASSIVE = 0x00
   Scan without requesting additional information from advertisers.

enumerator BT_LE_SCAN_TYPE_ACTIVE = 0x01
   Scan and request additional information from advertisers.
   Using this scan type will automatically send scan requests to all devices. Scan responses are received in the same manner and using the same callbacks as advertising reports.

Functions

int bt_enable(bt_ready_cb_t cb)
   Enable Bluetooth.
   Enable Bluetooth. Must be the called before any calls that require communication with the local Bluetooth hardware.
   When CONFIG_BT_SETTINGS is enabled, the application must load the Bluetooth settings after this API call successfully completes before Bluetooth APIs can be used. Loading the settings before calling this function is insufficient. Bluetooth settings can be loaded with settings_load() or settings_load_subtree() with argument “bt”. The latter selectively loads only Bluetooth settings and is recommended if settings_load() has been called earlier.

Parameters
   • cb – Callback to notify completion or NULL to perform the enabling synchronously.
Returns
Zero on success or (negative) error code otherwise.

int bt_disable(void)
Disable Bluetooth.
Disable Bluetooth. Can’t be called before bt_enable has completed.
Close and release HCI resources. Result is architecture dependent.

Returns
Zero on success or (negative) error code otherwise.

bool bt_is_ready(void)
Check if Bluetooth is ready.

Returns
ture when Bluetooth is ready, false otherwise

int bt_set_name(const char *name)
Set Bluetooth Device Name.
Set Bluetooth GAP Device Name.
When advertising with device name in the advertising data the name should be updated by calling bt_le_adv_update_data or bt_le_ext_adv_set_data.

See also:
CONFIG_BT_DEVICE_NAME_MAX.

Note: Requires CONFIG_BT_DEVICE_NAME_DYNAMIC.

Parameters
• name – New name

Returns
Zero on success or (negative) error code otherwise.

const char *bt_get_name(void)
Get Bluetooth Device Name.
Get Bluetooth GAP Device Name.

Returns
Bluetooth Device Name

uint16_t bt_get_appearance(void)
Get local Bluetooth appearance.
Bluetooth Appearance is a description of the external appearance of a device in terms of an Appearance Value.

See also:
https://specificationrefs.bluetooth.com/assigned-values/Appearance%20Values.pdf

Returns
Appearance Value of local Bluetooth host.
int bt_set_appearance(uint16_t new_appearance)
Set local Bluetooth appearance.

Automatically preserves the new appearance across reboots if CONFIG_BT_SETTINGS is enabled.

This symbol is linkable if CONFIG_BT_DEVICE_APPEARANCE_DYNAMIC is enabled.

Parameters
• new_appearance – Appearance Value

Return values
• 0 – Success.
• other – Persistent storage failed. Appearance was not updated.

void bt_id_get(bt_addr_le_t *addrs, size_t *count)
Get the currently configured identities.

Returns an array of the currently configured identity addresses. To make sure all available identities can be retrieved, the number of elements in the addrs array should be CONFIG_BT_ID_MAX. The identity identifier that some APIs expect (such as advertising parameters) is simply the index of the identity in the addrs array.

If addrs is passed as NULL, then returned count contains the count of all available identities that can be retrieved with a subsequent call to this function with non-NULL addrs parameter.

Note: Deleted identities may show up as BT_ADDR_LE_ANY in the returned array.

Parameters
• addrs – Array where to store the configured identities.
• count – Should be initialized to the array size. Once the function returns it will contain the number of returned identities.

int bt_id_create(bt_addr_le_t *addr, uint8_t *irk)
Create a new identity.

Create a new identity using the given address and IRK. This function can be called before calling bt_enable(). However, the new identity will only be stored persistently in flash when this API is used after bt_enable(). The reason is that the persistent settings are loaded after bt_enable() and would therefore cause potential conflicts with the stack blindly overwriting what's stored in flash. The identity will also not be written to flash in case a pre-defined address is provided, since in such a situation the app clearly has some place it got the address from and will be able to repeat the procedure on every power cycle, i.e. it would be redundant to also store the information in flash.

Generating random static address or random IRK is not supported when calling this function before bt_enable().

If the application wants to have the stack randomly generate identities and store them in flash for later recovery, the way to do it would be to first initialize the stack (using bt_enable), then call settings_load(), and after that check with bt_id_get() how many identities were recovered. If an insufficient amount of identities were recovered the app may then call bt_id_create() to create new ones.

If supported by the HCI driver (indicated by setting CONFIG_BT_HCI_SET_PUBLIC_ADDR), the first call to this function can be used to set the controller's public identity address. This call must happen before calling bt_enable(). Subsequent calls always add/generate random static addresses.
Parameters

• **addr** – Address to use for the new identity. If NULL or initialized to BT_ADDR_LE_ANY the stack will generate a new random static address for the identity and copy it to the given parameter upon return from this function (in case the parameter was non-NULL).

• **irk** – Identity Resolving Key (16 bytes) to be used with this identity. If set to all zeroes or NULL, the stack will generate a random IRK for the identity and copy it back to the parameter upon return from this function (in case the parameter was non-NULL). If privacy CONFIG_BT_PRIVACY is not enabled this parameter must be NULL.

Returns

Identity identifier (>= 0) in case of success, or a negative error code on failure.

```c
int bt_id_reset(uint8_t id, bt_addr_le_t *addr, uint8_t *irk)
```

Reset/reclaim an identity for reuse.

The semantics of the **addr** and **irk** parameters of this function are the same as with **bt_id_create()**. The difference is the first **id** parameter that needs to be an existing identity (if it doesn’t exist this function will return an error). When given an existing identity this function will disconnect any connections created using it, remove any pairing keys or other data associated with it, and then create a new identity in the same slot, based on the **addr** and **irk** parameters.

**Note:** the default identity (BT_ID_DEFAULT) cannot be reset, i.e. this API will return an error if asked to do that.

---

Parameters

• **id** – Existing identity identifier.

• **addr** – Address to use for the new identity. If NULL or initialized to BT_ADDR_LE_ANY the stack will generate a new static random address for the identity and copy it to the given parameter upon return from this function (in case the parameter was non-NULL).

• **irk** – Identity Resolving Key (16 bytes) to be used with this identity. If set to all zeroes or NULL, the stack will generate a random IRK for the identity and copy it back to the parameter upon return from this function (in case the parameter was non-NULL). If privacy CONFIG_BT_PRIVACY is not enabled this parameter must be NULL.

Returns

Identity identifier (>= 0) in case of success, or a negative error code on failure.

```c
int bt_id_delete(uint8_t id)
```

Delete an identity.

When given a valid identity this function will disconnect any connections created using it, remove any pairing keys or other data associated with it, and then flag it as deleted, so that it can not be used for any operations. To take back into use the slot the identity was occupying the **bt_id_reset()** API needs to be used.

**Note:** the default identity (BT_ID_DEFAULT) cannot be deleted, i.e. this API will return an error if asked to do that.
Parameters

- **id** – Existing identity identifier.

Returns

0 in case of success, or a negative error code on failure.

```c
size_t bt_data_get_len(const struct bt_data data[], size_t data_count)
```

Get the total size (in bytes) of a given set of `bt_data` structures.

Parameters

- **data_count** – [in] Number of `bt_data` structures in `data`.

Returns

Size of the concatenated data, built from the `bt_data` structure set.

```c
size_t bt_data_serialize(const struct bt_data *input, uint8_t *output)
```

Serialize a `bt_data` struct into an advertising structure (a flat byte array).

The data are formatted according to the Bluetooth Core Specification v. 5.4, vol. 3, part C, 11.

Parameters

- **input** – [in] Single `bt_data` structure to read from.
- **output** – [out] Buffer large enough to store the advertising structure in `input`. The size of it must be at least the size of the `input->data_len + 2` (for the type and the length).

Returns

Number of bytes written in `output`.

```c
int bt_le_adv_start(const struct bt_le_adv_param *param, const struct bt_data *ad, size_t ad_len, const struct bt_data *sd, size_t sd_len)
```

Start advertising.

Set advertisement data, scan response data, advertisement parameters and start advertising.

When the advertisement parameter peer address has been set the advertising will be directed to the peer. In this case advertisement data and scan response data parameters are ignored. If the mode is high duty cycle the timeout will be `BT_GAP_ADV_HIGH_DUTY_CYCLE_MAX_TIMEOUT`.

This function cannot be used with `BT_LE_ADV_OPT_EXT_ADV` in the `param.options`. For extended advertising, the `bt_le_ext_adv_*` functions must be used.

Parameters

- **param** – Advertising parameters.
- **ad** – Data to be used in advertisement packets.
- **ad_len** – Number of elements in ad
- **sd** – Data to be used in scan response packets.
- **sd_len** – Number of elements in sd

Returns

Zero on success or (negative) error code otherwise.

Returns

-ENOMEM No free connection objects available for connectable advertiser.
Returns
-ECONNREFUSED When connectable advertising is requested and there is
already maximum number of connections established in the controller.
This error code is only guaranteed when using Zephyr controller, for other
controllers code returned in this case may be -EIO.

int bt_le_adv_update_data(const struct bt_data *ad, size_t ad_len, const struct bt_data
    *sd, size_t sd_len)

Update advertising.
Update advertisement and scan response data.

Parameters
- ad – Data to be used in advertisement packets.
- ad_len – Number of elements in ad
- sd – Data to be used in scan response packets.
- sd_len – Number of elements in sd

Returns
Zero on success or (negative) error code otherwise.

int bt_le_adv_stop(void)
Stop advertising.
Stops ongoing advertising.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_ext_adv_create(const struct bt_le_adv_param *param, const struct bt_le_ext_adv_cb
    *cb, struct bt_le_ext_adv **adv)

Create advertising set.
Create a new advertising set and set advertising parameters. Advertising parameters
can be updated with bt_le_ext_adv_update_param.

Parameters
- cb – [in] Callback struct to notify about advertiser activity. Can be NULL.
  Must point to valid memory during the lifetime of the advertising set.
- adv – [out] Valid advertising set object on success.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_ext_adv_start(struct bt_le_ext_adv *adv, struct bt_le_ext_adv_start_param
    *param)

Start advertising with the given advertising set.
If the advertiser is limited by either the timeout or number of advertising events the
application will be notified by the advertiser sent callback once the limit is reached.
If the advertiser is limited by both the timeout and the number of advertising events
then the limit that is reached first will stop the advertiser.

Parameters
- adv – Advertising set object.
- param – Advertise start parameters.
int bt_le_ext_adv_stop(struct bt_le_ext_adv *adv)
Stop advertising with the given advertising set.
Stop advertising with a specific advertising set. When using this function the advertising sent callback will not be called.

Parameters
• adv – Advertising set object.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_ext_adv_set_data(struct bt_le_ext_adv *adv, const struct bt_data *ad, size_t ad_len, const struct bt_data *sd, size_t sd_len)
Set an advertising set’s advertising or scan response data.
Set advertisement data or scan response data. If the advertising set is currently advertising then the advertising data will be updated in subsequent advertising events.
When both BT_LE_ADV_OPT_EXT_ADV and BT_LE_ADV_OPT_SCANNABLE are enabled then advertising data is ignored. When BT_LE_ADV_OPT_SCANNABLE is not enabled then scan response data is ignored.
If the advertising set has been configured to send advertising data on the primary advertising channels then the maximum data length is BT_GAP_ADV_MAX_ADV_DATA_LEN bytes. If the advertising set has been configured for extended advertising, then the maximum data length is defined by the controller with the maximum possible of BT_GAP_ADV_MAX_EXT_ADV_DATA_LEN bytes.

Note: Not all scanners support extended data length advertising data.

Note: When updating the advertising data while advertising the advertising data and scan response data length must be smaller or equal to what can be fit in a single advertising packet. Otherwise the advertiser must be stopped.

Parameters
• adv – Advertising set object.
• ad – Data to be used in advertisement packets.
• ad_len – Number of elements in ad
• sd – Data to be used in scan response packets.
• sd_len – Number of elements in sd

Returns
Zero on success or (negative) error code otherwise.

int bt_le_ext_adv_update_param(struct bt_le_ext_adv *adv, const struct bt_le_adv_param *param)
Update advertising parameters.
Update the advertising parameters. The function will return an error if the advertiser set is currently advertising. Stop the advertising set before calling this function.
Note: When changing the option `BT_LE_ADV_OPT_USE_NAME` then `bt_le_ext_adv_set_data` needs to be called in order to update the advertising data and scan response data.

### Parameters
- `adv` – Advertising set object.
- `param` – Advertising parameters.

### Returns
Zero on success or (negative) error code otherwise.

```c
int bt_le_ext_adv_delete(struct bt_le_ext_adv *adv)
```
Delete advertising set.
Delete advertising set. This will free up the advertising set and make it possible to create a new advertising set.

### Returns
Zero on success or (negative) error code otherwise.

```c
uint8_t bt_le_ext_adv_get_index(struct bt_le_ext_adv *adv)
```
Get array index of an advertising set.
This function is used to map `bt_adv` to index of an array of advertising sets. The array has `CONFIG_BT_EXT_ADV_MAX_ADV_SET` elements.

### Parameters
- `adv` – Advertising set.

### Returns
Index of the advertising set object. The range of the returned value is `0..CONFIG_BT_EXT_ADV_MAX_ADV_SET-1`

```c
int bt_le_ext_adv_get_info(const struct bt_le_ext_adv *adv, struct bt_le_ext_adv_info *info)
```
Get advertising set info.

### Parameters
- `adv` – Advertising set object
- `info` – Advertising set info object

### Returns
Zero on success or (negative) error code on failure.

```c
int bt_le_per_adv_set_param(struct bt_le_ext_adv *adv, const struct bt_le_per_adv_param *param)
```
Set or update the periodic advertising parameters.
The periodic advertising parameters can only be set or updated on an extended advertisement set which is neither scannable, connectable nor anonymous.

### Parameters
- `adv` – Advertising set object.
- `param` – Advertising parameters.

### Returns
Zero on success or (negative) error code otherwise.
int bt_le_per_adv_set_data(const struct bt_le_ext_adv *adv, const struct bt_data *ad, size_t ad_len)

Set or update the periodic advertising data.

The periodic advertisement data can only be set or updated on an extended advertise-
ment set which is neither scannable, connectable nor anonymous.

**Parameters**

- **adv** – Advertising set object.
- **ad** – Advertising data.
- **ad_len** – Advertising data length.

**Returns**

Zero on success or (negative) error code otherwise.

int bt_le_per_adv_set_subevent_data(const struct bt_le_ext_adv *adv, uint8_t num_subevents, const struct bt_le_per_adv_subevent_data_params *params)

Set the periodic advertising with response subevent data.

Set the data for one or more subevents of a Periodic Advertising with Responses Ad-
vertiser in reply data request.

**Parameters**

- **adv** – The extended advertiser the PAwR train belongs to.
- **num_subevents** – The number of subevents to set data for.
- **params** – Subevent parameters.

**Pre**

There are num_subevents elements in params.

**Pre**

The controller has requested data for the subevents in params.

**Returns**

Zero on success or (negative) error code otherwise.

int bt_le_per_adv_start(struct bt_le_ext_adv *adv)

Starts periodic advertising.

Enabling the periodic advertising can be done independently of extended advertising,
but both periodic advertising and extended advertising shall be enabled before any
periodic advertising data is sent. The periodic advertising and extended advertising
can be enabled in any order.

Once periodic advertising has been enabled, it will continue advertising un-
til bt_le_per_adv_stop() has been called, or if the advertising set is deleted by
bt_le_ext_adv_delete(). Calling bt_le_ext_adv_stop() will not stop the periodic advertis-
ing.

**Parameters**

- **adv** – Advertising set object.

**Returns**

Zero on success or (negative) error code otherwise.

int bt_le_per_adv_stop(struct bt_le_ext_adv *adv)

Stops periodic advertising.

Disabling the periodic advertising can be done independently of extended advertising.
Disabling periodic advertising will not disable extended advertising.
Parameters

- adv – Advertising set object.

Returns

Zero on success or (negative) error code otherwise.

uint8_t bt_le_per_adv_sync_get_index(struct bt_le_per_adv_sync *per_adv_sync)

Get array index of an periodic advertising sync object.

This function is get the index of an array of periodic advertising sync objects. The array has CONFIG_BT_PER_ADV_SYNC_MAX elements.

Parameters

- per_adv_sync – The periodic advertising sync object.

Returns

Index of the periodic advertising sync object. The range of the returned value is 0..CONFIG_BT_PER_ADV_SYNC_MAX-1

struct bt_le_per_adv_sync *bt_le_per_adv_sync_lookup_index(uint8_t index)

Get a periodic advertising sync object from the array index.

This function is to get the periodic advertising sync object from the array index. The array has CONFIG_BT_PER_ADV_SYNC_MAX elements.

Parameters

- index – The index of the periodic advertising sync object. The range of the index value is 0..CONFIG_BT_PER_ADV_SYNC_MAX-1

Returns

The periodic advertising sync object of the array index or NULL if invalid index.

int bt_le_per_adv_sync_get_info(struct bt_le_per_adv_sync *per_adv_sync, struct bt_le_per_adv_sync_info *info)

Get periodic adv sync information.

Parameters

- per_adv_sync – Periodic advertising sync object.
  - info – Periodic advertising sync info object

Returns

Zero on success or (negative) error code on failure.

struct bt_le_per_adv_sync *bt_le_per_adv_sync_lookup_addr(const bt_addr_le_t *adv_addr, uint8_t sid)

Look up an existing periodic advertising sync object by advertiser address.

Parameters

- adv_addr – Advertiser address.
- sid – The advertising set ID.

Returns

Periodic advertising sync object or NULL if not found.

int bt_le_per_adv_sync_create(const struct bt_le_per_adv_sync_param *param, struct bt_le_per_adv_sync **out_sync)

Create a periodic advertising sync object.

Create a periodic advertising sync object that can try to synchronize to periodic advertising reports from an advertiser. Scan shall either be disabled or extended scan shall be enabled.
This function does not timeout, and will continue to look for an advertiser until it either finds it or `bt_le_per_adv_sync_delete()` is called. It is thus suggested to implement a timeout when using this, if it is expected to find the advertiser within a reasonable timeframe.

Parameters
- **param** – [in] Periodic advertising sync parameters.
- **out_sync** – [out] Periodic advertising sync object on.

Returns
Zero on success or (negative) error code otherwise.

```c
int bt_le_per_adv_sync_delete(struct bt_le_per_adv_sync *per_adv_sync)
```
Delete periodic advertising sync.

Delete the periodic advertising sync object. Can be called regardless of the state of the sync. If the syncing is currently syncing, the syncing is cancelled. If the sync has been established, it is terminated. The periodic advertising sync object will be invalidated afterwards.

If the state of the sync object is syncing, then a new periodic advertising sync object may not be created until the controller has finished canceling this object.

Parameters
- **per_adv_sync** – The periodic advertising sync object.

Returns
Zero on success or (negative) error code otherwise.

```c
void bt_le_per_adv_sync_cb_register(struct bt_le_per_adv_sync_cb *cb)
```
Register periodic advertising sync callbacks.

Adds the callback structure to the list of callback structures for periodic advertising syncs.

This callback will be called for all periodic advertising sync activity, such as synced, terminated and when data is received.

Parameters
- **cb** – Callback struct. Must point to memory that remains valid.

Returns
Zero on success or (negative) error code otherwise.

```c
int bt_le_per_adv_sync_recv_enable(struct bt_le_per_adv_sync *per_adv_sync)
```
Enables receiving periodic advertising reports for a sync.

If the sync is already receiving the reports, -EALREADY is returned.

Parameters
- **per_adv_sync** – The periodic advertising sync object.

Returns
Zero on success or (negative) error code otherwise.

```c
int bt_le_per_adv_sync_recv_disable(struct bt_le_per_adv_sync *per_adv_sync)
```
Disables receiving periodic advertising reports for a sync.

If the sync report receiving is already disabled, -EALREADY is returned.

Parameters
- **per_adv_sync** – The periodic advertising sync object.

Returns
Zero on success or (negative) error code otherwise.
int bt_le_per_adv_sync_transfer(const struct bt_le_per_adv_sync *per_adv_sync, const struct bt_conn *conn, uint16_t service_data)

Transfer the periodic advertising sync information to a peer device.

This will allow another device to quickly synchronize to the same periodic advertising train that this device is currently synced to.

Parameters

• per_adv_sync – The periodic advertising sync to transfer.
• conn – The peer device that will receive the sync information.
• service_data – Application service data provided to the remote host.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_set_info_transfer(const struct bt_le_ext_adv *adv, const struct bt_conn *conn, uint16_t service_data)

Transfer the information about a periodic advertising set.

This will allow another device to quickly synchronize to periodic advertising set from this device.

Parameters

• adv – The periodic advertising set to transfer info of.
• conn – The peer device that will receive the information.
• service_data – Application service data provided to the remote host.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_sync_transfer_subscribe(const struct bt_conn *conn, const struct bt_le_per_adv_sync_transfer_param *param)

Subscribe to periodic advertising sync transfers (PASTs).

Sets the parameters and allow other devices to transfer periodic advertising syncs.

Parameters

• conn – The connection to set the parameters for. If NULL default parameters for all connections will be set. Parameters set for specific connection will always have precedence.
• param – The periodic advertising sync transfer parameters.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_sync_transfer_unsubscribe(const struct bt_conn *conn)

Unsubscribe from periodic advertising sync transfers (PASTs).

Remove the parameters that allow other devices to transfer periodic advertising syncs.

Parameters

• conn – The connection to remove the parameters for. If NULL default parameters for all connections will be removed. Unsubscribing for a specific device, will still allow other devices to transfer periodic advertising syncs.

Returns
Zero on success or (negative) error code otherwise.
int bt_le_per_adv_list_add(const bt_addr_le_t *addr, uint8_t sid)
Add a device to the periodic advertising list.
Add peer device LE address to the periodic advertising list. This will make it possibly
to automatically create a periodic advertising sync to this device.

Parameters
• addr – Bluetooth LE identity address.
• sid – The advertising set ID. This value is obtained from the
  bt_le_scan_recv_info in the scan callback.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_list_remove(const bt_addr_le_t *addr, uint8_t sid)
Remove a device from the periodic advertising list.
Removes peer device LE address from the periodic advertising list.

Parameters
• addr – Bluetooth LE identity address.
• sid – The advertising set ID. This value is obtained from the
  bt_le_scan_recv_info in the scan callback.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_list_clear(void)
Clear the periodic advertising list.
Clears the entire periodic advertising list.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_scan_start(const struct bt_le_scan_param *param, bt_le_scan_cb_t cb)
Start (LE) scanning.
Start LE scanning with given parameters and provide results through the specified
callback.

Note: The LE scanner by default does not use the Identity Address of the local
device when CONFIG_BT_PRIVACY is disabled. This is to prevent the active scanner
from disclosing the identity information when requesting additional information
from advertisers. In order to enable directed advertiser reports then CONFIG_BT_SCAN_WITH_IDENTITY must be enabled.

Parameters
• param – Scan parameters.
• cb – Callback to notify scan results. May be NULL if callback registration
  through bt_le_scan_cb_register is preferred.

Returns
Zero on success or error code otherwise, positive in case of protocol error
or negative (POSIX) in case of stack internal error.
int bt_le_scan_stop(void)
    Stop (LE) scanning.
    Stops ongoing LE scanning.

    **Returns**
    Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

void bt_le_scan_cb_register(struct bt_le_scan_cb *cb)
    Register scanner packet callbacks.
    Adds the callback structure to the list of callback structures that monitors scanner activity.
    This callback will be called for all scanner activity, regardless of what API was used to start the scanner.

    **Parameters**
    • cb – Callback struct. Must point to memory that remains valid.

void bt_le_scan_cb_unregister(struct bt_le_scan_cb *cb)
    Unregister scanner packet callbacks.
    Remove the callback structure from the list of scanner callbacks.

    **Parameters**
    • cb – Callback struct. Must point to memory that remains valid.

int bt_le_filter_accept_list_add(const bt_addr_le_t *addr)
    Add device (LE) to filter accept list.
    Add peer device LE address to the filter accept list.

    **Note:** The filter accept list cannot be modified when an LE role is using the filter accept list, i.e advertiser or scanner using a filter accept list or automatic connecting to devices using filter accept list.

    **Parameters**
    • addr – Bluetooth LE identity address.

    **Returns**
    Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

static inline int bt_le_whitelist_add(const bt_addr_le_t *addr)

int bt_le_filter_accept_list_remove(const bt_addr_le_t *addr)
    Remove device (LE) from filter accept list.
    Remove peer device LE address from the filter accept list.

    **Note:** The filter accept list cannot be modified when an LE role is using the filter accept list, i.e advertiser or scanner using a filter accept list or automatic connecting to devices using filter accept list.

    **Parameters**
    • addr – Bluetooth LE identity address.
Returns
Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

static inline int bt_le_whitelist_rem(const bt_addr_le_t *addr)

int bt_le_filter_accept_list_clear(void)
Clear filter accept list.
Clear all devices from the filter accept list.

Note: The filter accept list cannot be modified when an LE role is using the filter accept list, i.e. advertiser or scanner using a filter accept list or automatic connecting to devices using filter accept list.

Returns
Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

static inline int bt_le_whitelist_clear(void)

int bt_le_set_chan_map(uint8_t chan_map[5])
Set (LE) channel map.

Parameters
• chan_map – Channel map.

Returns
Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

int bt_le_set_rpa_timeout(uint16_t new_rpa_timeout)
Set the Resolvable Private Address timeout in runtime.

The new RPA timeout value will be used for the next RPA rotation and all subsequent rotations until another override is scheduled with this API.

Initially, the if CONFIG_BT_RPA_TIMEOUT is used as the RPA timeout.

This symbol is linkable if CONFIG_BT_RPA_TIMEOUT_DYNAMIC is enabled.

Parameters
• new_rpa_timeout – Resolvable Private Address timeout in seconds

Return values
• 0 – Success.
• -EINVAL – RPA timeout value is invalid. Valid range is 1s - 3600s.

void bt_data_parse(struct net_buf_simple *ad, bool (*func)(struct bt_data *data, void *user_data), void *user_data)
Helper for parsing advertising (or EIR or OOB) data.

A helper for parsing the basic data types used for Extended Inquiry Response (EIR), Advertising Data (AD), and OOB data blocks. The most common scenario is to call this helper on the advertising data received in the callback that was given to bt_le_scan_start().
**Warning:** This helper function will consume ad when parsing. The user should make a copy if the original data is to be used afterwards

**Parameters**

- **ad** – Advertising data as given to the bt_le_scan_cb_t callback.
- **func** – Callback function which will be called for each element that’s found in the data. The callback should return true to continue parsing, or false to stop parsing.
- **user_data** – User data to be passed to the callback.

```c
int bt_le_oob_get_local(uint8_t id, struct bt_le_oob *oob)
```

Get local LE Out of Band (OOB) information.

This function allows to get local information that are useful for Out of Band pairing or connection creation.

If privacy CONFIG_BT_PRIVACY is enabled this will result in generating new Resolvable Private Address (RPA) that is valid for CONFIG_BT_RPA_TIMEOUT seconds. This address will be used for advertising started by `bt_le_adv_start`, active scanning and connection creation.

**Note:** If privacy is enabled the RPA cannot be refreshed in the following cases:

- Creating a connection in progress, wait for the connected callback. In addition when extended advertising CONFIG_BT_EXT_ADV is not enabled or not supported by the controller:
- Advertiser is enabled using a Random Static Identity Address for a different local identity.
- The local identity conflicts with the local identity used by other roles.

**Parameters**

- **id** – [in] Local identity, in most cases BT_ID_DEFAULT.
- **oob** – [out] LE OOB information

**Returns**

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_le_ext_adv_oob_get_local(struct bt_le_ext_adv *adv, struct bt_le_oob *oob)
```

Get local LE Out of Band (OOB) information.

This function allows to get local information that are useful for Out of Band pairing or connection creation.

If privacy CONFIG_BT_PRIVACY is enabled this will result in generating new Resolvable Private Address (RPA) that is valid for CONFIG_BT_RPA_TIMEOUT seconds. This address will be used by the advertising set.

**Note:** When generating OOB information for multiple advertising set all OOB information needs to be generated at the same time.

**Note:** If privacy is enabled the RPA cannot be refreshed in the following cases:
• Creating a connection in progress, wait for the connected callback.

Parameters

- `adv` – [in] The advertising set object
- `oob` – [out] LE OOB information

Returns

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_br_discovery_start(const struct bt_br_discovery_param *param, struct bt_br_discovery_result *results, size_t count, bt_br_discovery_cb_t cb)
```

Start BR/EDR discovery.

Start BR/EDR discovery (inquiry) and provide results through the specified callback. When `bt_br_discovery_cb_t` is called it indicates that discovery has completed. If more inquiry results were received during session than fits in provided result storage, only ones with highest RSSI will be reported.

Parameters

- `param` – Discovery parameters.
- `results` – Storage for discovery results.
- `count` – Number of results in storage. Valid range: 1-255.
- `cb` – Callback to notify discovery results.

Returns

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_br_discovery_stop(void)
```

Stop BR/EDR discovery.

Stops ongoing BR/EDR discovery. If discovery was stopped by this call results won’t be reported.

Parameters

Returns

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_br_oob_get_local(struct bt_br_oob *oob)
```

Get BR/EDR local Out Of Band information.

This function allows to get local controller information that are useful for Out Of Band pairing or connection creation process.

Parameters

- `oob` – Out Of Band information

```c
int bt_br_set_discoverable(bool enable)
```

Enable/disable set controller in discoverable state.

Allows make local controller to listen on INQUIRY SCAN channel and responds to devices making general inquiry. To enable this state it’s mandatory to first be in connectable state.

Parameters

- `enable` – Value allowing/disallowing controller to become discoverable.
Returns
Negative if fail set to requested state or requested state has been already set. Zero if done successfully.

int bt_br_set_connectable(bool enable)
Enable/disable set controller in connectable state.
Allows make local controller to be connectable. It means the controller start listen to devices requests on PAGE SCAN channel. If disabled also resets discoverability if was set.

Parameters
- enable – Value allowing/disallowing controller to be connectable.

Returns
Negative if fail set to requested state or requested state has been already set. Zero if done successfully.

int bt_unpair(uint8_t id, const bt_addr_le_t *addr)
Clear pairing information.

Parameters
- id – Local identity (mostly just BT_ID_DEFAULT).
- addr – Remote address, NULL or BT_ADDR_LE_ANY to clear all remote devices.

Returns
0 on success or negative error value on failure.

void bt_foreach_bond(uint8_t id, void (*func)(const struct bt_bond_info *info, void *user_data), void *user_data)
Iterate through all existing bonds.

Parameters
- id – Local identity (mostly just BT_ID_DEFAULT).
- func – Function to call for each bond.
- user_data – Data to pass to the callback function.

int bt_configure_data_path(uint8_t dir, uint8_t id, uint8_t vs_config_len, const uint8_t *vs_config)
Configure vendor data path.
Request the Controller to configure the data transport path in a given direction between the Controller and the Host.

Parameters
- dir – Direction to be configured, BT_HCI_DATAPATH_DIR_HOST_TO_CTLR or BT_HCI_DATAPATH_DIR_CTLR_TO_HOST
- id – Vendor specific logical transport channel ID, range [BT_HCI_DATAPATH_ID_VS..BT_HCI_DATAPATH_ID_VS_END]
- vs_config_len – Length of additional vendor specific configuration data
- vs_config – Pointer to additional vendor specific configuration data

Returns
0 in case of success or negative value in case of error.
int bt_le_per_adv_sync_subevent(struct bt_le_per_adv_sync *per_adv_sync, struct 
bt_le_per_adv_sync_subevent_params *params)

Synchronize with a subset of subevents. 
Until this command is issued, the subevent(s) the controller is synchronized to is un-
specified.

Parameters

• per_adv_sync – The periodic advertising sync object.
• params – Parameters.

Returns

0 in case of success or negative value in case of error.

int bt_le_per_adv_set_response_data(struct bt_le_per_adv_sync *per_adv_sync, const 
struct bt_le_per_adv_response_params *params, const struct net_buf_simple *data)

Set the data for a response slot in a specific subevent of the PAwR. 
This function is called by the application to set the response data. The data for a re-
sponse slot shall be transmitted only once.

Parameters

• per_adv_sync – The periodic advertising sync object.
• params – Parameters.
• data – The response data to send.

Returns

Zero on success or (negative) error code otherwise.

struct bt_le_ext_adv_sent_info

#include <bluetooth.h>

Public Members

uint8_t num_sent

The number of advertising events completed.

struct bt_le_ext_adv_connected_info

#include <bluetooth.h>

Public Members

struct bt_conn *conn

Connection object of the new connection.

struct bt_le_ext_adv_scanned_info

#include <bluetooth.h>
Public Members

bt_addr_le_t *addr
Active scanner LE address and type.

struct bt_le_per_adv_data_request
#include <bluetooth.h>

Public Members

uint8_t start
The first subevent data can be set for.

uint8_t count
The number of subevents data can be set for.

struct bt_le_per_adv_response_info
#include <bluetooth.h>

Public Members

uint8_t subevent
The subevent the response was received in.

uint8_t tx_status
Status of the subevent indication.
0 if subevent indication was transmitted. 1 if subevent indication was not transmitted. All other values RFU.

int8_t tx_power
The TX power of the response in dBm.

int8_t rssi
The RSSI of the response in dBm.

uint8_t cte_type
The Constant Tone Extension (CTE) of the advertisement (bt_df_cste_type)

uint8_t response_slot
The slot the response was received in.

struct bt_le_ext_adv_cb
#include <bluetooth.h>
Public Members

void (*sent)(struct bt_le_ext_adv *adv, struct bt_le_ext_adv_sent_info *info)
   The advertising set has finished sending adv data.
   This callback notifies the application that the advertising set has finished sending advertising data. The advertising set can either have been stopped by a timeout or because the specified number of advertising events has been reached.
   **Param adv**
   The advertising set object.
   **Param info**
   Information about the sent event.

void (*connected)(struct bt_le_ext_adv *adv, struct bt_le_ext_adv_connected_info *info)
   The advertising set has accepted a new connection.
   This callback notifies the application that the advertising set has accepted a new connection.
   **Param adv**
   The advertising set object.
   **Param info**
   Information about the connected event.

void (*scanned)(struct bt_le_ext_adv *adv, struct bt_le_ext_adv_scanned_info *info)
   The advertising set has sent scan response data.
   This callback notifies the application that the advertising set has has received a Scan Request packet, and has sent a Scan Response packet.
   **Param adv**
   The advertising set object.
   **Param addr**
   Information about the scanned event.

struct bt_data
   #include <bluetooth.h> Bluetooth data.
   Description of different data types that can be encoded into advertising data. Used to form arrays that are passed to the *bt_le_adv_start()* function.

struct bt_le_adv_param
   #include <bluetooth.h> LE Advertising Parameters.

Public Members

uint8_t id
   Local identity.

**Note:** When extended advertising CONFIG_BT_EXTADV is not enabled or not supported by the controller it is not possible to scan and advertise simultaneously using two different random addresses.
uint8_t sid
Advertising Set Identifier, valid range 0x00 - 0x0f.

**Note:** Requires `BT_LE_ADV_OPT_EXT_ADV`

uint8_t secondary_max_skip
Secondary channel maximum skip count.
Maximum advertising events the advertiser can skip before it must send advertising data on the secondary advertising channel.

**Note:** Requires `BT_LE_ADV_OPT_EXT_ADV`

uint32_t options
Bit-field of advertising options.

uint32_t interval_min
Minimum Advertising Interval (N * 0.625 milliseconds) Minimum Advertising Interval shall be less than or equal to the Maximum Advertising Interval.
The Minimum Advertising Interval and Maximum Advertising Interval should not be the same value (as stated in Bluetooth Core Spec 5.2, section 7.8.5) Range: 0x0020 to 0x4000

uint32_t interval_max
Maximum Advertising Interval (N * 0.625 milliseconds) Minimum Advertising Interval shall be less than or equal to the Maximum Advertising Interval.
The Minimum Advertising Interval and Maximum Advertising Interval should not be the same value (as stated in Bluetooth Core Spec 5.2, section 7.8.5) Range: 0x0020 to 0x4000

const bt_addr_le_t *peer
Directed advertising to peer.
When this parameter is set the advertiser will send directed advertising to the remote device.
The advertising type will either be high duty cycle, or low duty cycle if the `BT_LE_ADV_OPT_DIR_MODE_LOW_DUTY` option is enabled. When using `BT_LE_ADV_OPT_EXT_ADV` then only low duty cycle is allowed.
In case of connectable high duty cycle if the connection could not be established within the timeout the `connected()` callback will be called with the status set to `BT_HCI_ERR_ADV_TIMEOUT`.

```c
#include <bluetooth.h>
```

struct bt_le_per_adv_param

**Public Members**
uint16_t interval_min
    Minimum Periodic Advertising Interval (N * 1.25 ms)
    Shall be greater or equal to BT_GAP_PER_ADV_MIN_INTERVAL and less or equal to
    interval_max.

uint16_t interval_max
    Maximum Periodic Advertising Interval (N * 1.25 ms)
    Shall be less or equal to BT_GAP_PER_ADV_MAX_INTERVAL and greater or equal
    to interval_min.

uint32_t options
    Bit-field of periodic advertising options.

struct bt_le_ext_adv_start_param
    #include <bluetooth.h>

Public Members

uint16_t timeout
    Advertiser timeout (N * 10 ms).
    Application will be notified by the advertiser sent callback. Set to zero for no time-
    out.
    When using high duty cycle directed connectable advertising then this param-
    eters must be set to a non-zero value less than or equal to the maximum of
    BT_GAP_ADV_HIGH_DUTY_CYCLE_MAX_TIMEOUT.
    If privacy CONFIG_BT_PRIVACY is enabled then the timeout must be less than CON-
    FIG_BT_RPA_TIMEOUT.

uint8_t num_events
    Number of advertising events.
    Application will be notified by the advertiser sent callback. Set to zero for no limit.

struct bt_le_ext_adv_info
    #include <bluetooth.h> Advertising set info structure.

Public Members

int8_t tx_power
    Currently selected Transmit Power (dBm).

cnst bt_addr_le_t *addr
    Current local advertising address used.

struct bt_le_per_adv_subevent_data_params
    #include <bluetooth.h>
Public Members

```c
uint8_t subevent
    The subevent to set data for.

uint8_t response_slot_start
    The first response slot to listen to.

uint8_t response_slot_count
    The number of response slots to listen to.

const struct net_buf_simple *data
    The data to send.
```

```c
struct bt_le_per_adv_sync_synced_info
    #include <bluetooth.h>
```

Public Members

```c
const bt_addr_le_t *addr
    Advertiser LE address and type.

uint8_t sid
    Advertiser SID.

uint16_t interval
    Periodic advertising interval (N * 1.25 ms)

uint8_t phy
    Advertiser PHY.

bool recv_enabled
    True if receiving periodic advertisements, false otherwise.

uint16_t service_data
    Service Data provided by the peer when sync is transferred.
    Will always be 0 when the sync is locally created.

struct bt_conn *conn
    Peer that transferred the periodic advertising sync.
    Will always be 0 when the sync is locally created.
```

```c
struct bt_le_per_adv_sync_term_info
    #include <bluetooth.h>
```

6.1. Bluetooth
Public Members

const bt_addr_le_t *addr
   Advertiser LE address and type.

uint8_t sid
   Advertiser SID.

uint8_t reason
   Cause of periodic advertising termination.

struct bt_le_per_adv_sync_recv_info
   #include <bluetooth.h>

Public Members

const bt_addr_le_t *addr
   Advertiser LE address and type.

uint8_t sid
   Advertiser SID.

int8_t tx_power
   The TX power of the advertisement.

int8_t rssi
   The RSSI of the advertisement excluding any CTE.

uint8_t cte_type
   The Constant Tone Extension (CTE) of the advertisement (bt_df_cte_type)

struct bt_le_per_adv_sync_state_info
   #include <bluetooth.h>

Public Members

bool recv_enabled
   True if receiving periodic advertisements, false otherwise.

struct bt_le_per_adv_sync_cb
   #include <bluetooth.h>

Public Members
void (*synced)(struct bt_le_per_adv_sync *sync, struct bt_le_per_adv_sync_synced_info *info)

The periodic advertising has been successfully synced.
This callback notifies the application that the periodic advertising set has been successfully synced, and will now start to receive periodic advertising reports.

**Param sync**
The periodic advertising sync object.

**Param info**
Information about the sync event.

void (*term)(struct bt_le_per_adv_sync *sync, const struct bt_le_per_adv_sync_term_info *info)

The periodic advertising sync has been terminated.
This callback notifies the application that the periodic advertising sync has been terminated, either by local request, remote request or because due to missing data, e.g. by being out of range or sync.

**Param sync**
The periodic advertising sync object.

void (*recv)(struct bt_le_per_adv_sync *sync, const struct bt_le_per_adv_sync_recv_info *info, struct net_buf_simple *buf)

Periodic advertising data received.
This callback notifies the application of an periodic advertising report.

**Param sync**
The advertising set object.

**Param info**
Information about the periodic advertising event.

**Param buf**
Buffer containing the periodic advertising data. NULL if the controller failed to receive a subevent indication. Only happens if CONFIG_BT_PER_ADV_SYNC_RSP is enabled.

void (*state_changed)(struct bt_le_per_adv_sync *sync, const struct bt_le_per_adv_sync_state_info *info)

The periodic advertising sync state has changed.
This callback notifies the application about changes to the sync state. Initialize sync and termination is handled by their individual callbacks, and won't be notified here.

**Param sync**
The periodic advertising sync object.

**Param info**
Information about the state change.

void (*biginfo)(struct bt_le_per_adv_sync *sync, const struct bt_iso_biginfo *biginfo)

BIGInfo advertising report received.
This callback notifies the application of a BIGInfo advertising report. This is received if the advertiser is broadcasting isochronous streams in a BIG. See iso.h for more information.

**Param sync**
The advertising set object.

**Param biginfo**
The BIGInfo report.
void (*cte_report_cb)(struct bt_le_per_adv_sync *sync, struct bt_df_per_adv_sync_iq_samples_report const *info)

Callback for IQ samples report collected when sampling CTE received with periodic advertising PDU.

**Param sync**
The periodic advertising sync object.

**Param info**
Information about the sync event.

```c
#include <bluetooth.h>
```

**Public Members**

```c
bt_addr_le_t addr
```
Periodic Advertiser Address.

- Only valid if not using the periodic advertising list (BT_LE_PER_ADV_SYNC_OPT_USE_PER_ADV_LIST)

```c
uint8_t sid
```
Advertiser SID.

- Only valid if not using the periodic advertising list (BT_LE_PER_ADV_SYNC_OPT_USE_PER_ADV_LIST)

```c
uint32_t options
```
Bit-field of periodic advertising sync options.

```c
uint16_t skip
```
Maximum event skip.

- Maximum number of periodic advertising events that can be skipped after a successful receive. Range: 0x0000 to 0x01F3

```c
uint16_t timeout
```
Synchronization timeout (N * 10 ms)

- Synchronization timeout for the periodic advertising sync. Range 0x000A to 0x4000 (100 ms to 163840 ms)

```c
#include <bluetooth.h> Advertising set info structure.
```

**Public Members**

```c
bt_addr_le_t addr
```
Periodic Advertiser Address.

```c
uint8_t sid
```
Advertiser SID.
# Bluetooth

## Public Members

### `uint16_t interval`
Periodic advertising interval (N * 1.25 ms)

### `uint8_t phy`
Advertiser PHY.

### `struct bt_le_per_adv_sync_transfer_param`

```c
#include <bluetooth.h>
```

#### Public Members

### `uint16_t skip`
Maximum event skip.
The number of periodic advertising packets that can be skipped after a successful receive.

### `uint16_t timeout`
Synchronization timeout (N * 10 ms)
Synchronization timeout for the periodic advertising sync. Range 0x000A to 0x4000 (100 ms to 163840 ms)

### `uint32_t options`
Periodic Advertising Sync Transfer options.

### `struct bt_le_scan_param`

```c
#include <bluetooth.h>
```

#### Public Members

### `uint8_t type`
Scan type (BT_LE_SCAN_TYPE_ACTIVE or BT_LE_SCAN_TYPE_PASSIVE)

### `uint32_t options`
Bit-field of scanning options.

### `uint16_t interval`
Scan interval (N * 0.625 ms)

### `uint16_t window`
Scan window (N * 0.625 ms)

### `uint16_t timeout`
Scan timeout (N * 10 ms)
Application will be notified by the scan timeout callback. Set zero to disable timeout.
uint16_t interval_coded
    Scan interval LE Coded PHY (N * 0.625 MS)
    Set zero to use same as LE 1M PHY scan interval.

uint16_t window_coded
    Scan window LE Coded PHY (N * 0.625 MS)
    Set zero to use same as LE 1M PHY scan window.

struct bt_le_scan_recv_info
    #include <bluetooth.h> LE advertisement and scan response packet information.

Public Members

const bt_addr_le_t *addr
    Advertiser LE address and type.
    If advertiser is anonymous then this address will be BT_ADDR_LE_ANY.

uint8_t sid
    Advertising Set Identifier.

int8_t rssi
    Strength of advertiser signal.

int8_t tx_power
    Transmit power of the advertiser.

uint8_t adv_type
    Advertising packet type.
    Uses the BT_GAP_ADV_TYPE_* value.
    May indicate that this is a scan response if the type is
    BT_GAP_ADV_TYPE_SCAN_RSP.

uint16_t adv_props
    Advertising packet properties bitfield.
    Uses the BT_GAP_ADV_PROP_* values. May indicate that this is a scan response if
    the value contains the BT_GAP_ADV_PROP_SCAN_RESPONSE bit.

uint16_t interval
    Periodic advertising interval.
    If 0 there is no periodic advertising.

uint8_t primary_phy
    Primary advertising channel PHY.

uint8_t secondary_phy
    Secondary advertising channel PHY.
struct bt_le_scan_cb
#include <bluetooth.h> Listener context for (LE) scanning.

Public Members

void (*recv)(const struct bt_le_scan_recv_info *info, struct net_buf_simple *buf)
  Advertisement packet and scan response received callback.
  Param info
   Advertiser packet and scan response information.
  Param buf
   Buffer containing advertiser data.

void (*timeout)(void)
  The scanner has stopped scanning after scan timeout.

struct bt_le_oob_sc_data
#include <bluetooth.h> LE Secure Connections pairing Out of Band data.

Public Members

uint8_t r[16]
  Random Number.

uint8_t c[16]
  Confirm Value.

struct bt_le_oob
#include <bluetooth.h> LE Out of Band information.

Public Members

bt_addr_le_t addr
  LE address.
  If privacy is enabled this is a Resolvable Private Address.

struct bt_le_oob_sc_data le_sc_data
  LE Secure Connections pairing Out of Band data.

struct bt_br_discovery_result
#include <bluetooth.h> BR/EDR discovery result structure.

Public Members

bt_addr_t addr
  Remote device address.
int8_t rssi
    RSSI from inquiry.

uint8_t cod[3]
    Class of Device.

uint8_t eir[240]
    Extended Inquiry Response.

struct bt_br_discovery_param
    #include <bluetooth.h> BR/EDR discovery parameters.

Public Members

uint8_t length
    Maximum length of the discovery in units of 1.28 seconds.
    Valid range is 0x01 - 0x30.

bool limited
    True if limited discovery procedure is to be used.

struct bt_br_oob
    #include <bluetooth.h>

Public Members

bt_addr_t addr
    BR/EDR address.

struct bt_bond_info
    #include <bluetooth.h> Information about a bond with a remote device.

Public Members

bt_addr_le_t addr
    Address of the remote device.

struct bt_le_per_adv_sync_subevent_params
    #include <bluetooth.h>

Public Members
uint16_t properties
    Periodic Advertising Properties.
    Bit 6 is include TxPower, all others RFU.

uint8_t num_subevents
    Number of subevents to sync to.

uint8_t *subevents
    The subevent(s) to synchronize with.
    The array must have num_subevents elements.

struct bt_le_per_adv_response_params
    #include <bluetooth.h>

Public Members

uint16_t request_event
    The periodic event counter of the request the response is sent to.
    bt_le_per_adv_sync_recv_info

    Note: The response can be sent up to one periodic interval after the request was received.

uint8_t request_subevent
    The subevent counter of the request the response is sent to.
    bt_le_per_adv_sync_recv_info

uint8_t response_subevent
    The subevent the response shall be sent in.

uint8_t response_slot
    The response slot the response shall be sent in.

group bt_addr
    Bluetooth device address definitions and utilities.

Defines

    BT_ADDR_LE_PUBLIC

    BT_ADDR_LE_RANDOM

    BT_ADDR_LE_PUBLIC_ID

6.1. Bluetooth
BT_ADDR_LE_RANDOM_ID

BT_ADDR_LE_UNRESOLVED

BT_ADDR_LE_ANONYMOUS

BT_ADDR_SIZE
  Length in bytes of a standard Bluetooth address.

BT_ADDR_LE_SIZE
  Length in bytes of an LE Bluetooth address.
  Not packed, so no sizeof()

BT_ADDR_ANY
  Bluetooth device “any” address, not a valid address.

BT_ADDR_NONE
  Bluetooth device “none” address, not a valid address.

BT_ADDR_LE_ANY
  Bluetooth LE device “any” address, not a valid address.

BT_ADDR_LE_NONE
  Bluetooth LE device “none” address, not a valid address.

BT_ADDR_IS_RPA(a)
  Check if a Bluetooth LE random address is resolvable private address.

BT_ADDR_IS_NRPA(a)
  Check if a Bluetooth LE random address is a non-resolvable private address.

BT_ADDR_IS_STATIC(a)
  Check if a Bluetooth LE random address is a static address.

BT_ADDR_SET_RPA(a)
  Set a Bluetooth LE random address as a resolvable private address.

BT_ADDR_SET_NRPA(a)
  Set a Bluetooth LE random address as a non-resolvable private address.

BT_ADDR_SET_STATIC(a)
  Set a Bluetooth LE random address as a static address.

BT_ADDR_STR_LEN
  Recommended length of user string buffer for Bluetooth address.
  The recommended length guarantee the output of address conversion will not lose valuable information about address being processed.

BT_ADDR_LE_STR_LEN
  Recommended length of user string buffer for Bluetooth LE address.
  The recommended length guarantee the output of address conversion will not lose valuable information about address being processed.
Functions

static inline int bt_addr_cmp(const bt_addr_t *a, const bt_addr_t *b)

Compare Bluetooth device addresses.

**Parameters**

- `a` – First Bluetooth device address to compare
- `b` – Second Bluetooth device address to compare

**Returns**

negative value if `a < b`, 0 if `a == b`, else positive

static inline bool bt_addr_eq(const bt_addr_t *a, const bt_addr_t *b)

Determine equality of two Bluetooth device addresses.

**Return values**

- `true` – if the two addresses are equal
- `false` – otherwise

static inline int bt_addr_le_cmp(const bt_addr_le_t *a, const bt_addr_le_t *b)

Compare Bluetooth LE device addresses.

See also:

`bt_addr_le_eq`

**Parameters**

- `a` – First Bluetooth LE device address to compare
- `b` – Second Bluetooth LE device address to compare

**Returns**

negative value if `a < b`, 0 if `a == b`, else positive

static inline bool bt_addr_le_eq(const bt_addr_le_t *a, const bt_addr_le_t *b)

Determine equality of two Bluetooth LE device addresses.

The Bluetooth LE addresses are equal iff both the types and the 48-bit addresses are numerically equal.

**Return values**

- `true` – if the two addresses are equal
- `false` – otherwise

static inline void bt_addr_copy(bt_addr_t *dst, const bt_addr_t *src)

Copy Bluetooth device address.

**Parameters**

- `dst` – Bluetooth device address destination buffer.
- `src` – Bluetooth device address source buffer.

static inline void bt_addr_le_copy(bt_addr_le_t *dst, const bt_addr_le_t *src)

Copy Bluetooth LE device address.

**Parameters**

- `dst` – Bluetooth LE device address destination buffer.
- `src` – Bluetooth LE device address source buffer.
int bt_addr_le_create_nrpa(bt_addr_le_t *addr)
   Create a Bluetooth LE random non-resolvable private address.

int bt_addr_le_create_static(bt_addr_le_t *addr)
   Create a Bluetooth LE random static address.

static inline bool bt_addr_le_is_rpa(const bt_addr_le_t *addr)
   Check if a Bluetooth LE address is a random private resolvable address.

   Parameters
   • addr – Bluetooth LE device address.

   Returns
   true if address is a random private resolvable address.

static inline bool bt_addr_le_is_identity(const bt_addr_le_t *addr)
   Check if a Bluetooth LE address is valid identity address.

   Valid Bluetooth LE identity addresses are either public address or random static address.

   Parameters
   • addr – Bluetooth LE device address.

   Returns
   true if address is a valid identity address.

static inline int bt_addr_to_str(const bt_addr_t *addr, char *str, size_t len)
   Converts binary Bluetooth address to string.

   Parameters
   • addr – Address of buffer containing binary Bluetooth address.
   • str – Address of user buffer with enough room to store formatted string containing binary address.
   • len – Length of data to be copied to user string buffer. Refer to BT_ADDR_STR_LEN about recommended value.

   Returns
   Number of successfully formatted bytes from binary address.

static inline int bt_addr_le_to_str(const bt_addr_le_t *addr, char *str, size_t len)
   Converts binary LE Bluetooth address to string.

   Parameters
   • addr – Address of buffer containing binary LE Bluetooth address.
   • str – Address of user buffer with enough room to store formatted string containing binary LE address.
   • len – Length of data to be copied to user string buffer. Refer to BT_ADDR_LE_STR_LEN about recommended value.

   Returns
   Number of successfully formatted bytes from binary address.

int bt_addr_from_str(const char *str, bt_addr_t *addr)
   Convert Bluetooth address from string to binary.

   Parameters
   • str – [in] The string representation of a Bluetooth address.
   • addr – [out] Address of buffer to store the Bluetooth address
**Return values**

- **0** – Success. The parsed address is stored in `addr`.

**Returns**

- **EINVAL** Invalid address string. `str` is not a well-formed Bluetooth address.

```c
int bt_addr_le_from_str(const char *str, const char *type, bt_addr_le_t *addr)
```

Convert LE Bluetooth address from string to binary.

**Parameters**

- `type` – [in] The string representation of the LE Bluetooth address type.
- `addr` – [out] Address of buffer to store the LE Bluetooth address

**Returns**

Zero on success or (negative) error code otherwise.

**Variables**

- `const bt_addr_t bt_addr_any`
- `const bt_addr_t bt_addr_none`
- `const bt_addr_le_t bt_addr_le_any`
- `const bt_addr_le_t bt_addr_le_none`

```c
#include <addr.h>
```

Bluetooth Device Address.

```c
#include <addr.h>
```

Bluetooth LE Device Address.

**group bt_gap_defines**

Bluetooth Generic Access Profile defines and Assigned Numbers.

**Company Identifiers (see Bluetooth Assigned Numbers)**

**BT_COMP_ID_LF**

The Linux Foundation.

**EIR/AD data type definitions**

**BT_DATA_FLAGS**

AD flags.

**BT_DATA_UUID16_SOME**

16-bit UUID, more available
BT_DATA_UUID16_ALL
   16-bit UUID, all listed

BT_DATA_UUID32_SOME
   32-bit UUID, more available

BT_DATA_UUID32_ALL
   32-bit UUID, all listed

BT_DATA_UUID128_SOME
   128-bit UUID, more available

BT_DATA_UUID128_ALL
   128-bit UUID, all listed

BT_DATA_NAME_SHORTENED
   Shortened name.

BT_DATA_NAME_COMPLETE
   Complete name.

BT_DATA_TX_POWER
   Tx Power.

BT_DATA_SM_TK_VALUE
   Security Manager TK Value.

BT_DATA_SM_OOB_FLAGS
   Security Manager OOB Flags.

BT_DATA_PERIPHERAL_INT_RANGE
   Peripheral Connection Interval Range.

BT_DATA_SOLICIT16
   Solicit UUIDs, 16-bit.

BT_DATA_SOLICIT128
   Solicit UUIDs, 128-bit.

BT_DATA_SVC_DATA16
   Service data, 16-bit UUID.

BT_DATA_PUB_TARGET_ADDR
   Public Target Address.

BT_DATA_RAND_TARGET_ADDR
   Random Target Address.
BT_DATA_GAP_APPEARANCE
GAP appearance.

BT_DATA_ADV_INT
Advertising Interval.

BT_DATA_LE_BT_DEVICE_ADDRESS
LE Bluetooth Device Address.

BT_DATA_LE_ROLE
LE Role.

BT_DATA_SIMPLE_PAIRING_HASH
Simple Pairing Hash C256.

BT_DATA_SIMPLE_PAIRING_RAND
Simple Pairing Randomizer R256.

BT_DATA_SOLICIT32
Solicit UUIDs, 32-bit.

BT_DATA_SVC_DATA32
Service data, 32-bit UUID.

BT_DATA_SVC_DATA128
Service data, 128-bit UUID.

BT_DATA_LE_SC_CONFIRM_VALUE
LE SC Confirmation Value.

BT_DATA_LE_SC_RANDOM_VALUE
LE SC Random Value.

BT_DATA_URI
URI.

BT_DATA_INDOOR_POS
Indoor Positioning.

BT_DATA_TRANS_DISCOVER_DATA
Transport Discovery Data.

BT_DATA_LE_SUPPORTED_FEATURES
LE Supported Features.

BT_DATA_CHANNEL_MAP_UPDATE_IND
Channel Map Update Indication.
BT_DATA_MESH_PROV
Mesh Provisioning PDU.

BT_DATA_MESH_MESSAGE
Mesh Networking PDU.

BT_DATA_MESH_BEACON
Mesh Beacon.

BT_DATA_BIG_INFO
BIGInfo.

BT_DATA_BROADCAST_CODE
Broadcast Code.

BT_DATA_CSIS_RSI
CSIS Random Set ID type.

BT_DATA_ADV_INT_LONG
Advertising Interval long.

BT_DATA_BROADCAST_NAME
Broadcast Name.

BT_DATA_ENCRYPTED_AD_DATA
Encrypted Advertising Data.

BT_DATA_3D_INFO
3D Information Data

BT_DATA_MANUFACTURER_DATA
Manufacturer Specific Data.

BT_LE_AD_LIMITED
Limited Discoverable.

BT_LE_AD_GENERAL
General Discoverable.

BT_LE_AD_NO_BREDR
BR/EDR not supported.

Appearance Values

Last Modified on 2023-01-05

BT_APPEARANCE_UNKNOWN
Generic Unknown.
**BT_APPEARANCE_GENERIC_PHONE**
Generic Phone.

**BT_APPEARANCE_GENERIC_COMPUTER**
Generic Computer.

**BT_APPEARANCE_COMPUTER_DESKTOP_WORKSTATION**
Desktop Workstation.

**BT_APPEARANCE_COMPUTER_SERVER_CLASS**
Server-class Computer.

**BT_APPEARANCE_COMPUTER_LAPTOP**
Laptop.

**BT_APPEARANCE_COMPUTER_HANDHELD_PCPDA**
Handheld PC/PDA (clamshell)

**BT_APPEARANCE_COMPUTER_PALMSIZE_PCPDA**
Palmsize PC/PDA.

**BT_APPEARANCE_COMPUTER_WEARABLE_COMPUTER**
Wearable computer (watch size)

**BT_APPEARANCE_COMPUTER_TABLET**
Tablet.

**BT_APPEARANCE_COMPUTER_DOCKING_STATION**
Docking Station.

**BT_APPEARANCE_COMPUTER_ALL_IN_ONE**
All in One.

**BT_APPEARANCE_COMPUTER_BLADE_SERVER**
Blade Server.

**BT_APPEARANCE_COMPUTER_CONVERTIBLE**
Convertible.

**BT_APPEARANCE_COMPUTER_DETACHABLE**
Detachable.

**BT_APPEARANCE_COMPUTER_IOT_GATEWAY**
IoT Gateway.

**BT_APPEARANCE_COMPUTER_MINI_PC**
Mini PC.
BT_APPEARANCE_COMPUTER_STICK_PC
  Stick PC.

BT_APPEARANCE_GENERIC_WATCH
  Generic Watch.

BT_APPEARANCE_SPORTS_WATCH
  Sports Watch.

BT_APPEARANCE_SMARTWATCH
  Smartwatch.

BT_APPEARANCE GENERIC_CLOCK
  Generic Clock.

BT_APPEARANCE_GENERIC_DISPLAY
  Generic Display.

BT_APPEARANCE_GENERIC_REMOTE
  Generic Remote Control.

BT_APPEARANCE GENERIC_EYEGlasses
  Generic Eye-glasses.

BT_APPEARANCE_GENERIC_TAG
  Generic Tag.

BT_APPEARANCE GENERIC_KEYRING
  Generic Keyring.

BT_APPEARANCE GENERIC_MEDIA PLAYER
  Generic Media Player.

BT_APPEARANCE GENERIC BARCODE SCANNER
  Generic Barcode Scanner.

BT_APPEARANCE GENERIC THERMOMETER
  Generic Thermometer.

BT_APPEARANCE THERMOMETER EAR
  Ear Thermometer.

BT_APPEARANCE_GENERIC HEART_RATE
  Generic Heart Rate Sensor.

BT_APPEARANCE HEART_RATE BELT
  Heart Rate Belt.
BT_APPEARANCE_GENERIC_BLOOD_PRESSURE
Generic Blood Pressure.

BT_APPEARANCE_BLOOD_PRESSURE_ARM
Arm Blood Pressure.

BT_APPEARANCE_BLOOD_PRESSURE_WRIST
Wrist Blood Pressure.

BT_APPEARANCE_GENERIC_HID
Generic Human Interface Device.

BT_APPEARANCE_HID_KEYBOARD
Keyboard.

BT_APPEARANCE_HID_MOUSE
Mouse.

BT_APPEARANCE_HID_JOYSTICK
Joystick.

BT_APPEARANCE_HID_GAMEPAD
Gamepad.

BT_APPEARANCE_HID_DIGITIZER_TABLET
Digitizer Tablet.

BT_APPEARANCE_HID_CARD_READER
Card Reader.

BT_APPEARANCE_HID_DIGITAL_PEN
Digital Pen.

BT_APPEARANCE_HID_BARCODE_SCANNER
Barcode Scanner.

BT_APPEARANCE_HID_TOUCHPAD
Touchpad.

BT_APPEARANCE_HID_PRESENTATION_REMOTE
Presentation Remote.

BT_APPEARANCE_GENERIC_GLUCOSE
Generic Glucose Meter.

BT_APPEARANCE_GENERIC_WALKING
Generic Running Walking Sensor.
BT_APPEARANCE_WALKING_IN_SHOE
In-Shoe Running Walking Sensor.

BT_APPEARANCE_WALKING_ON_SHOE
On-Shoe Running Walking Sensor.

BT_APPEARANCE_WALKING_ON_HIP

BT_APPEARANCE GENERIC CYCLING
Generic Cycling.

BT_APPEARANCE CYCLING COMPUTER
Cycling Computer.

BT_APPEARANCE CYCLING SPEED
Speed Sensor.

BT_APPEARANCE_CYCLING_CADENCE
Cadence Sensor.

BT_APPEARANCE CYCLING POWER
Power Sensor.

BT_APPEARANCE CYCLING SPEED_CADENCE
Speed and Cadence Sensor.

BT_APPEARANCE GENERIC CONTROL DEVICE
Generic Control Device.

BT_APPEARANCE CONTROL SWITCH
Switch.

BT_APPEARANCE CONTROL MULTI_SWITCH
Multi-switch.

BT_APPEARANCE CONTROL BUTTON
Button.

BT_APPEARANCE CONTROL SLIDER
Slider.

BT_APPEARANCE CONTROL ROTARY_SWITCH
Rotary Switch.

BT_APPEARANCE CONTROL TOUCH PANEL
Touch Panel.
BT_APPEARANCE_CONTROL_SINGLE_SWITCH
Single Switch.

BT_APPEARANCE_CONTROL_DOUBLE_SWITCH
Double Switch.

BT_APPEARANCE_CONTROL_TRIPLE_SWITCH
Triple Switch.

BT_APPEARANCE_CONTROL_BATTERY_SWITCH
Battery Switch.

BT_APPEARANCE_CONTROL_ENERGY_HARVESTING_SWITCH
Energy Harvesting Switch.

BT_APPEARANCE_CONTROL_PUSH BUTTON
Push Button.

BT_APPEARANCE_GENERIC_NETWORK_DEVICE
Generic Network Device.

BT_APPEARANCE_NETWORK_ACCESS_POINT
Access Point.

BT_APPEARANCE_NETWORK_MESH_DEVICE
Mesh Device.

BT_APPEARANCE_NETWORK_MESH_PROXY
Mesh Network Proxy.

BT_APPEARANCE_GENERIC_SENSOR
Generic Sensor.

BT_APPEARANCE_SENSOR_MOTION
Motion Sensor.

BT_APPEARANCE_SENSOR_AIR_QUALITY
Air quality Sensor.

BT_APPEARANCE_SENSOR_TEMPERATURE
Temperature Sensor.

BT_APPEARANCE_SENSOR_HUMIDITY
Humidity Sensor.

BT_APPEARANCE_SENSOR_LEAK
Leak Sensor.
BT_APPEARANCE_SENSOR_SMOKE
Smoke Sensor.

BT_APPEARANCE_SENSOR_OCCUPANCY
Occupancy Sensor.

BT_APPEARANCE_SENSOR_CONTACT
Contact Sensor.

BT_APPEARANCE_SENSOR_CARBURON_MONOXIDE
Carbon Monoxide Sensor.

BT_APPEARANCE_SENSOR_CARBURON_DIOXIDE
Carbon Dioxide Sensor.

BT_APPEARANCE_SENSOR_AMBIENT_LIGHT
Ambient Light Sensor.

BT_APPEARANCE_SENSOR_ENERGY
Energy Sensor.

BT_APPEARANCE_SENSOR_COLOR_LIGHT
Color Light Sensor.

BT_APPEARANCE_SENSOR_RAIN
Rain Sensor.

BT_APPEARANCE_SENSOR_FIRE
Fire Sensor.

BT_APPEARANCE_SENSOR_WIND
Wind Sensor.

BT_APPEARANCE_SENSOR_PROXIMITY
Proximity Sensor.

BT_APPEARANCE_SENSOR_MULTI
Multi-Sensor.

BT_APPEARANCE_SENSOR_FLUSH_MOUNTED
Flush Mounted Sensor.

BT_APPEARANCE_SENSOR_CEILING_MOUNTED
Ceiling Mounted Sensor.

BT_APPEARANCE_SENSOR_WALL_MOUNTED
Wall Mounted Sensor.
BT APPEARANCE MULTISENSOR
Multisensor.

BT APPEARANCE SENSOR ENERGY METER
Energy Meter.

BT APPEARANCE SENSOR FLAME DETECTOR
Flame Detector.

BT APPEARANCE SENSOR VEHICLE TIRE PRESSURE
Vehicle Tire Pressure Sensor.

BT APPEARANCE GENERIC LIGHT FIXTURES
Generic Light Fixtures.

BT APPEARANCE LIGHT FIXTURES WALL
Wall Light.

BT APPEARANCE LIGHT FIXTURES CEILING
Ceiling Light.

BT APPEARANCE LIGHT FIXTURES FLOOR
Floor Light.

BT APPEARANCE LIGHT FIXTURES CABINET
Cabinet Light.

BT APPEARANCE LIGHT FIXTURES DESK
Desk Light.

BT APPEARANCE LIGHT FIXTURES TROFFER
Troffer Light.

BT APPEARANCE LIGHT FIXTURES PENDANT
Pendant Light.

BT APPEARANCE LIGHT FIXTURES IN GROUND
In-ground Light.

BT APPEARANCE LIGHT FIXTURES FLOOD
Flood Light.

BT APPEARANCE LIGHT FIXTURES UNDERWATER
Underwater Light.

BT APPEARANCE LIGHT FIXTURES BOLLARD WITH
Bollard with Light.
BT_APPEARANCE_LIGHT_FIXTURES_PATHWAY
Pathway Light.

BT_APPEARANCE_LIGHT_FIXTURES_GARDEN
Garden Light.

BT_APPEARANCE_LIGHT_FIXTURES_POLE_TOP
Pole-top Light.

BT_APPEARANCE_SPOT_LIGHT
Spotlight.

BT_APPEARANCE_LIGHT_FIXTURES_LINEAR
Linear Light.

BT_APPEARANCE_LIGHT_FIXTURES_STREET
Street Light.

BT_APPEARANCE_LIGHT_FIXTURES_SHELVES
Shelves Light.

BT_APPEARANCE_LIGHT_FIXTURES_BAY
Bay Light.

BT_APPEARANCE_LIGHT_FIXTURES_EMERGENCY_EXIT
Emergency Exit Light.

BT_APPEARANCE_LIGHT_FIXTURES_CONTROLLER
Light Controller.

BT_APPEARANCE_LIGHT_FIXTURES_DRIVER
Light Driver.

BT_APPEARANCE_LIGHT_FIXTURES_BULB
Bulb.

BT_APPEARANCE_LIGHT_FIXTURES_LOW_BAY
Low-bay Light.

BT_APPEARANCE_LIGHT_FIXTURES_HIGH_BAY
High-bay Light.

BT_APPEARANCE_GENERIC_FAN
Generic Fan.

BT_APPEARANCE_FAN_CEILING
Ceiling Fan.
BT_APPEARANCE_FAN_AXIAL
Axial Fan.

BT_APPEARANCE_FAN_EXHAUST
Exhaust Fan.

BT_APPEARANCE_FAN_PEDESTAL
Pedestal Fan.

BT_APPEARANCE_FAN_DESK
Desk Fan.

BT_APPEARANCE_FAN_WALL
Wall Fan.

BT_APPEARANCE_GENERIC_HVAC
Generic HVAC.

BT_APPEARANCE_HVAC_THERMOSTAT
Thermostat.

BT_APPEARANCE_HVAC_HUMIDIFIER
Humidifier.

BT_APPEARANCE_HVAC_DEHUMIDIFIER
De-humidifier.

BT_APPEARANCE_HVAC_HEATER
Heater.

BT_APPEARANCE_HVAC_RADIATOR
Radiator.

BT_APPEARANCE_HVAC_BOILER
Boiler.

BT_APPEARANCE_HVAC_HEAT_PUMP
Heat Pump.

BT_APPEARANCE_HVAC_INFRARED_HEATER
Infrared Heater.

BT_APPEARANCE_HVAC_RADIANT_PANEL_HEATER
Radiant Panel Heater.

BT_APPEARANCE_HVAC_FAN_HEATER
Fan Heater.

6.1. Bluetooth
BT_APPEARANCE_HVAC_AIR_CURTAIN
Air Curtain.

BT_APPEARANCE_GENERIC_AIR_CONDITIONING
Generic Air Conditioning.

BT_APPEARANCE_GENERIC_HUMIDIFIER
Generic Humidifier.

BT_APPEARANCE_GENERIC_HEATING
Generic Heating.

BT_APPEARANCE_HEATING_RADIATOR
Radiator.

BT_APPEARANCE_HEATING_BOILER
Boiler.

BT_APPEARANCE_HEATING_HEAT_PUMP
Heat Pump.

BT_APPEARANCE_HEATING_INFRARED_HEATER
Infrared Heater.

BT_APPEARANCE_HEATING_RADIANT_PANEL_HEATER
Radiant Panel Heater.

BT_APPEARANCE_HEATING_FAN_HEATER
Fan Heater.

BT_APPEARANCE_HEATING_AIR_CURTAIN
Air Curtain.

BT_APPEARANCE_GENERIC_ACCESS_CONTROL
Generic Access Control.

BT_APPEARANCE_CONTROL_ACCESS_DOOR
Access Door.

BT_APPEARANCE_CONTROL_GARAGE_DOOR
Garage Door.

BT_APPEARANCE_CONTROL_EMERGENCY_EXIT_DOOR
Emergency Exit Door.

BT_APPEARANCE_CONTROL_ACCESS_LOCK
Access Lock.
BT_APPEARANCE_CONTROL_ELEVATOR
Elevator.

BT_APPEARANCE_CONTROL_WINDOW
Window.

BT_APPEARANCE_CONTROL_ENTRANCE_GATE
Entrance Gate.

BT_APPEARANCE_CONTROL_DOOR_LOCK
Door Lock.

BT_APPEARANCE_CONTROL_LOCKER
Locker.

BT_APPEARANCE_GENERIC_MOTORIZED_DEVICE
Generic Motorized Device.

BT_APPEARANCE_MOTORIZED_GATE
Motorized Gate.

BT_APPEARANCE_MOTORIZED_AWNING
Awning.

BT_APPEARANCE_MOTORIZED_BLINDS_OR_SHADES
Blinds or Shades.

BT_APPEARANCE_MOTORIZED_CURTAINS
Curtains.

BT_APPEARANCE_MOTORIZED_SCREEN
Screen.

BT_APPEARANCE_GENERIC_POWER_DEVICE
Generic Power Device.

BT_APPEARANCE_POWER_OUTLET
Power Outlet.

BT_APPEARANCE_POWER_STRIP
Power Strip.

BT_APPEARANCE_POWER_PLUG
Plug.

BT_APPEARANCE_POWER_SUPPLY
Power Supply.

6.1. Bluetooth
BT_APPEARANCE_POWER_LED_DRIVER
   LED Driver.

BT_APPEARANCE_POWER_FLUORESCENT_LAMP_GEAR
   Fluorescent Lamp Gear.

BT_APPEARANCE_POWER_HID_LAMP_GEAR
   HID Lamp Gear.

BT_APPEARANCE_POWER_CHARGE_CASE
   Charge Case.

BT_APPEARANCE_POWER_POWER_BANK
   Power Bank.

BT_APPEARANCE_GENERIC_LIGHT_SOURCE
   Generic Light Source.

BT_APPEARANCE_LIGHT_SOURCE_INCANDESCENT_BULB
   Incandescent Light Bulb.

BT_APPEARANCE_LIGHT_SOURCE_LED_LAMP
   LED Lamp.

BT_APPEARANCE_LIGHT_SOURCE_HID_LAMP
   HID Lamp.

BT_APPEARANCE_LIGHT_SOURCE_FLUORESCENT_LAMP
   Fluorescent Lamp.

BT_APPEARANCE_LIGHT_SOURCE_LED_ARRAY
   LED Array.

BT_APPEARANCE_LIGHT_SOURCE_MULTICOLOR_LED_ARRAY
   Multi-Color LED Array.

BT_APPEARANCE_LIGHT_SOURCE_LOW_VOLTAGE_HALOGEN
   Low voltage halogen.

BT_APPEARANCE_LIGHT_SOURCE_OLED
   Organic light emitting diode.

BT_APPEARANCE GENERIC_WINDOW_COVERING
   Generic Window Covering.

BT_APPEARANCE_WINDOW_SHADES
   Window Shades.
BT_APPEARANCE_WINDOW_BLINDS
   Window Blinds.

BT_APPEARANCE_WINDOW_AWNING
   Window Awning.

BT_APPEARANCE_WINDOW_CURTAIN
   Window Curtain.

BT_APPEARANCE_WINDOW_EXTERIOR_SHUTTER
   Exterior Shutter.

BT_APPEARANCE_WINDOW_EXTERIOR_SCREEN
   Exterior Screen.

BT_APPEARANCE_GENERIC_AUDIO_SINK
   Generic Audio Sink.

BT_APPEARANCE_AUDIO_SINK_STANDALONE_SPEAKER
   Standalone Speaker.

BT_APPEARANCE_AUDIO_SINK_SOUNDBAR
   Soundbar.

BT_APPEARANCE_AUDIO_SINK_BOOKSHELF_SPEAKER
   Bookshelf Speaker.

BT_APPEARANCE_AUDIO_SINK_STANDMOUNTED_SPEAKER
   Standmounted Speaker.

BT_APPEARANCE_AUDIO_SINK_SPEAKERPHONE
   Speakerphone.

BT_APPEARANCE_GENERIC_AUDIO_SOURCE
   Generic Audio Source.

BT_APPEARANCE_AUDIO_SOURCE_MICROPHONE
   Microphone.

BT_APPEARANCE_AUDIO_SOURCE_ALARM
   Alarm.

BT_APPEARANCE_AUDIO_SOURCE_BELL
   Bell.

BT_APPEARANCE_AUDIO_SOURCE_HORN
   Horn.
BT_APPEARANCE_AUDIO_SOURCE_BROADCASTING_DEVICE
   Broadcasting Device.

BT_APPEARANCE_AUDIO_SOURCE_SERVICE_DESK
   Service Desk.

BT_APPEARANCE_AUDIO_SOURCE_KIOSK
   Kiosk.

BT_APPEARANCE_AUDIO_SOURCE_BROADCASTING_ROOM
   Broadcasting Room.

BT_APPEARANCE_AUDIO_SOURCE_AUDITORIUM
   Auditorium.

BT_APPEARANCE_GENERIC_MOTORIZED_VEHICLE
   Generic Motorized Vehicle.

BT_APPEARANCE_VEHICLE_CAR
   Car.

BT_APPEARANCE_VEHICLE_LARGE_GOODS
   Large Goods Vehicle.

BT_APPEARANCE_VEHICLE_TWO_WHEELED
   2-Wheeled Vehicle

BT_APPEARANCE_VEHICLE_MOTORBIKE
   Motorbike.

BT_APPEARANCE_VEHICLE_SCOOTER
   Scooter.

BT_APPEARANCE_VEHICLE_MOPED
   Moped.

BT_APPEARANCE_VEHICLE_THREE_WHEELED
   3-Wheeled Vehicle

BT_APPEARANCE_VEHICLE_LIGHT
   Light Vehicle.

BT_APPEARANCE_VEHICLE_QUAD_BIKE
   Quad Bike.

BT_APPEARANCE_VEHICLE_MINIBUS
   Minibus.
BT_APPEARANCE_VEHICLE_BUS
Bus.

BT_APPEARANCE_VEHICLE_TROLLEY
Trolley.

BT_APPEARANCE_VEHICLE_AGRICULTURAL
Agricultural Vehicle.

BT_APPEARANCE_VEHICLE_CAMPER_OR_CARAVAN
Camper/Caravan.

BT_APPEARANCE_VEHICLE_RECREATIONAL
Recreational Vehicle/Motor Home.

BT_APPEARANCE_GENERIC_DOMESTIC_APPLIANCE
Generic Domestic Appliance.

BT_APPEARANCE_APPLIANCE_REFRIGERATOR
Refrigerator.

BT_APPEARANCE_APPLIANCE_FREEZER
Freezer.

BT_APPEARANCE_APPLIANCE_OVEN
Oven.

BT_APPEARANCE_APPLIANCE_MICROWAVE
Microwave.

BT_APPEARANCE_APPLIANCE_TOASTER
Toaster.

BT_APPEARANCE_APPLIANCE_WASHING_MACHINE
Washing Machine.

BT_APPEARANCE_APPLIANCE_DRYER
Dryer.

BT_APPEARANCE_APPLIANCE_COFFEE_MAKER
Coffee maker.

BT_APPEARANCE_APPLIANCE_CLOTHES_IRON
Clothes iron.

BT_APPEARANCE_APPLIANCE CURLING_IRON
Curling iron.
BT_APPEARANCE_APPLIANCE_HAIR_DRYER
Hair dryer.

BT_APPEARANCE_APPLIANCE_VACUUM_CLEANER
Vacuum cleaner.

BT_APPEARANCE_APPLIANCE_ROBOTIC_VACUUM_CLEANER
Robotic vacuum cleaner.

BT_APPEARANCE_APPLIANCE_RICE_COOKER
Rice cooker.

BT_APPEARANCE_APPLIANCE_CLOTHES_STEAMER
Clothes steamer.

BT_APPEARANCE_GENERIC_WEARABLE_AUDIO_DEVICE
Generic Wearable Audio Device.

BT_APPEARANCE_WEARABLE_AUDIO_DEVICE_EARBUD
Earbud.

BT_APPEARANCE_WEARABLE_AUDIO_DEVICE_HEADSET
Headset.

BT_APPEARANCE_WEARABLE_AUDIO_DEVICE_HEADPHONES
Headphones.

BT_APPEARANCE_WEARABLE_AUDIO_DEVICE_NECK_BAND
Neck Band.

BT_APPEARANCE GENERIC_AIRCRAFT
Generic Aircraft.

BT_APPEARANCE_AIRCRAFT_LIGHT
Light Aircraft.

BT_APPEARANCE_AIRCRAFT_MICROLIGHT
Microlight.

BT_APPEARANCE_AIRCRAFT_PARAGlider
Paraglider.

BT_APPEARANCE_AIRCRAFT_LARGE_PASSENGER
Large Passenger Aircraft.

BT_APPEARANCE GENERIC_AV_EQUIPMENT
Generic AV Equipment.
BT_APPEARANCE_AV_EQUIPMENT_AMPLIFIER
   Amplifier.

BT_APPEARANCE_AV_EQUIPMENT_RECEIVER
   Receiver.

BT_APPEARANCE_AV_EQUIPMENT_RADIO
   Radio.

BT_APPEARANCE_AV_EQUIPMENT_TUNER
   Tuner.

BT_APPEARANCE_AV_EQUIPMENT_TURNTABLE
   Turntable.

BT_APPEARANCE_AV_EQUIPMENT_CDPLAYER
   CD Player.

BT_APPEARANCE_AV_EQUIPMENT_DVDPLAYER
   DVD Player.

BT_APPEARANCE_AV_EQUIPMENT_BLURAYPLAYER
   Bluray Player.

BT_APPEARANCE_AV_EQUIPMENT_OPTICAL_DISCPLAYER
   Optical Disc Player.

BT_APPEARANCE_AV_EQUIPMENT_SET_TOP_BOX
   Set-Top Box.

BT_APPEARANCE_GENERIC_DISPLAY_EQUIPMENT
   Generic Display Equipment.

BT_APPEARANCE_DISPLAY_EQUIPMENT_TELEVISION
   Television.

BT_APPEARANCE_DISPLAY_EQUIPMENT_MONITOR
   Monitor.

BT_APPEARANCE_DISPLAY_EQUIPMENT_PROJECTOR
   Projector.

BT_APPEARANCE_GENERIC_HEARING_AID
   Generic Hearing aid.

BT_APPEARANCE_HEARING_AID_IN_EAR
   In-ear hearing aid.
BT_APPEARANCE_HEARING_AID_BEHIND_EAR
   Behind-ear hearing aid.

BT_APPEARANCE_HEARING_AID_COCHLEAR IMPLANT
   Cochlear Implant.

BT_APPEARANCE_GENERIC_GAMING
   Generic Gaming.

BT_APPEARANCE_HOME_VIDEO_GAME_CONSOLE
   Home Video Game Console.

BT_APPEARANCE_PORTABLE_HANDHELD_CONSOLE
   Portable handheld console.

BT_APPEARANCE_GENERIC_SIGNAGE
   Generic Signage.

BT_APPEARANCE_SIGNAGE_DIGITAL
   Digital Signage.

BT_APPEARANCE_SIGNAGE_ELECTRONIC_LABEL
   Electronic Label.

BT_APPEARANCE_GENERIC_PULSE_OXIMETER
   Generic Pulse Oximeter.

BT_APPEARANCE_PULSE_OXIMETER_FINGERTIP
   Fingertip Pulse Oximeter.

BT_APPEARANCE_PULSE_OXIMETER_WRIST
   Wrist Worn Pulse Oximeter.

BT_APPEARANCE_GENERIC_WEIGHT_SCALE
   Generic Weight Scale.

BT_APPEARANCE_GENERIC_PERSONAL_MOBILITY_DEVICE
   Generic Personal Mobility Device.

BT_APPEARANCE_MOBILITYPOWERED_WHEELCHAIR
   Powered Wheelchair.

BT_APPEARANCE_MOBILITY_SCOOTER
   Mobility Scooter.

BT_APPEARANCE_CONTINUOUS_GLUCOSE_MONITOR
   Continuous Glucose Monitor.
Defined GAP timers

- BT_GAP_SCAN_FAST_INTERVAL
- BT_GAP_SCAN_FAST_WINDOW
- BT_GAP_SCAN_SLOW_INTERVAL_1
- BT_GAP_SCAN_SLOW_WINDOW_1
- BT_GAP_SCAN_SLOW_INTERVAL_2
BT_GAP_SCAN_SLOW_WINDOW_2

BT_GAP_ADV_FAST_INT_MIN_1

BT_GAP_ADV_FAST_INT_MAX_1

BT_GAP_ADV_FAST_INT_MIN_2

BT_GAP_ADV_FAST_INT_MAX_2

BT_GAP_ADV_SLOW_INT_MIN

BT_GAP_ADV_SLOW_INT_MAX

BT_GAP_PER_ADV_FAST_INT_MIN_1

BT_GAP_PER_ADV_FAST_INT_MAX_1

BT_GAP_PER_ADV_FAST_INT_MIN_2

BT_GAP_PER_ADV_FAST_INT_MAX_2

BT_GAP_PER_ADV_SLOW_INT_MIN

BT_GAP_PER_ADV_SLOW_INT_MAX

BT_GAP_INIT_CONN_INT_MIN

BT_GAP_INIT_CONN_INT_MAX

Defines

BT_GAP_ADV_MAX_ADV_DATA_LEN
    Maximum advertising data length.

BT_GAP_ADV_MAX_EXT_ADV_DATA_LEN
    Maximum extended advertising data length.

**Note:** The maximum advertising data length that can be sent by an extended advertiser is defined by the controller.

BT_GAP_TX_POWER_INVALID

BT_GAP_RSSI_INVALID
BT_GAP_SID_INVALID

BT_GAP_NO_TIMEOUT

BT_GAP_ADV_HIGH_DUTY_CYCLE_MAX_TIMEOUT

BT_GAP_DATA_LEN_DEFAULT
  Default data length.

BT_GAP_DATA_LEN_MAX
  Maximum data length.

BT_GAP_DATA_TIME_DEFAULT
  Default data time.

BT_GAP_DATA_TIME_MAX
  Maximum data time.

BT_GAP_SID_MAX
  Maximum advertising set number.

BT_GAP_PER_ADV_MAX_SKIP
  Maximum number of consecutive periodic advertisement events that can be skipped after a successful receive.

BT_GAP_PER_ADV_MIN_TIMEOUT
  Minimum Periodic Advertising Timeout (N * 10 ms)

BT_GAP_PER_ADV_MAX_TIMEOUT
  Maximum Periodic Advertising Timeout (N * 10 ms)

BT_GAP_PER_ADV_MIN_INTERVAL
  Minimum Periodic Advertising Interval (N * 1.25 ms)

BT_GAP_PER_ADV_MAX_INTERVAL
  Maximum Periodic Advertising Interval (N * 1.25 ms)

BT_GAP_PER_ADV_INTERVAL_TO_MS(interval)
  Convert periodic advertising interval (N * 1.25 ms) to milliseconds.
  5 / 4 represents 1.25 ms unit.

BT_LE_SUPP_FEAT_40_ENCODE(w64)
  Encode 40 least significant bits of 64-bit LE Supported Features into array values in little-endian format.

  Helper macro to encode 40 least significant bits of 64-bit LE Supported Features value into advertising data. The number of bits that are encoded is a number of LE Supported Features defined by BT 5.3 Core specification.

  Example of how to encode the 0x000000DF00DF00D into advertising data.
Parameters

- \( w64 \) – LE Supported Features value (64-bits)

Returns

The comma separated values for LE Supported Features value that may be used directly as an argument for \( BT_DATA_BYTES \).

\( BT\_LE\_SUPP\_FEAT\_\_ENCODE(w64) \)

Encode 4 least significant bytes of 64-bit LE Supported Features into 4 bytes long array of values in little-endian format.

Helper macro to encode 64-bit LE Supported Features value into advertising data. The macro encodes 4 least significant bytes into advertising data. Other 4 bytes are not encoded.

Example of how to encode the \( 0x000000DFF00DF00D \) into advertising data.

\( BT\_DATA\_BYTES(BT\_DATA\_LE\_SUPPORTED\_FEATURES, BT\_LE\_SUPP\_FEAT\_\_ENCODE(0x000000DFF00DF00D)) \)

Parameters

- \( w64 \) – LE Supported Features value (64-bits)

Returns

The comma separated values for LE Supported Features value that may be used directly as an argument for \( BT\_DATA\_BYTES \).

\( BT\_LE\_SUPP\_FEAT\_\_ENCODE(w64) \)

Encode 3 least significant bytes of 64-bit LE Supported Features into 3 bytes long array of values in little-endian format.

Helper macro to encode 64-bit LE Supported Features value into advertising data. The macro encodes 3 least significant bytes into advertising data. Other 5 bytes are not encoded.

Example of how to encode the \( 0x000000DFF00DF00D \) into advertising data.

\( BT\_DATA\_BYTES(BT\_DATA\_LE\_SUPPORTED\_FEATURES, BT\_LE\_SUPP\_FEAT\_\_ENCODE(0x000000DFF00DF00D)) \)

Parameters

- \( w64 \) – LE Supported Features value (64-bits)

Returns

The comma separated values for LE Supported Features value that may be used directly as an argument for \( BT\_DATA\_BYTES \).

\( BT\_LE\_SUPP\_FEAT\_\_ENCODE(w64) \)

Encode 2 least significant bytes of 64-bit LE Supported Features into 2 bytes long array of values in little-endian format.

Helper macro to encode 64-bit LE Supported Features value into advertising data. The macro encodes 3 least significant bytes into advertising data. Other 6 bytes are not encoded.

Example of how to encode the \( 0x000000DFF00DF00D \) into advertising data.
BT_DATA_BYTES(BT_DATA_LE_SUPPORTED_FEATURES, BT_LE_SUPP_FEAT_16_ → ENCODE(0x000000DFF00DF00D))

Parameters

- w64 – LE Supported Features value (64-bits)

Returns

The comma separated values for LE Supported Features value that may be used directly as an argument for BT_DATA_BYTES.

BT_LE_SUPP_FEAT_8_ENCODE(w64)

Encode the least significant byte of 64-bit LE Supported Features into single byte long array.

Helper macro to encode 64-bit LE Supported Features value into advertising data. The macro encodes the least significant byte into advertising data. Other 7 bytes are not encoded.

Example of how to encode the 0x000000DFF00DF00D into advertising data.

BT_DATA_BYTES(BT_DATA_LE_SUPPORTED_FEATURES, BT_LE_SUPP_FEAT_8_ → ENCODE(0x000000DFF00DF00D))

Parameters

- w64 – LE Supported Features value (64-bits)

Returns

The value of least significant byte of LE Supported Features value that may be used directly as an argument for BT_DATA_BYTES.

BT_LE_SUPP_FEAT_VALIDATE(w64)

Validate whether LE Supported Features value does not use bits that are reserved for future use.

Helper macro to check if w64 has zeros as bits 40-63. The macro is compliant with BT 5.3 Core Specification where bits 0-40 has assigned values. In case of invalid value, build time error is reported.

Enums

LE PHY types.

Values:

enumerator BT_GAP_LE_PHY_NONE = 0
    Convenience macro for when no PHY is set.

enumerator BT_GAP_LE_PHY_1M = BIT(0)
    LE 1M PHY.

enumerator BT_GAP_LE_PHY_2M = BIT(1)
    LE 2M PHY.
enumerator `BT_GAP_LE_PHY_CODED = BIT(2)`
   LE Coded PHY.

Advertising PDU types.
*Values:*

enumerator `BT_GAP_ADV_TYPE_ADV_IND = 0x00`  
   Scannable and connectable advertising.

enumerator `BT_GAP_ADV_TYPE_ADV_DIRECT_IND = 0x01`  
   Directed connectable advertising.

enumerator `BT_GAP_ADV_TYPE_ADV_SCAN_IND = 0x02`  
   Non-connectable and scannable advertising.

enumerator `BT_GAP_ADV_TYPE_ADV_NONCONN_IND = 0x03`  
   Non-connectable and non-scannable advertising.

enumerator `BT_GAP_ADV_TYPE_SCAN_RSP = 0x04`  
   Additional advertising data requested by an active scanner.

enumerator `BT_GAP_ADV_TYPE_EXT_ADV = 0x05`  
   Extended advertising, see advertising properties.

Advertising PDU properties.
*Values:*

enumerator `BT_GAP_ADV_PROP_CONNECTABLE = BIT(0)`  
   Connectable advertising.

enumerator `BT_GAP_ADV_PROP_SCANNABLE = BIT(1)`  
   Scannable advertising.

enumerator `BT_GAP_ADV_PROP_DIRECTED = BIT(2)`  
   Directed advertising.

enumerator `BT_GAP_ADV_PROP_SCAN_RESPONSE = BIT(3)`  
   Additional advertising data requested by an active scanner.

enumerator `BT_GAP_ADV_PROP_EXT_ADV = BIT(4)`  
   Extended advertising.

Constant Tone Extension (CTE) types.
*Values:*

enumerator BT_GAP_CTE_AOA = 0x00
    Angle of Arrival.

enumerator BT_GAP_CTE_AOD_1US = 0x01
    Angle of Departure with 1 us slots.

enumerator BT_GAP_CTE_AOD_2US = 0x02
    Angle of Departure with 2 us slots.

enumerator BT_GAP_CTE_NONE = 0xFF
    No extensions.

Peripheral sleep clock accuracy (SCA) in ppm (parts per million)
Values:

enumerator BT_GAP_SCA_UNKNOWN = 0
    Unknown.

enumerator BT_GAP_SCA_251_500 = 0
251 ppm to 500 ppm

enumerator BT_GAP_SCA_151_250 = 1
151 ppm to 250 ppm

enumerator BT_GAP_SCA_101_150 = 2
101 ppm to 150 ppm

enumerator BT_GAP_SCA_76_100 = 3
76 ppm to 100 ppm

enumerator BT_GAP_SCA_51_75 = 4
51 ppm to 75 ppm

enumerator BT_GAP_SCA_31_50 = 5
31 ppm to 50 ppm

enumerator BT_GAP_SCA_21_30 = 6
21 ppm to 30 ppm

enumerator BT_GAP_SCA_0_20 = 7
0 ppm to 20 ppm

**Generic Attribute Profile (GATT)**

GATT layer manages the service database providing APIs for service registration and attribute declaration.
Services can be registered using `bt_gatt_service_register()` API which takes the `bt_gatt_service` struct that provides the list of attributes the service contains. The helper macro `BT_GATT_SERVICE()` can be used to declare a service.

Attributes can be declared using the `bt_gatt_attr` struct or using one of the helper macros:

- `BT_GATT_PRIMARY_SERVICE`: Declares a Primary Service.
- `BT_GATT_INCLUDE_SERVICE`: Declares a Include Service.
- `BT_GATT_CHARACTERISTIC`: Declares a Characteristic.
- `BT_GATT_DESCRIPTOR`: Declares a Descriptor.
- `BT_GATT_ATTRIBUTE`: Declares an Attribute.
- `BT_GATT_CCC`: Declares a Client Characteristic Configuration.
- `BT_GATT_CEP`: Declares a Characteristic Extended Properties.
- `BT_GATT_CUD`: Declares a Characteristic User Format.

Each attribute contains a uuid, which describes their type, a read callback, a write callback and a set of permission. Both read and write callbacks can be set to NULL if the attribute permission don't allow their respective operations.

**Note:** 32-bit UUIDs are not supported in GATT. All 32-bit UUIDs shall be converted to 128-bit UUIDs when the UUID is contained in an ATT PDU.

**Note:** Attribute read and write callbacks are called directly from RX Thread thus it is not recommended to block for long periods of time in them.

Attribute value changes can be notified using `bt_gatt_notify()` API, alternatively there is `bt_gatt_notify_cb()` where it is possible to pass a callback to be called when it is necessary to know the exact instant when the data has been transmitted over the air. Indications are supported by `bt_gatt_indicate()` API.

Client procedures can be enabled with the configuration option: `CONFIG_BT_GATT_CLIENT`

Discover procedures can be initiated with the use of `bt_gatt_discover()` API which takes the `bt_gatt_discover_params` struct which describes the type of discovery. The parameters also serve as a filter when setting the `uuid` field only attributes which matches will be discovered, in contrast setting it to NULL allows all attributes to be discovered.

**Note:** Caching discovered attributes is not supported.

Read procedures are supported by `bt_gatt_read()` API which takes the `bt_gatt_read_params` struct as parameters. In the parameters one or more attributes can be set, though setting multiple handles requires the option: `CONFIG_BT_GATT_READ_MULTIPLE`
Write procedures are supported by `bt_gatt_write()` API and takes `bt_gatt_write_params` struct as parameters. In case the write operation don’t require a response `bt_gatt_write_without_response()` or `bt_gatt_write_without_response_cb()` APIs can be used, with the later working similarly to `bt_gatt_notify_cb()`.

Subscriptions to notification and indication can be initiated with use of `bt_gatt_subscribe()` API which takes `bt_gatt_subscribe_params` as parameters. Multiple subscriptions to the same attribute are supported so there could be multiple notify callback being triggered for the same attribute. Subscriptions can be removed with use of `bt_gatt_unsubscribe()` API.

**Note:** When subscriptions are removed notify callback is called with the data set to NULL.

---

**API Reference**

**Related code samples**

**BLE logging backend**

Send log messages over BLE using the BLE logging backend.

---

**group bt_gatt**

Generic Attribute Profile (GATT)

**Defines**

`BT_GATT_ERR(~_att_err)`

Construct error return value for attribute read and write callbacks.

**Parameters**

- `~_att_err` – ATT error code

**Returns**

Appropriate error code for the attribute callbacks.

`BT_GATT_CHRC_BROADCAST`

Characteristic Properties Bit field values.

Characteristic broadcast property.

If set, permits broadcasts of the Characteristic Value using Server Characteristic Configuration Descriptor.

`BT_GATT_CHRC_READ`

Characteristic read property.

If set, permits reads of the Characteristic Value.

`BT_GATT_CHRC_WRITE_WITHOUT_RESP`

Characteristic write without response property.

If set, permits write of the Characteristic Value without response.

`BT_GATT_CHRC_WRITE`

Characteristic write with response property.

If set, permits write of the Characteristic Value with response.
BT_GATT_CHRC_NOTIFY
    Characteristic notify property.
    If set, permits notifications of a Characteristic Value without acknowledgment.

BT_GATT_CHRC_INDICATE
    Characteristic indicate property.
    If set, permits indications of a Characteristic Value with acknowledgment.

BT_GATT_CHRC_AUTH
    Characteristic Authenticated Signed Writes property.
    If set, permits signed writes to the Characteristic Value.

BT_GATT_CHRC_EXT_PROP
    Characteristic Extended Properties property.
    If set, additional characteristic properties are defined in the Characteristic Extended
    Properties Descriptor.

BT_GATT_CEP_RELIABLE_WRITE
    Characteristic Extended Properties Bit field values.

BT_GATT_CEP_WRITABLE_AUX

BT_GATT_CCC_NOTIFY
    Client Characteristic Configuration Values.
    Client Characteristic Configuration Notification.
    If set, changes to Characteristic Value shall be notified.

BT_GATT_CCC_INDICATE
    Client Characteristic Configuration Indication.
    If set, changes to Characteristic Value shall be indicated.

BT_GATT_SCC_BROADCAST
    Server Characteristic Configuration Values.
    Server Characteristic Configuration Broadcast
    If set, the characteristic value shall be broadcast in the advertising data when the
    server is advertising.

**Typedefs**

typedef ssize_t (*bt_gatt_attr_read_func_t)(struct bt_conn *conn, const struct
bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
    Attribute read callback.
    The callback can also be used locally to read the contents of the attribute in which case
    no connection will be set.

**Param conn**
    The connection that is requesting to read
**Param attr**  
The attribute that's being read

**Param buf**  
Buffer to place the read result in

**Param len**  
Length of data to read

**Param offset**  
Offset to start reading from

**Return**  
Number of bytes read, or in case of an error `BT_GATT_ERR()` with a specific `BT_ATT_ERR_*` error code.

typedef ssize_t (*bt_gatt_attr_write_func_t)(struct bt_conn *conn, const struct bt_gatt_attr *attr, const void *buf, uint16_t len, uint16_t offset, uint8_t flags)

Attribute write callback.

**Param conn**  
The connection that is requesting to write

**Param attr**  
The attribute that's being written

**Param buf**  
Buffer with the data to write

**Param len**  
Number of bytes in the buffer

**Param offset**  
Offset to start writing from

**Param flags**  
Flags (`BT_GATT_WRITE_FLAG_*`)

**Return**  
Number of bytes written, or in case of an error `BT_GATT_ERR()` with a specific `BT_ATT_ERR_*` error code.

**Enums**

enum bt_gatt_perm  
GATT attribute permission bit field values.

**Values:**

enumerator `BT_GATT_PERM_NONE` = 0  
No operations supported, e.g.

for notify-only

enumerator `BT_GATT_PERM_READ` = `BIT(0)`  
Attribute read permission.

enumerator `BT_GATT_PERM_WRITE` = `BIT(1)`  
Attribute write permission.

---

6.1. Bluetooth
enumerator BT_GATT_PERM_READ_ENCRYPT = \textit{BIT}(2)
Attribute read permission with encryption.
\begin{itemize}
\item If set, requires encryption for read access.
\end{itemize}

enumerator BT_GATT_PERM_WRITE_ENCRYPT = \textit{BIT}(3)
Attribute write permission with encryption.
\begin{itemize}
\item If set, requires encryption for write access.
\end{itemize}

enumerator BT_GATT_PERM_READ_AUTHEN = \textit{BIT}(4)
Attribute read permission with authentication.
\begin{itemize}
\item If set, requires encryption using authenticated link-key for read access.
\end{itemize}

enumerator BT_GATT_PERM_WRITE_AUTHEN = \textit{BIT}(5)
Attribute write permission with authentication.
\begin{itemize}
\item If set, requires encryption using authenticated link-key for write access.
\end{itemize}

enumerator BT_GATT_PERM_PREPARE_WRITE = \textit{BIT}(6)
Attribute prepare write permission.
\begin{itemize}
\item If set, allows prepare writes with use of `\texttt{BT_GATT_WRITE_FLAG_PREPARE}` passed to write callback.
\end{itemize}

enumerator BT_GATT_PERM_READ_LESC = \textit{BIT}(7)
Attribute read permission with LE Secure Connection encryption.
\begin{itemize}
\item If set, requires that LE Secure Connections is used for read access.
\end{itemize}

enumerator BT_GATT_PERM_WRITE_LESC = \textit{BIT}(8)
Attribute write permission with LE Secure Connection encryption.
\begin{itemize}
\item If set, requires that LE Secure Connections is used for write access.
\end{itemize}

GATT attribute write flags.

\textit{Values:}

enumerator BT_GATT_WRITE_FLAG_PREPARE = \textit{BIT}(0)
Attribute prepare write flag.
\begin{itemize}
\item If set, write callback should only check if the device is authorized but no data shall be written.
\end{itemize}

enumerator BT_GATT_WRITE_FLAG_CMD = \textit{BIT}(1)
Attribute write command flag.
If set, indicates that write operation is a command (Write without response) which doesn't generate any response.

**enumerator BT_GATT_WRITE_FLAG_EXECUTE = BIT(2)**

Attribute write execute flag.

If set, indicates that write operation is a execute, which indicates the end of a long write, and will come after 1 or more @ref BT_GATT_WRITE_FLAG_PREPARE.

```c
struct bt_gatt_attr
#include <gatt.h> GATT Attribute structure.

Public Members

const struct bt_uuid *uuid
Attribute UUID.

bt_gatt_attr_write_func_t write
Attribute write callback.

void *user_data
Attribute user data.

uint16_t handle
Attribute handle.

uint16_t perm
Attribute permissions.
Will be 0 if returned from bt_gatt_discover().

struct bt_gatt_service_static
#include <gatt.h> GATT Service structure.

Public Members

const struct bt_gatt_attr *attrs
Service Attributes.

size_t attr_count
Service Attribute count.

struct bt_gatt_service
#include <gatt.h> GATT Service structure.
```

6.1. Bluetooth
Public Members

struct bt_gatt_attr *attrs
    Service Attributes.

size_t attr_count
    Service Attribute count.

struct bt_gatt_service_val
    #include <gatt.h> Service Attribute Value.

Public Members

const struct bt_uuid *uuid
    Service UUID.

uint16_t end_handle
    Service end handle.

struct bt_gatt_include
    #include <gatt.h> Include Attribute Value.

Public Members

const struct bt_uuid *uuid
    Service UUID.

uint16_t start_handle
    Service start handle.

uint16_t end_handle
    Service end handle.

struct bt_gatt_cb
    #include <gatt.h> GATT callback structure.

Public Members

void (*att_mtu_updated)(struct bt_conn *conn, uint16_t tx, uint16_t rx)
    The maximum ATT MTU on a connection has changed.
    This callback notifies the application that the maximum TX or RX ATT MTU has increased.
    Param conn
        Connection object.
    Param tx
        Updated TX ATT MTU.
Param rx
Updated RX ATT MTU.

struct bt_gatt_authorization_cb
#include <gatt.h> GATT authorization callback structure.

Public Members

bool (*read_authorize)(struct bt_conn *conn, const struct bt_gatt_attr *attr)
Authorize the GATT read operation.
This callback allows the application to authorize the GATT read operation for the attribute that is being read.
  Param conn
   Connection object.
  Param attr
   The attribute that is being read.
  Retval true
   Authorize the operation and allow it to execute.
  Retval false
   Reject the operation and prevent it from executing.

bool (*write_authorize)(struct bt_conn *conn, const struct bt_gatt_attr *attr)
Authorize the GATT write operation.
This callback allows the application to authorize the GATT write operation for the attribute that is being written.
  Param conn
   Connection object.
  Param attr
   The attribute that is being written.
  Retval true
   Authorize the operation and allow it to execute.
  Retval false
   Reject the operation and prevent it from executing.

struct bt_gatt_chrc
#include <gatt.h> Characteristic Attribute Value.

Public Members

const struct bt_uuid *uuid
Characteristic UUID.

uint16_t value_handle
Characteristic Value handle.

uint8_t properties
Characteristic properties.

struct bt_gatt_cep
#include <gatt.h> Characteristic Extended Properties Attribute Value.
Public Members

uint16_t properties
    Characteristic Extended properties.

struct bt_gatt_ccc
    #include <gatt.h> Client Characteristic Configuration Attribute Value.

Public Members

uint16_t flags
    Client Characteristic Configuration flags.

struct bt_gatt_scc
    #include <gatt.h> Server Characteristic Configuration Attribute Value.

Public Members

uint16_t flags
    Server Characteristic Configuration flags.

struct bt_gatt_cpf
    #include <gatt.h> GATT Characteristic Presentation Format Attribute Value.

Public Members

uint8_t format
    Format of the value of the characteristic.

int8_t exponent
    Exponent field to determine how the value of this characteristic is further formatted.

uint16_t unit
    Unit of the characteristic.

uint8_t name_space
    Name space of the description.

uint16_t description
    Description of the characteristic as defined in a higher layer profile.

GATT Server

group bt_gatt_server
Defines

**BT_GATT_SERVICE_DEFINE(_name, ...)**
Statically define and register a service.
Helper macro to statically define and register a service.

**Parameters**
- **_name** – Service name.

**BT_GATT_SERVICE_INSTANCE_DEFINE(_name, _instances, _instance_num, _attrs_def)**
Statically define service structure array.
Helper macro to statically define service structure array. Each element of the array is linked to the service attribute array which is also defined in this scope using _attrs_def macro.

**Parameters**
- **_name** – Name of service structure array.
- **_instances** – Array of instances to pass as user context to the attribute callbacks.
- **_instance_num** – Number of elements in instance array.
- **_attrs_def** – Macro provided by the user that defines attribute array for the service. This macro should accept single parameter which is the instance context.

**BT_GATT_SERVICE(_attrs)**
Service Structure Declaration Macro.
Helper macro to declare a service structure.

**Parameters**
- **_attrs** – Service attributes.

**BT_GATT_PRIMARY_SERVICE(_service)**
Primary Service Declaration Macro.
Helper macro to declare a primary service attribute.

**Parameters**
- **_service** – Service attribute value.

**BT_GATT_SECONDARY_SERVICE(_service)**
Secondary Service Declaration Macro.
Helper macro to declare a secondary service attribute.

**Note:** A secondary service is only intended to be included from a primary service or another secondary service or other higher layer specification.

**Parameters**
- **_service** – Service attribute value.

**BT_GATT_INCLUDE_SERVICE(_service_incl)**
Include Service Declaration Macro.
Helper macro to declare database internal include service attribute.

**Parameters**
• `_service_incl` – the first service attribute of service to include

```
BT_GATT_CHRC_INIT(_uuid, _handle, _props)
```

```
BT_GATT_CHARACTERISTIC(_uuid, _props, _perm, _read, _write, _user_data)
```

Characteristic and Value Declaration Macro.

Helper macro to declare a characteristic attribute along with its attribute value.

**Parameters**

- `_uuid` – Characteristic attribute uuid.
- `_props` – Characteristic attribute properties, a bitmap of `BT_GATT_CHRC_*` macros.
- `_perm` – Characteristic Attribute access permissions, a bitmap of `bt_gatt_perm` values.
- `_read` – Characteristic Attribute read callback (`bt_gatt_attr_read_func_t`).
- `_write` – Characteristic Attribute write callback (`bt_gatt_attr_write_func_t`).
- `_user_data` – Characteristic Attribute user data.

```
BT_GATT_CCC_MAX
```

```
BT_GATT_CCC_INITIALIZER(_changed, _write, _match)
```

Initialize Client Characteristic Configuration Declaration Macro.

Helper macro to initialize a Managed CCC attribute value.

**Parameters**

- `_changed` – Configuration changed callback.
- `_write` – Configuration write callback.
- `_match` – Configuration match callback.

```
BT_GATT_CCC_MANAGED(_ccc, _perm)
```

Managed Client Characteristic Configuration Declaration Macro.

Helper macro to declare a Managed CCC attribute.

**Parameters**

- `_ccc` – CCC attribute user data, shall point to a `_bt_gatt_ccc`.
- `_perm` – CCC access permissions, a bitmap of `bt_gatt_perm` values.

```
BT_GATT_CCC(_changed, _perm)
```

Client Characteristic Configuration Declaration Macro.

Helper macro to declare a CCC attribute.

**Parameters**

- `_changed` – Configuration changed callback.
- `_perm` – CCC access permissions, a bitmap of `bt_gatt_perm` values.

```
BT_GATT_CEP(_value)
```

Characteristic Extended Properties Declaration Macro.

Helper macro to declare a CEP attribute.

**Parameters**

- `_value` – Pointer to a struct `bt_gatt_cep`. 
BT_GATT_CUD(_value, _perm)
Characteristic User Format Descriptor Declaration Macro.
Helper macro to declare a CUD attribute.

Parameters
- _value – User description NULL-terminated C string.
- _perm – Descriptor attribute access permissions, a bitmap of bt_gatt_perm values.

BT_GATT_CPF(_value)
Characteristic Presentation Format Descriptor Declaration Macro.
Helper macro to declare a CPF attribute.

Parameters
- _value – Pointer to a struct bt_gatt_cpf.

BT_GATT_DESCRIPTOR(_uuid, _perm, _read, _write, _user_data)
Descriptor Declaration Macro.
Helper macro to declare a descriptor attribute.

Parameters
- _uuid – Descriptor attribute uuid.
- _perm – Descriptor attribute access permissions, a bitmap of bt_gatt_perm values.
- _read – Descriptor attribute read callback (bt_gatt_attr_read_func_t).
- _write – Descriptor attribute write callback (bt_gatt_attr_write_func_t).
- _user_data – Descriptor attribute user data.

BT_GATT_ATTRIBUTE(_uuid, _perm, _read, _write, _user_data)
Attribute Declaration Macro.
Helper macro to declare an attribute.

Parameters
- _uuid – Attribute uuid.
- _perm – Attribute access permissions, a bitmap of bt_gatt_perm values.
- _read – Attribute read callback (bt_gatt_attr_read_func_t).
- _write – Attribute write callback (bt_gatt_attr_write_func_t).
- _user_data – Attribute user data.

Typedefs

typedef uint8_t (*bt_gatt_attr_func_t)(const struct bt_gatt_attr *attr, uint16_t handle, void *user_data)
Attribute iterator callback.

Param attr
Attribute found.

Param handle
Attribute handle found.
**Param user_data**
Data given.

**Return**
BT_GATT_ITER_CONTINUE if should continue to the next attribute.

**Return**
BT_GATT_ITER_STOP to stop.

typedef void (*bt_gatt_complete_func_t)(struct bt_conn *conn, void *user_data)
Notification complete result callback.

**Param conn**
Connection object.

**Param user_data**
Data passed in by the user.

typedef void (*bt_gatt_indicate_func_t)(struct bt_conn *conn, struct bt_gatt_indicate_params *params, uint8_t err)
Indication complete result callback.

**Param conn**
Connection object.

**Param params**
Indication params object.

**Param err**
ATT error code

typedef void (*bt_gatt_indicate_params_destroy_t)(struct bt_gatt_indicate_params *params)

**Enums**

**Values:**

enumerator BT_GATT_ITER_STOP = 0

enumerator BT_GATT_ITER_CONTINUE

**Functions**

void bt_gatt_cb_register(struct bt_gatt_cb *cb)
Register GATT callbacks.

Register callbacks to monitor the state of GATT. The callback struct must remain valid for the remainder of the program.

**Parameters**

- cb – Callback struct.
int bt_gatt_authorization_cb_register(const struct bt_gatt_authorization_cb *cb)
Register GATT authorization callbacks.

Register callbacks to perform application-specific authorization of GATT operations on all registered GATT attributes. The callback structure must remain valid throughout the entire duration of the Bluetooth subsys activity.

The CONFIG_BT_GATT_AUTHORIZATION_CUSTOM Kconfig must be enabled to make this API functional.

This API allows the user to register only one callback structure concurrently. Passing NULL unregisters the previous set of callbacks and makes it possible to register a new one.

Parameters
• cb – Callback struct.

Returns
Zero on success or negative error code otherwise

int bt_gatt_service_register(struct bt_gatt_service *svc)
Register GATT service.

Register GATT service. Applications can make use of macros such as BT_GATT_PRIMARY_SERVICE, BT_GATT_CHARACTERISTIC, BT_GATT_DESCRIPTOR, etc.

When using CONFIG_BT_SETTINGS then all services that should have bond configuration loaded, i.e. CCC values, must be registered before calling settings_load.

When using CONFIG_BT_GATT_CACHING and CONFIG_BT_SETTINGS then all services that should be included in the GATT Database Hash calculation should be added before calling settings_load. All services registered after settings_load will trigger a new database hash calculation and a new hash stored.

There are two situations where this function can be called: either before bt_init() has been called, or after settings_load() has been called. Registering a service in the middle is not supported and will return an error.

Parameters
• svc – Service containing the available attributes

Returns
0 in case of success or negative value in case of error.

Returns
-EAGAIN if bt_init() has been called but settings_load() hasn't yet.

int bt_gatt_service_unregister(struct bt_gatt_service *svc)
Unregister GATT service.

Parameters
• svc – Service to be unregistered.

Returns
0 in case of success or negative value in case of error.

bool bt_gatt_service_is_registered(const struct bt_gatt_service *svc)
Check if GATT service is registered.

Parameters
• svc – Service to be checked.

Returns
true if registered or false if not register.
void bt_gatt_foreach_attr_type(uint16_t start_handle, uint16_t end_handle, const struct bt_uuid *uuid, const void *attr_data, uint16_t num_matches, bt_gatt_attr_func_t func, void *user_data)

Attribute iterator by type.
Iterate attributes in the given range matching given UUID and/or data.

**Parameters**
- **start_handle** – Start handle.
- **end_handle** – End handle.
- **uuid** – UUID to match, passing NULL skips UUID matching.
- **attr_data** – Attribute data to match, passing NULL skips data matching.
- **num_matches** – Number matches, passing 0 makes it unlimited.
- **func** – Callback function.
- **user_data** – Data to pass to the callback.

static inline void bt_gatt_foreach_attr(uint16_t start_handle, uint16_t end_handle, bt_gatt_attr_func_t func, void *user_data)

Attribute iterator.
Iterate attributes in the given range.

**Parameters**
- **start_handle** – Start handle.
- **end_handle** – End handle.
- **func** – Callback function.
- **user_data** – Data to pass to the callback.

struct bt_gatt_attr *bt_gatt_attr_next(const struct bt_gatt_attr *attr)

Iterate to the next attribute.
Iterate to the next attribute following a given attribute.

**Parameters**
- **attr** – Current Attribute.

**Returns**
The next attribute or NULL if it cannot be found.

struct bt_gatt_attr *bt_gatt_find_by_uuid(const struct bt_gatt_attr *attr, uint16_t attr_count, const struct bt_uuid *uuid)

Find Attribute by UUID.
Find the attribute with the matching UUID. To limit the search to a service set the **attr** to the service attributes and the **attr_count** to the service attribute count.

**Parameters**
- **attr** – Pointer to an attribute that serves as the starting point for the search of a match for the UUID. Passing NULL will search the entire range.
- **attr_count** – The number of attributes from the starting point to search for a match for the UUID. Set to 0 to search until the end.
- **uuid** – UUID to match.
uint16_t bt_gatt_attr_get_handle(const struct bt_gatt_attr *attr)
Get Attribute handle.

**Parameters**
- attr – Attribute object.

**Returns**
Handle of the corresponding attribute or zero if the attribute could not be found.

uint16_t bt_gatt_attr_value_handle(const struct bt_gatt_attr *attr)
Get the handle of the characteristic value descriptor.

**Note:** The user_data of the attribute must of type `bt_gatt_chrc`.

**Parameters**
- attr – A Characteristic Attribute.

**Returns**
the handle of the corresponding Characteristic Value. The value will be zero (the invalid handle) if attr was not a characteristic attribute.

ssize_t bt_gatt_attr_read(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t buf_len, uint16_t offset, const void *value, uint16_t value_len)
Generic Read Attribute value helper.
Read attribute value from local database storing the result into buffer.

**Parameters**
- conn – Connection object.
- attr – Attribute to read.
- buf – Buffer to store the value.
- buf_len – Buffer length.
- offset – Start offset.
- value – Attribute value.
- value_len – Length of the attribute value.

**Returns**
number of bytes read in case of success or negative values in case of error.

ssize_t bt_gatt_attr_read_service(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
Read Service Attribute helper.
Read service attribute value from local database storing the result into buffer after encoding it.

**Note:** Only use this with attributes which user_data is a `bt_uuid`.

**Parameters**
- conn – Connection object.
- attr – Attribute to read.
buf – Buffer to store the value read.

len – Buffer length.

offset – Start offset.

Returns
number of bytes read in case of success or negative values in case of error.

ssize_t bt_gatt_attr_read_included(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)

Read Include Attribute helper.

Read include service attribute value from local database storing the result into buffer after encoding it.

Note: Only use this with attributes which user_data is a bt_gatt_include.

Parameters
- conn – Connection object.
- attr – Attribute to read.
- buf – Buffer to store the value read.
- len – Buffer length.
- offset – Start offset.

Returns
number of bytes read in case of success or negative values in case of error.

ssize_t bt_gatt_attr_read_chrc(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)

Read Characteristic Attribute helper.

Read characteristic attribute value from local database storing the result into buffer after encoding it.

Note: Only use this with attributes which user_data is a bt_gatt_chrc.

Parameters
- conn – Connection object.
- attr – Attribute to read.
- buf – Buffer to store the value read.
- len – Buffer length.
- offset – Start offset.

Returns
number of bytes read in case of success or negative values in case of error.

ssize_t bt_gatt_attr_read_ccc(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)

Read Client Characteristic Configuration Attribute helper.

Read CCC attribute value from local database storing the result into buffer after encoding it.
Zephyr Project Documentation, Release 3.6.0-rc3

Note: Only use this with attributes which user_data is a _bt_gatt_ccc.

Parameters
- conn – Connection object.
- attr – Attribute to read.
- buf – Buffer to store the value read.
- len – Buffer length.
- offset – Start offset.

Returns
number of bytes read in case of success or negative values in case of error.

 ssize_t bt_gatt_attr_write_ccc(struct bt_conn *conn, const struct bt_gatt_attr *attr, const void *buf, uint16_t len, uint16_t offset, uint8_t flags)
Write Client Characteristic Configuration Attribute helper.
Write value in the buffer into CCC attribute.

Note: Only use this with attributes which user_data is a _bt_gatt_ccc.

Parameters
- conn – Connection object.
- attr – Attribute to read.
- buf – Buffer to store the value read.
- len – Buffer length.
- offset – Start offset.
- flags – Write flags.

Returns
number of bytes written in case of success or negative values in case of error.

 ssize_t bt_gatt_attr_read_cep(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
Read Characteristic Extended Properties Attribute helper.
Read CEP attribute value from local database storing the result into buffer after encoding it.

Note: Only use this with attributes which user_data is a bt_gatt_cep.

Parameters
- conn – Connection object
- attr – Attribute to read
- buf – Buffer to store the value read
- len – Buffer length

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• offset – Start offset

**Returns**

number of bytes read in case of success or negative values in case of error.

```c
ssize_t bt_gatt_attr_read_cud(const struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
```

Read Characteristic User Description Descriptor Attribute helper.

Read CUD attribute value from local database storing the result into buffer after encoding it.

**Note:** Only use this with attributes which user_data is a NULL-terminated C string.

**Parameters**

- conn – Connection object
- attr – Attribute to read
- buf – Buffer to store the value read
- len – Buffer length
- offset – Start offset

**Returns**

number of bytes read in case of success or negative values in case of error.

```c
ssize_t bt_gatt_attr_read_cpfc(const struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
```

Read Characteristic Presentation format Descriptor Attribute helper.

Read CPF attribute value from local database storing the result into buffer after encoding it.

**Note:** Only use this with attributes which user_data is a bt_gatt_pf.

**Parameters**

- conn – Connection object
- attr – Attribute to read
- buf – Buffer to store the value read
- len – Buffer length
- offset – Start offset

**Returns**

number of bytes read in case of success or negative values in case of error.

```c
int bt_gatt_notify_cb(const struct bt_conn *conn, const struct bt_gatt_notify_params *params)
```

Notify attribute value change.

This function works in the same way as `bt_gatt_notify`. With the addition that after sending the notification the callback function will be called.

The callback is run from System Workqueue context. When called from the System Workqueue context this API will not wait for resources for the callback but instead return an error. The number of pending callbacks can be increased with the CONFIG_BT_CONN_TX_MAX option.
Alternatively it is possible to notify by UUID by setting it on the parameters, when using this method the attribute if provided is used as the start range when looking up for possible matches.

**Parameters**
- conn – Connection object.
- params – Notification parameters.

**Returns**
0 in case of success or negative value in case of error.

```c
int bt_gatt_notify_multiple(struct bt_conn *conn, uint16_t num_params, struct bt_gatt_notify_params params[])
```

Send multiple notifications in a single PDU.

The GATT Server will send a single ATT_MULTIPLE_HANDLE_VALUE_NTF PDU containing all the notifications passed to this API.

All `params` must have the same `func` and `user_data` (due to implementation limitation). But `func(user_data)` will be invoked for each parameter.

As this API may block to wait for Bluetooth Host resources, it is not recommended to call it from a cooperative thread or a Bluetooth callback.

The peer’s GATT Client must write to this device’s Client Supported Features attribute and set the bit for Multiple Handle Value Notifications before this API can be used.

Only use this API to force the use of the ATT_MULTIPLE_HANDLE_VALUE_NTF PDU. For standard applications, `bt_gatt_notify_cb` is preferred, as it will use this PDU if supported and automatically fallback to ATT_HANDLE_VALUE_NTF when not supported by the peer.

This API has an additional limitation: it only accepts valid attribute references and not UUIDs like `bt_gatt_notify` and `bt_gatt_notify_cb`.

**Parameters**
- conn – Target client. Notifying all connected clients by passing NULL is not yet supported, please use `bt_gatt_notify` instead.
- num_params – Element count of `params` array. Has to be greater than 1.
- params – Array of notification parameters. It is okay to free this after calling this function.

**Return values**
- 0 – Success. The PDU is queued for sending.
- -EINVAL –
  - One of the attribute handles is invalid.
  - Only one parameter was passed. This API expects 2 or more.
  - Not all `func` were equal or not all `user_data` were equal.
  - One of the characteristics is not notifiable.
  - An UUID was passed in one of the parameters.
- -ERANGE –
  - The notifications cannot all fit in a single ATT_MULTIPLE_HANDLE_VALUE_NTF.
  - They exceed the MTU of all open ATT bearers.
• -EPERM – The connection has a lower security level than required by one of the attributes.
• -EOPNOTSUPP – The peer hasn’t yet communicated that it supports this PDU type.

static inline int bt_gatt_notify(struct bt_conn *conn, const struct bt_gatt_attr *attr, const void *data, uint16_t len)

Notify attribute value change.

Send notification of attribute value change, if connection is NULL notify all peer that have notification enabled via CCC otherwise do a direct notification only the given connection.

The attribute object on the parameters can be the so called Characteristic Declaration, which is usually declared with BT_GATT_CHARACTERISTIC followed by BT_GATT_CCC, or the Characteristic Value Declaration which is automatically created after the Characteristic Declaration when using BT_GATT_CHARACTERISTIC.

Parameters
• conn – Connection object.
• attr – Characteristic or Characteristic Value attribute.
• data – Pointer to Attribute data.
• len – Attribute value length.

Returns
0 in case of success or negative value in case of error.

static inline int bt_gatt_notify_uuid(struct bt_conn *conn, const struct bt_uuid *uuid, const struct bt_gatt_attr *attr, const void *data, uint16_t len)

Notify attribute value change by UUID.

Send notification of attribute value change, if connection is NULL notify all peer that have notification enabled via CCC otherwise do a direct notification only on the given connection.

The attribute object is the starting point for the search of the UUID.

Parameters
• conn – Connection object.
• uuid – The UUID. If the server contains multiple services with the same UUID, then the first occurrence, starting from the attr given, is used.
• attr – Pointer to an attribute that serves as the starting point for the search of a match for the UUID.
• data – Pointer to Attribute data.
• len – Attribute value length.

Returns
0 in case of success or negative value in case of error.

int bt_gatt_indicate(struct bt_conn *conn, struct bt_gatt_indicate_params *params)

Indicate attribute value change.

Send an indication of attribute value change. If connection is NULL indicate all peer that have notification enabled via CCC otherwise do a direct indication only the given connection.

The attribute object on the parameters can be the so called Characteristic Declaration, which is usually declared with BT_GATT_CHARACTERISTIC followed by BT_GATT_CCC,
or the Characteristic Value Declaration which is automatically created after the Characteristic Declaration when using BT_GATT_CHARACTERISTIC.

Alternatively it is possible to indicate by UUID by setting it on the parameters, when using this method the attribute if provided is used as the start range when looking up for possible matches.

**Note:** This procedure is asynchronous therefore the parameters need to remain valid while it is active. The procedure is active until the destroy callback is run.

### Parameters

- `conn` – Connection object.
- `params` – Indicate parameters.

### Returns

0 in case of success or negative value in case of error.

```c
bool bt_gatt_is_subscribed(struct bt_conn *conn, const struct bt_gatt_attr *attr, uint16_t ccc_type)
```

Check if connection has subscribed to attribute.

Check if connection has subscribed to attribute value change.

The attribute object can be the so-called Characteristic Declaration, which is usually declared with BT_GATT_CHARACTERISTIC followed by BT_GATT_CCC, or the Characteristic Value Declaration which is automatically created after the Characteristic Declaration when using BT_GATT_CHARACTERISTIC, or the Client Characteristic Configuration Descriptor (CCCD) which is created by BT_GATT_CCC.

### Parameters

- `conn` – Connection object.
- `attr` – Attribute object.
- `ccc_type` – The subscription type, `BT_GATT_CCC_NOTIFY` and/or `BT_GATT_CCC_INDICATE`.

### Returns

true if the attribute object has been subscribed.

```c
uint16_t bt_gatt_get_mtu(struct bt_conn *conn)
```

Get ATT MTU for a connection.

Get negotiated ATT connection MTU, note that this does not equal the largest amount of attribute data that can be transferred within a single packet.

### Parameters

- `conn` – Connection object.

### Returns

MTU in bytes

```c
struct bt_gatt_ccc_cfg
#include <gatt.h> GATT CCC configuration entry.
```

### Public Members

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uint8_t id
    Local identity, BT_ID_DEFAULT in most cases.

bt_addr_le_t peer
    Remote peer address.

uint16_t value
    Configuration value.

struct bt_gatt_notify_params
    #include <gatt.h>

Public Members

const struct bt_uuid *uuid
    Notification Attribute UUID type.
    Optional, use to search for an attribute with matching UUID when the attribute
    object pointer is not known.

const struct bt_gatt_attr *attr
    Notification Attribute object.
    Optional if uuid is provided, in this case it will be used as start range to search for
    the attribute with the given UUID.

const void *data
    Notification Value data.

uint16_t len
    Notification Value length.

bt_gatt_complete_func_t func
    Notification Value callback.

void *user_data
    Notification Value callback user data.

struct bt_gatt_indicate_params
    #include <gatt.h> GATT Indicate Value parameters.

Public Members

const struct bt_uuid *uuid
    Indicate Attribute UUID type.
    Optional, use to search for an attribute with matching UUID when the attribute
    object pointer is not known.
const struct \texttt{bt\_gatt\_attr} *\texttt{attr}

Indicate Attribute object.

Optional if uuid is provided, in this case it will be used as start range to search for
the attribute with the given UUID.

\texttt{bt\_gatt\_indicate\_func\_t} \texttt{func}

Indicate Value callback.

\texttt{bt\_gatt\_indicate\_params\_destroy\_t} \texttt{destroy}

Indicate operation complete callback.

const void *\texttt{data}

Indicate Value data.

\texttt{uint16\_t} \texttt{len}

Indicate Value length.

\textbf{GATT Client}

\textit{group} \texttt{bt\_gatt\_client}

\textbf{Typedefs}

\texttt{typedef uint8\_t (*bt\_gatt\_discover\_func\_t)(struct bt\_conn *conn, const struct \texttt{bt\_gatt\_attr} *attr, struct \texttt{bt\_gatt\_discover\_params} *params)}

Discover attribute callback function.

If discovery procedure has completed this callback will be called with \texttt{attr} set to \texttt{NULL}.
This will not happen if procedure was stopped by returning \texttt{BT\_GATT\_ITER\_STOP}.

The attribute object as well as its UUID and value objects are temporary and must be
copied to in order to cache its information. Only the following fields of the attribute
contains valid information:

\begin{itemize}
  \item \texttt{uuid} UUID representing the type of attribute.
  \item \texttt{handle} Handle in the remote database.
  \item \texttt{user\_data} The value of the attribute, if the discovery type maps to an ATT operation
  that provides this information. \texttt{NULL} otherwise. See below.
\end{itemize}

The effective type of \texttt{attr->user\_data} is determined by \texttt{params}. Note that the fields
\texttt{params->type} and \texttt{params->uuid} are left unchanged by the discovery procedure.
Also consider if using read-by-type instead of discovery is more convenient. See `bt_gatt_read` with `bt_gatt_read_params::handle_count` set to 0.

**Param conn**
Connection object.

**Param attr**
Attribute found, or NULL if not found.

**Param params**
Discovery parameters given.

**Return**
BT_GATT_ITER_CONTINUE to continue discovery procedure.

**Return**
BT_GATT_ITER_STOP to stop discovery procedure.

typedef uint8_t (*bt_gatt_read_func_t)(struct bt_conn *conn, uint8_t err , struct bt_gatt_read_params *params, const void *data, uint16_t length)

Read callback function.

When reading using by_uuid, params->start_handle is the attribute handle for this data item.

**Param conn**
Connection object.

**Param err**
ATT error code.

**Param params**
Read parameters used.

**Param data**
Attribute value data. NULL means read has completed.

**Param length**
Attribute value length.

**Return**
BT_GATT_ITER_CONTINUE if should continue to the next attribute.

**Return**
BT_GATT_ITER_STOP to stop.

typedef void (*bt_gatt_write_func_t)(struct bt_conn *conn, uint8_t err , struct bt_gatt_write_params *params)

Write callback function.
**Param conn**
Connection object.

**Param err**
ATT error code.

**Param params**
Write parameters used.

typedef uint8_t (*bt_gatt_notify_func_t)(struct bt_conn *conn, struct bt_gatt_subscribe_params *params, const void *data, uint16_t length)

Notification callback function.

In the case of an empty notification, the data pointer will be non-NUL while the length will be 0, which is due to the special case where a data NULL pointer means unsubscribed.

**Param conn**
Connection object. May be NULL, indicating that the peer is being unpaired

**Param params**
Subscription parameters.

**Param data**
Attribute value data. If NULL then subscription was removed.

**Param length**
Attribute value length.

**Return**
BT_GATT_ITER_CONTINUE to continue receiving value notifications.
BT_GATT_ITER_STOP to unsubscribe from value notifications.

typedef void (*bt_gatt_subscribe_func_t)(struct bt_conn *conn, uint8_t err, struct bt_gatt_subscribe_params *params)

Subscription callback function.

**Param conn**
Connection object.

**Param err**
ATT error code.

**Param params**
Subscription parameters used.

**Enums**

GATT Discover types.

*Values:*

enumerator BT_GATT_DISCOVER_PRIMARY
Discover Primary Services.

eumerator BT_GATT_DISCOVER_SECONDARY
Discover Secondary Services.
enumerator BT_GATT_DISCOVER_INCLUDE
Discover Included Services.

enumerator BT_GATT_DISCOVER_CHARACTERISTIC
Discover Characteristic Values.

Discover Characteristic Value and its properties.

enumerator BT_GATT_DISCOVER_DESCRIPTOR
Discover Descriptors.

Discover Attributes which are not services or characteristics.

@note The use of this type of discover is not recommended for discovering in ranges across multiple services/characteristics as it may incur in extra round trips.

enumerator BT_GATT_DISCOVER_ATTRIBUTE
Discover Attributes.

Discover Attributes of any type.

@note The use of this type of discover is not recommended for discovering in ranges across multiple services/characteristics as it may incur in more round trips.

enumerator BT_GATT_DISCOVER_STD_CHAR_DESC
Discover standard characteristic descriptor values.

Discover standard characteristic descriptor values and their properties.

Supported descriptors:
- Characteristic Extended Properties
- Client Characteristic Configuration
- Server Characteristic Configuration
- Characteristic Presentation Format

Subscription flags.

Values:

enumerator BT_GATT_SUBSCRIBE_FLAG_VOLATILE
Persistence flag.

If set, indicates that the subscription is not saved on the GATT server side. Therefore, upon disconnection, the subscription will be automatically removed from the client's subscriptions list and when the client reconnects, it will have to issue a new subscription.

enumerator BT_GATT_SUBSCRIBE_FLAG_NO_RESUB
No resubscribe flag.
By default when BT_GATT_SUBSCRIBE_FLAG_VOLATILE is unset, the subscription will be automatically renewed when the client reconnects, as a workaround for GATT servers that do not persist subscriptions.

This flag will disable the automatic resubscription. It is useful if the application layer knows that the GATT server remembers subscriptions from previous connections and wants to avoid renewing the subscriptions.

enumerator BT_GATT_SUBSCRIBE_FLAG_WRITE_PENDING
Write pending flag.
- If set, indicates write operation is pending waiting remote end to respond.
  @note Internal use only.

enumerator BT_GATT_SUBSCRIBE_FLAG_SENT
Sent flag.
- If set, indicates that a subscription request (CCC write) has already been sent in the active connection.
  Used to avoid sending subscription requests multiple times when the \htmlonly <code>CONFIG_BT_GATT_AUTO_RESUBSCRIBE</code> \endhtmlonly \xmlonly <verbatim>embed:rst:inline :kconfig:option:`CONFIG_BT_GATT_AUTO_RESUBSCRIBE`</verbatim> \endxmlonly quirk is enabled.
  @note Internal use only.

enumerator BT_GATT_SUBSCRIBE_NUM_FLAGS

Functions

int bt_gatt_exchange_mtu(struct bt_conn *conn, struct bt_gatt_exchange_params *params)

Exchange MTU.
This client procedure can be used to set the MTU to the maximum possible size the buffers can hold.

The Response comes in callback params->func. The callback is run from the context specified by ‘config BT_RECV_CONTEXT’. params must remain valid until start of callback.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

**Note:** Shall only be used once per connection.

**Parameters**

- **conn** – Connection object.
• **params** – Exchange MTU parameters.

**Return values**

- 0 – Successfully queued request. Will call `params->func` on resolution.
- -ENOMEM – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by `CONFIG_BT_ATT_TX_COUNT`.
- -EALREADY – The MTU exchange procedure has been already performed.

```c
int bt_gatt_discover(struct bt_conn *conn, struct bt_gatt_discover_params *params)
```

GATT Discover function.

This procedure is used by a client to discover attributes on a server.

Primary Service Discovery: Procedure allows to discover primary services either by Discover All Primary Services or Discover Primary Services by Service UUID. Include Service Discovery: Procedure allows to discover all Include Services within specified range. Characteristic Discovery: Procedure allows to discover all characteristics within specified handle range as well as discover characteristics with specified UUID. Descriptors Discovery: Procedure allows to discover all characteristic descriptors within specified range.

For each attribute found the callback is called which can then decide whether to continue discovering or stop.

The Response comes in callback `params->func`. The callback is run from the BT RX thread. `params` must remain valid until start of callback where `iter attr` is NULL or callback will return `BT_GATT_ITER_STOP`.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

**Parameters**

- `conn` – Connection object.
- `params` – Discover parameters.

**Return values**

- 0 – Successfully queued request. Will call `params->func` on resolution.
- -ENOMEM – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by `CONFIG_BT_ATT_TX_COUNT`.

```c
int bt_gatt_read(struct bt_conn *conn, struct bt_gatt_read_params *params)
```

Read Attribute Value by handle.

This procedure read the attribute value and return it to the callback.

When reading attributes by UUID the callback can be called multiple times depending on how many instances of given the UUID exists with the start_handle being updated for each instance.

To perform a GATT Long Read procedure, start with a Characteristic Value Read (by setting `offset` 0 and `handle_count` 1) and then return `BT_GATT_ITER_CONTINUE` from the callback. This is equivalent to calling `bt_gatt_read` again, but with the correct offset to continue the read. This may be repeated until the procedure is complete, which is signaled by the callback being called with data set to NULL.

Note that returning `BT_GATT_ITER_CONTINUE` is really starting a new ATT operation, so this can fail to allocate resources. However, all API errors are reported as if the
server returned \texttt{BT\_ATT\_ERR\_UNLIKELY}. There is no way to distinguish between this condition and a \texttt{BT\_ATT\_ERR\_UNLIKELY} response from the server itself.

Note that the effect of returning \texttt{BT\_GATT\_ITER\_CONTINUE} from the callback varies depending on the type of read operation.

The Response comes in callback \texttt{params-\textgreater{}func}. The callback is run from the context specified by \texttt{\textasciitilde{}config BT\_RECV\_CONTEXT}. \texttt{params} must remain valid until start of callback.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

**Parameters**

- \texttt{conn} – Connection object.
- \texttt{params} – Read parameters.

**Return values**

- 0 – Successfully queued request. Will call \texttt{params-\textgreater{}func} on resolution.
- \texttt{-ENOMEM} – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by \texttt{CONFIG\_BT\_ATT\_TX\_COUNT}.

```c
int bt_gatt_write(struct bt_conn *conn, struct bt_gatt_write_params *params)
```

Write Attribute Value by handle.

The Response comes in callback \texttt{params-\textgreater{}func}. The callback is run from the context specified by \texttt{\textasciitilde{}config BT\_RECV\_CONTEXT}. \texttt{params} must remain valid until start of callback.

This function will block while the ATT request queue is full, except when called from Bluetooth event context. When called from Bluetooth context, this function will instead instead return \texttt{-ENOMEM} if it would block to avoid a deadlock.

**Parameters**

- \texttt{conn} – Connection object.
- \texttt{params} – Write parameters.

**Return values**

- 0 – Successfully queued request. Will call \texttt{params-\textgreater{}func} on resolution.
- \texttt{-ENOMEM} – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside Bluetooth event context to get blocking behavior. Queue size is controlled by \texttt{CONFIG\_BT\_ATT\_TX\_COUNT}.

```c
int bt_gatt_write_without_response_cb(struct bt_conn *conn, uint16_t handle, const void *data, uint16_t length, bool sign, bt_gatt_complete_func_t func, void *user_data)
```

Write Attribute Value by handle without response with callback.

This function works in the same way as \texttt{bt_gatt_write_without_response}. With the addition that after sending the write the callback function will be called.

The callback is run from System Workqueue context. When called from the System Workqueue context this API will not wait for resources for the callback but instead return an error. The number of pending callbacks can be increased with the \texttt{CONFIG\_BT\_CONN\_TX\_MAX} option.
This function will block while the ATT request queue is full, except when called from
the BT RX thread, as this would cause a deadlock.

**Note:** By using a callback it also disable the internal flow control which would prevent
sending multiple commands without waiting for their transmissions to complete, so if
that is required the caller shall not submit more data until the callback is called.

### Parameters
- `conn` – Connection object.
- `handle` – Attribute handle.
- `data` – Data to be written.
- `length` – Data length.
- `sign` – Whether to sign data
- `func` – Transmission complete callback.
- `user_data` – User data to be passed back to callback.

### Return values
- `0` – Successfully queued request.
- `-ENOMEM` – ATT request queue is full and blocking would cause deadlock.
  Allow a pending request to resolve before retrying, or call this function
  outside the BT RX thread to get blocking behavior. Queue size is con-
trolled by `CONFIG_BT_ATT_TX_COUNT`.

```c
static inline int bt_gatt_write_without_response(struct bt_conn *conn, uint16_t handle,
                                                const void *data, uint16_t length, bool
                                                sign)
```

Write Attribute Value by handle without response.

This procedure write the attribute value without requiring an acknowledgment that
the write was successfully performed

This function will block while the ATT request queue is full, except when called from
the BT RX thread, as this would cause a deadlock.

### Parameters
- `conn` – Connection object.
- `handle` – Attribute handle.
- `data` – Data to be written.
- `length` – Data length.
- `sign` – Whether to sign data

### Return values
- `0` – Successfully queued request.
- `-ENOMEM` – ATT request queue is full and blocking would cause deadlock.
  Allow a pending request to resolve before retrying, or call this function
  outside the BT RX thread to get blocking behavior. Queue size is con-
trolled by `CONFIG_BT_ATT_TX_COUNT`.

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int bt_gatt_subscribe(struct bt_conn *conn, struct bt_gatt_subscribe_params *params)

Subscribe Attribute Value Notification.

This procedure subscribe to value notification using the Client Characteristic Configuration handle. If notification received subscribe value callback is called to return notified value. One may then decide whether to unsubscribe directly from this callback. Notification callback with NULL data will not be called if subscription was removed by this method.

The Response comes in callback params->subscribe. The callback is run from the context specified by ‘config BT_RECV_CONTEXT’. The Notification callback params->notify is also called from the BT RX thread.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

Note: Notifications are asynchronous therefore the params must remain valid while subscribed and cannot be reused for additional subscriptions whilst active.

Parameters

• conn – Connection object.
• params – Subscribe parameters.

Return values

• 0 – Successfully queued request. Will call params->write on resolution.
• -ENOMEM – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by CONFIG_BT_ATT_TX_COUNT.
• -EALREADY – if there already exist a subscription using the params.
• -EBUSY – if params.ccc_handle is 0 and CONFIG_BT_GATT_AUTO_DISCOVER_CCC is enabled and discovery for the params is already in progress.

int bt_gatt_resubscribe(uint8_t id, const bt_addr_le_t *peer, struct bt_gatt_subscribe_params *params)

Resubscribe Attribute Value Notification subscription.

Resubscribe to Attribute Value Notification when already subscribed from a previous connection. The GATT server will remember subscription from previous connections when bonded, so resubscribing can be done without performing a new subscribe procedure after a power cycle.

Note: Notifications are asynchronous therefore the parameters need to remain valid while subscribed.

Parameters

• id – Local identity (in most cases BT_ID_DEFAULT).
• peer – Remote address.
• params – Subscribe parameters.
Returns
0 in case of success or negative value in case of error.

```c
int bt_gatt_unsubscribe(struct bt_conn *conn, struct bt_gatt_subscribe_params *params)
```

Unsubscribe Attribute Value Notification.

This procedure unsubscribe to value notification using the Client Characteristic Configuration handle. Notification callback with NULL data will be called if subscription was removed by this call, until then the parameters cannot be reused.

The Response comes in callback `params->func`. The callback is run from the BT RX thread.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

**Parameters**

- **conn** – Connection object.
- **params** – Subscribe parameters.

**Return values**

- `'0` – Successfully queued request. Will call `params->write` on resolution.
- `-ENOMEM` – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by `CONFIG_BT_ATT_TX_COUNT`.

```c
void bt_gatt_cancel(struct bt_conn *conn, void *params)
```

Try to cancel the first pending request identified by `params`.

This function does not release `params` for reuse. The usual callbacks for the request still apply. A successful cancel simulates a `BT_ATT_ERR_UNLIKELY` response from the server.

This function can cancel the following request functions:

- `bt_gatt_exchange_mtu`
- `bt_gatt_discover`
- `bt_gatt_read`
- `bt_gatt_write`
- `bt_gatt_subscribe`
- `bt_gatt_unsubscribe`

**Parameters**

- **conn** – The connection the request was issued on.
- **params** – The address `params` used in the request function call.

```c
struct bt_gatt_exchange_params
```

`#include <gatt.h>` GATT Exchange MTU parameters.

**Public Members**
void (*func)(struct bt_conn *conn, uint8_t err, struct bt_gatt_exchange_params *params)
   Response callback.

struct bt_gatt_discover_params
   #include <gatt.h> GATT Discover Attributes parameters.

   Public Members

   const struct bt_uuid *uuid
      Discover UUID type.

   bt_gatt_discover_func_t func
      Discover attribute callback.

   uint16_t attr_handle
      Include service attribute declaration handle.

   uint16_t start_handle
      Included service start handle.
      Discover start handle.

   uint16_t end_handle
      Included service end handle.
      Discover end handle.

   uint8_t type
      Discover type.

   struct bt_gatt_subscribe_params *sub_params
      Only for stack-internal use, used for automatic discovery.

struct bt_gatt_read_params
   #include <gatt.h> GATT Read parameters.

   Public Members

   bt_gatt_read_func_t func
      Read attribute callback.

   size_t handle_count
      If equals to 1 single.handle and single.offset are used.
      If greater than 1 multiple.handles are used. If equals to 0 by_uuid is used for Read
      Using Characteristic UUID.
**Public Members**

*bt_gatt_write_func_t* `func`
Response callback.

uint16_t `handle`
Attribute handle.

uint16_t `offset`
Attribute data offset.

const void *`data`
Data to be written.

uint16_t `length`
Length of the data.

struct `bt_gatt_subscribe_params`
GATT Subscribe parameters.

```c
#include <gatt.h>
```
Public Members

```c
bt_gatt_notify_func_t notify
    Notification value callback.
```

```c
bt_gatt_subscribe_func_t subscribe
    Subscribe CCC write request response callback If given, called with the subscription parameters given when subscribing.
```

```c
bt_gatt_write_func_t write
    Deprecated:
```

```c
uint16_t value_handle
    Subscribe value handle.
```

```c
uint16_t ccc_handle
    Subscribe CCC handle.
```

```c
uint16_t end_handle
    Subscribe End handle (for automatic discovery)
```

```c
struct bt_gatt_discover_params *disc_params
    Discover parameters used when ccc_handle = 0.
```

```c
uint16_t value
    Subscribe value.
```

```c
bt_security_t min_security
    Minimum required security for received notification.
    Notifications and indications received over a connection with a lower security level are silently discarded.
```

```c
atomic_t flags[ATOMICT_BITMAP_SIZE(BT_GATT_SUBSCRIBE_NUM_FLAGS)]
    Subscription flags.
```

HCI Drivers

API Reference

```c
bt_hci_driver
    HCI drivers.
```

Defines

```c
IS_BT_QUIRK_NO_AUTO_DLE(bt_dev)
```

```c
BT_HCI_EVT_FLAG_RECV_PRIO
```
 enums

 Enums

 Values:

 enumerator BT_QUIRK_NO_RESET = BIT(0)

 enumerator BT_QUIRK_NO_AUTO_DLE = BIT(1)

 enum bt_hci_driver_bus
 Possible values for the ‘bus’ member of the bt_hci_driver struct.
 Values:

 enumerator BT_HCI_DRIVER_BUS_VIRTUAL = 0

 enumerator BT_HCI_DRIVER_BUS_USB = 1

 enumerator BT_HCI_DRIVER_BUS_PCCARD = 2

 enumerator BT_HCI_DRIVER_BUS_UART = 3

 enumerator BT_HCI_DRIVER_BUS_RS232 = 4

 enumerator BT_HCI_DRIVER_BUS_PCI = 5

 enumerator BT_HCI_DRIVER_BUS_SDIO = 6

 enumerator BT_HCI_DRIVER_BUS_SPI = 7

 enumerator BT_HCI_DRIVER_BUS_I2C = 8

 enumerator BT_HCI_DRIVER_BUS_IPM = 9

 Functions

 static inline uint8_t bt_hci_evt_get_flags(uint8_t evt)
 Get HCI event flags.
 Helper for the HCI driver to get HCI event flags that describes rules that must be followed.
 When CONFIG_BT_RECV_BLOCKING is enabled the flags BT_HCI_EVT_FLAG_RECV and BT_HCI_EVT_FLAG_RECV_PRIO indicates if the event should be given to bt_recv or bt_recv_prio.

 Parameters
• \texttt{evt} – HCI event code.

\textbf{Returns}

HCI event flags for the specified event.

\texttt{int bt\_recv(\textbf{struct net\_buf } *buf)}

Receive data from the controller/HCI driver.

This is the main function through which the HCI driver provides the host with data from the controller. The buffer needs to have its type set with the help of \texttt{bt\_buf\_set\_type()} before calling this API.

When \texttt{CONFIG\_BT\_RECV\_BLOCKING} is defined then this API should not be used for so-called high priority HCI events, which should instead be delivered to the host stack through \texttt{bt\_recv\_prio()}.

\textbf{Note:} This function must only be called from a cooperative thread.

\textbf{Parameters}

• \texttt{buf} – Network buffer containing data from the controller.

\textbf{Returns}

0 on success or negative error number on failure.

\texttt{int bt\_recv\_prio(\textbf{struct net\_buf } *buf)}

Receive high priority data from the controller/HCI driver.

This is the same as \texttt{bt\_recv()}, except that it should be used for so-called high priority HCI events. There's a separate \texttt{bt\_hci\_evt\_get\_flags()} helper that can be used to identify which events have the BT\_HCI\__EVT\_FLAG\_RECV\_PRIO flag set.

As with \texttt{bt\_recv()}, the buffer needs to have its type set with the help of \texttt{bt\_buf\_set\_type()} before calling this API. The only exception is so called high priority HCI events which should be delivered to the host stack through \texttt{bt\_recv\_prio()} instead.

\textbf{Parameters}

• \texttt{buf} – Network buffer containing data from the controller.

\textbf{Returns}

0 on success or negative error number on failure.

\texttt{uint8\_t \texttt{bt\_read\_static\_addr(\textbf{struct bt\_hci\_vs\_static\_addr } addrs[], uint8\_t size)}}

Read static addresses from the controller.

\textbf{Parameters}

• \texttt{addrs} – Random static address and Identity Root (IR) array.

• \texttt{size} – Size of array.

\textbf{Returns}

Number of addresses read.

\texttt{int bt\_hci\_driver\_register(\textbf{const struct bt\_hci\_driver } *drv)}}

Register a new HCI driver to the Bluetooth stack.

This needs to be called before any application code runs. The \texttt{bt\_enable()} API will fail if there is no driver registered.

\textbf{Parameters}

• \texttt{drv} – A \texttt{bt\_hci\_driver} struct representing the driver.
Returns
0 on success or negative error number on failure.

```c
int bt_hci_transport_setup(const struct device *dev)
```

Setup the HCI transport, which usually means to reset the Bluetooth IC.

**Note:** A weak version of this function is included in the H4 driver, so defining it is optional per board.

**Parameters**
- `dev` – The device structure for the bus connecting to the IC

**Returns**
0 on success, negative error value on failure

```c
int bt_hci_transport_teardown(const struct device *dev)
```

Teardown the HCI transport.

**Note:** A weak version of this function is included in the IPC driver, so defining it is optional. NRF5340 includes support to put network core in reset state.

**Parameters**
- `dev` – The device structure for the bus connecting to the IC

**Returns**
0 on success, negative error value on failure

```c
struct net_buf *bt_hciEvtCreate(uint8_t evt, uint8_t len)
```

Allocate an HCI event buffer.

This function allocates a new buffer for an HCI event. It is given the event code and the total length of the parameters. Upon successful return the buffer is ready to have the parameters encoded into it.

**Parameters**
- `len` – Length of event parameters.

**Returns**
Newly allocated buffer.

```c
struct net_buf *bt_hciCmdCompleteCreate(uint16_t op, uint8_t plen)
```

Allocate an HCI Command Complete event buffer.

This function allocates a new buffer for HCI Command Complete event. It is given the OpCode (encoded e.g. using the BT_OP macro) and the total length of the parameters. Upon successful return the buffer is ready to have the parameters encoded into it.

**Parameters**
- `plen` – Length of command parameters.

**Returns**
Newly allocated buffer.
struct net_buf * bt_hci_cmd_status_create(uint16_t op, uint8_t status)
Allocate an HCI Command Status event buffer.

This function allocates a new buffer for HCI Command Status event. It is given the OpCode (encoded e.g. using the BT_OP macro) and the status code. Upon successful return the buffer is ready to have the parameters encoded into it.

**Parameters**

- status – Status code.

**Returns**
Newly allocated buffer.

struct bt_hci_setup_params
#include <hci_driver.h>

**Public Members**

*bt_addr_t* public_addr
The public identity address to give to the controller.

This field is used when the driver selects CONFIG_BT_HCI_SET_PUBLIC_ADDR to indicate that it supports setting the controller’s public address.

struct bt_hci_driver
#include <hci_driver.h> Abstraction which represents the HCI transport to the controller.

This struct is used to represent the HCI transport to the Bluetooth controller.

**Public Members**

*const char* *name*
Name of the driver.

*enum bt_hci_driver_bus* bus
Bus of the transport (BT_HCI_DRIVER_BUS_*)

*uint32_t* quirks
Specific controller quirks.

These are set by the HCI driver and acted upon by the host. They can either be statically set at buildtime, or set at runtime before the HCI driver’s *open*() callback returns.

*int (*open)(void)*
Open the HCI transport.

Opens the HCI transport for operation. This function must not return until the transport is ready for operation, meaning it is safe to start calling the *send*() handler.

If the driver uses its own RX thread, i.e. CONFIG_BT_RECV_BLOCKING is set, then this function is expected to start that thread.

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**Return**

0 on success or negative error number on failure.

```c
int (*close)(void)
```

Close the HCI transport.

Closes the HCI transport. This function must not return until the transport is closed.

If the driver uses its own RX thread, i.e. `CONFIG_BT_RECV_BLOCKING` is set, then this function is expected to abort that thread.

**Return**

0 on success or negative error number on failure.

```c
int (*send)(struct net_buf *buf)
```

Send HCI buffer to controller.

Send an HCI command or ACL data to the controller. The exact type of the data can be checked with the help of `bt_buf_get_type()`.

**Note:** This function must only be called from a cooperative thread.

**Param buf**

Buffer containing data to be sent to the controller.

**Return**

0 on success or negative error number on failure.

```c
int (*setup)(const struct bt_hci_setup_params *params)
```

HCI vendor-specific setup.

Executes vendor-specific commands sequence to initialize BT Controller before BT Host executes Reset sequence.

**Note:** `CONFIG_BT_HCI_SETUP` must be selected for this field to be available.

**Return**

0 on success or negative error number on failure.

---

**HCI RAW channel**

**Overview**

HCI RAW channel API is intended to expose HCI interface to the remote entity. The local Bluetooth controller gets owned by the remote entity and host Bluetooth stack is not used. RAW API provides direct access to packets which are sent and received by the Bluetooth HCI driver.

**API Reference**

- **group hci_raw**
  
  HCI RAW channel.

**Defines**
BT_HCI_ERR_EXTHandled

BT_HCI_RAW_CMD_EXT(_op, _min_len, _func)
Helper macro to define a command extension.

Parameters
• _op – Opcode of the command.
• _min_len – Minimal length of the command.
• _func – Handler function to be called.

Enums

Values:

enumerator BT_HCI_RAW_MODE_PASSTHROUGH = 0x00
Passthrough mode.
While in this mode the buffers are passed as is between the stack and the driver.

enumerator BT_HCI_RAW_MODE_H4 = 0x01
H:4 mode.
While in this mode H:4 headers will added into the buffers according to the buffer type when coming from the stack and will be removed and used to set the buffer type.

Functions

int bt_send(struct net_buf *buf)
Send packet to the Bluetooth controller.
Send packet to the Bluetooth controller. Caller needs to implement netbuf pool.

Parameters
• buf – netbuf packet to be send

Returns
Zero on success or (negative) error code otherwise.

int bt_hci_raw_set_mode(uint8_t mode)
Set Bluetooth RAW channel mode.
Set access mode of Bluetooth RAW channel.

Parameters
• mode – Access mode.

Returns
Zero on success or (negative) error code otherwise.
uint8_t bt_hci_raw_get_mode(void)

Get Bluetooth RAW channel mode.

Get access mode of Bluetooth RAW channel.

Returns
Access mode.

void bt_hci_raw_cmd_ext_register(struct bt_hci_raw_cmd_ext *cmds, size_t size)

Register Bluetooth RAW command extension table.

Register Bluetooth RAW channel command extension table, opcodes in this table are
intercepted to sent to the handler function.

Parameters

• cmds – Pointer to the command extension table.
• size – Size of the command extension table.

int bt_enable_raw(struct k_fifo *rx_queue)

Enable Bluetooth RAW channel:

Enable Bluetooth RAW HCI channel.

Parameters

• rx_queue – netbuf queue where HCI packets received from the Bluetooth
controller are to be queued. The queue is defined in the caller while the
available buffers pools are handled in the stack.

Returns
Zero on success or (negative) error code otherwise.

#include <hci_raw.h>

Public Members

uint16_t op

Opcode of the command.

size_t min_len

Minimal length of the command.

uint8_t (*func)(struct net_buf *buf)

Handler function.

Handler function to be called when a command is intercepted.

Param buf

Buffer containing the command.

Return
HCI Status code or BT_HCI_ERR_EXT_HANDLED if command has
been handled already and a response has been sent as oppose to
BT_HCI_ERR_SUCCESS which just indicates that the command can be sent
to the controller to be processed.
Hands Free Profile (HFP)

API Reference

group bt_hfp

Groups

Hands Free Profile (HFP)

Defines

HFP_HF_CMD_OK

HFP_HF_CMD_ERROR

HFP_HF_CMD_CME_ERROR

HFP_HF_CMD_UNKNOWN_ERROR

Enums

enum bt_hfp_hf_at_cmd

Values:

enumerator BT_HFP_HF_ATA

enumerator BT_HFP_HF_AT_CHUP

Functions

int bt_hfp_hf_register(struct bt_hfp_hf_cb *cb)

Register HFP HF profile.

Register Handsfree profile callbacks to monitor the state and get the required HFP details to display.

Parameters

• cb – callback structure.

Returns

0 in case of success or negative value in case of error.

int bt_hfp_hf_send_cmd(struct bt_conn *conn, enum bt_hfp_hf_at_cmd cmd)

Send specific AT commands to handsfree client profile.

Parameters

• conn – Connection object.

• cmd – AT command to be sent.

Returns

0 in case of success or negative value in case of error.
struct bt_hfp_hf_cmd_complete
#include <hfp_hf.h>  // HFP HF Command completion field.

struct bt_hfp_hf_cb
#include <hfp_hf.h>  // HFP profile application callback.

Public Members

void (*connected)(struct bt_conn *conn)
  HF connected callback to application.
  If this callback is provided it will be called whenever the connection completes.
  Param conn
    Connection object.

void (*disconnected)(struct bt_conn *conn)
  HF disconnected callback to application.
  If this callback is provided it will be called whenever the connection gets disconnected, including when a connection gets rejected or cancelled or any error in SLC establishment.
  Param conn
    Connection object.

void (*service)(struct bt_conn *conn, uint32_t value)
  HF indicator Callback.
  This callback provides service indicator value to the application
  Param conn
    Connection object.
  Param value
    service indicator value received from the AG.

void (*call)(struct bt_conn *conn, uint32_t value)
  HF indicator Callback.
  This callback provides call indicator value to the application
  Param conn
    Connection object.
  Param value
    call indicator value received from the AG.

void (*call_setup)(struct bt_conn *conn, uint32_t value)
  HF indicator Callback.
  This callback provides call setup indicator value to the application
  Param conn
    Connection object.
  Param value
    call setup indicator value received from the AG.

void (*call_held)(struct bt_conn *conn, uint32_t value)
  HF indicator Callback.
  This callback provides call held indicator value to the application
Param conn
Connection object.

Param value
call held indicator value received from the AG.

void (*signal)(struct bt_conn *conn, uint32_t value)
HF indicator Callback.
This callback provides signal indicator value to the application
  Param conn
  Connection object.
  Param value
  signal indicator value received from the AG.

void (*roam)(struct bt_conn *conn, uint32_t value)
HF indicator Callback.
This callback provides roaming indicator value to the application
  Param conn
  Connection object.
  Param value
  roaming indicator value received from the AG.

void (*battery)(struct bt_conn *conn, uint32_t value)
HF indicator Callback.
This callback battery service indicator value to the application
  Param conn
  Connection object.
  Param value
  battery indicator value received from the AG.

void (*ring_indication)(struct bt_conn *conn)
HF incoming call Ring indication callback to application.
If this callback is provided it will be called whenever there is an incoming call.
  Param conn
  Connection object.

void (*cmd_complete_cb)(struct bt_conn *conn, struct bt_hfp_hf_cmd_complete *cmd)
HF notify command completed callback to application.
The command sent from the application is notified about its status
  Param conn
  Connection object.
  Param cmd
  structure contains status of the command including cme.

Logical Link Control and Adaptation Protocol (L2CAP)

L2CAP layer enables connection-oriented channels which can be enable with the configuration option: CONFIG_BT_L2CAP_DYNAMIC_CHANNEL. This channels support segmentation and reassembly transparently, they also support credit based flow control making it suitable for data streams.

Channels instances are represented by the bt_12cap_chan struct which contains the callbacks in the bt_12cap_chan_ops struct to inform when the channel has been connected, disconnected or when the encryption has changed. In addition to that it also contains the recv callback which
is called whenever an incoming data has been received. Data received this way can be marked as processed by returning 0 or using `bt_l2cap_chan_recv_complete()` API if processing is asynchronous.

**Note:** The `recv` callback is called directly from RX Thread thus it is not recommended to block for long periods of time.

For sending data the `bt_l2cap_chan_send()` API can be used noting that it may block if no credits are available, and resuming as soon as more credits are available.

Servers can be registered using `bt_l2cap_server_register()` API passing the `bt_l2cap_server` struct which informs what `psm` it should listen to, the required security level `sec_level`, and the callback `accept` which is called to authorize incoming connection requests and allocate channel instances.

Client channels can be initiated with use of `bt_l2cap_chan_connect()` API and can be disconnected with the `bt_l2cap_chan_disconnect()` API. Note that the later can also disconnect channel instances created by servers.

**API Reference**

*group* `bt_l2cap`

L2CAP.

**Defines**

`BT_L2CAP_HDR_SIZE`

L2CAP PDU header size, used for buffer size calculations.

`BT_L2CAP_TX_MTU`

Maximum Transmission Unit (MTU) for an outgoing L2CAP PDU.

`BT_L2CAP_RX_MTU`

Maximum Transmission Unit (MTU) for an incoming L2CAP PDU.

`BT_L2CAP_BUF_SIZE(mtu)`

Helper to calculate needed buffer size for L2CAP PDUs.

Useful for creating buffer pools.

**Parameters**

- `mtu` – Needed L2CAP PDU MTU.

**Returns**

Needed buffer size to match the requested L2CAP PDU MTU.

`BT_L2CAP_SDU_HDR_SIZE`

L2CAP SDU header size, used for buffer size calculations.

`BT_L2CAP_SDU_TX_MTU`

Maximum Transmission Unit for an unsegmented outgoing L2CAP SDU.

The Maximum Transmission Unit for an outgoing L2CAP SDU when sent without segmentation, i.e. a single L2CAP SDU will fit inside a single L2CAP PDU.
The MTU for outgoing L2CAP SDUs with segmentation is defined by the size of the application buffer pool.

**BT_L2CAP_SDU_RX_MTU**

Maximum Transmission Unit for an unsegmented incoming L2CAP SDU.

The Maximum Transmission Unit for an incoming L2CAP SDU when sent without segmentation, i.e. a single L2CAP SDU will fit inside a single L2CAP PDU.

The MTU for incoming L2CAP SDUs with segmentation is defined by the size of the application buffer pool. The application will have to define an alloc_buf callback for the channel in order to support receiving segmented L2CAP SDUs.

**BT_L2CAP_SDU_BUF_SIZE(mtu)**

Helper to calculate needed buffer size for L2CAP SDUs.

Useful for creating buffer pools.

**Parameters**

- **mtu** – Required BT_L2CAP_*_SDU.

**Returns**

Needed buffer size to match the requested L2CAP SDU MTU.

**BT_L2CAP_LE_CHAN(_ch)**

Helper macro getting container object of type `bt_l2cap_le_chan` address having the same container chan member address as object in question.

**Parameters**

- **_ch** – Address of object of `bt_l2cap_chan` type

**Returns**

Address of in memory `bt_l2cap_le_chan` object type containing the address of in question object.

**BT_L2CAP_CHAN_SEND_RESERVE**

Headroom needed for outgoing L2CAP PDUs.

**BT_L2CAP_SDU_CHAN_SEND_RESERVE**

Headroom needed for outgoing L2CAP SDUs.

**Typedefs**

typedef void (*bt_l2cap_chan_destroy_t)(struct `bt_l2cap_chan` *chan)

Channel destroy callback.

**Param chan**

Channel object.

typedef enum `bt_l2cap_chan_state` bt_l2cap_chan_state_t

Life-span states of L2CAP CoC channel.

Used only by internal APIs dealing with setting channel to proper state depending on operational context.

A channel enters the **BT_L2CAP_CONNECTING** state upon `bt_l2cap_chan_connect`, `bt_l2cap_ecred_chan_connect` or upon returning from `bt_l2cap_server::accept`. 6.1. Bluetooth
When a channel leaves the `BT_L2CAP_CONNECTING` state, `bt_l2cap_chan_ops::connected` is called.

typedef enum `bt_l2cap_chan_status` bt_l2cap_chan_status_t
Status of L2CAP channel.

**Enums**

`enum bt_l2cap_chan_state`  
Life-span states of L2CAP CoC channel.

Used only by internal APIs dealing with setting channel to proper state depending on operational context.

A channel enters the `BT_L2CAP_CONNECTING` state upon `bt_l2cap_chan_connect`, `bt_l2cap_ecred_chan_connect` or upon returning from `bt_l2cap_server::accept`.

When a channel leaves the `BT_L2CAP_CONNECTING` state, `bt_l2cap_chan_ops::connected` is called.

Values:

enumerator `BT_L2CAP_DISCONNECTED`  
Channel disconnected.

enumerator `BT_L2CAP_CONNECTING`  
Channel in connecting state.

enumerator `BT_L2CAP_CONFIG`  
Channel in config state, BR/EDR specific.

enumerator `BT_L2CAP_CONNECTED`  
Channel ready for upper layer traffic on it.

enumerator `BT_L2CAP_DISCONNECTING`  
Channel in disconnecting state.

`enum bt_l2cap_chan_status`  
Status of L2CAP channel.

Values:

enumerator `BT_L2CAP_STATUS_OUT`  
Channel can send at least one PDU.

enumerator `BT_L2CAP_STATUS_SHUTDOWN`  
Channel shutdown status.

Once this status is notified it means the channel will no longer be able to transmit or receive data.

enumerator `BT_L2CAP_STATUS_ENCRYPT_PENDING`  
Channel encryption pending status.
enumerator BT_L2CAP_NUM_STATUS

Functions

int bt_l2cap_server_register(struct bt_l2cap_server *server)
Register L2CAP server.

Register L2CAP server for a PSM, each new connection is authorized using the accept() callback which in case of success shall allocate the channel structure to be used by the new connection.

For fixed, SIG-assigned PSMs (in the range 0x0001-0x007f) the PSM should be assigned to server->psm before calling this API. For dynamic PSMs (in the range 0x0080-0x00ff) server->psm may be pre-set to a given value (this is however not recommended) or be left as 0, in which case upon return a newly allocated value will have been assigned to it. For dynamically allocated values the expectation is that it's exposed through a GATT service, and that's how L2CAP clients discover how to connect to the server.

Parameters
  • server – Server structure.

Returns
  0 in case of success or negative value in case of error.

int bt_l2cap_br_server_register(struct bt_l2cap_server *server)
Register L2CAP server on BR/EDR oriented connection.

Register L2CAP server for a PSM, each new connection is authorized using the accept() callback which in case of success shall allocate the channel structure to be used by the new connection.

Parameters
  • server – Server structure.

Returns
  0 in case of success or negative value in case of error.

int bt_l2cap_ecred_chan_connect(struct bt_conn *conn, struct bt_l2cap_chan **chans, uint16_t psm)
Connect Enhanced Credit Based L2CAP channels.

Connect up to 5 L2CAP channels by PSM, once the connection is completed each channel connected() callback will be called. If the connection is rejected disconnected() callback is called instead.

Parameters
  • conn – Connection object.
  • chans – Array of channel objects.
  • psm – Channel PSM to connect to.

Returns
  0 in case of success or negative value in case of error.

int bt_l2cap_ecred_chan_reconfigure(struct bt_l2cap_chan **chans, uint16_t mtu)
Reconfigure Enhanced Credit Based L2CAP channels.

Reconfigure up to 5 L2CAP channels. Channels must be from the same bt_conn. Once reconfiguration is completed each channel reconfigured() callback will be called. MTU cannot be decreased on any of provided channels.
Parameters

- `chans` – Array of channel objects. Null-terminated. Elements after the first 5 are silently ignored.
- `mtu` – Channel MTU to reconfigure to.

Returns

0 in case of success or negative value in case of error.

```c
int bt_l2cap_chan_connect(struct bt_conn *conn, struct bt_l2cap_chan *chan, uint16_t psm)
```

Connect L2CAP channel.

Connect L2CAP channel by PSM, once the connection is completed channel connected() callback will be called. If the connection is rejected disconnected() callback is called instead. Channel object passed (over an address of it) as second parameter shouldn’t be instantiated in application as standalone. Instead of, application should create transport dedicated L2CAP objects, i.e. type of `bt_l2cap_le_chan` for LE and/or type of `bt_l2cap_br_chan` for BR/EDR. Then pass to this API the location (address) of `bt_l2cap_chan` type object which is a member of both transport dedicated objects.

Parameters

- `conn` – Connection object.
- `chan` – Channel object.
- `psm` – Channel PSM to connect to.

Returns

0 in case of success or negative value in case of error.

```c
int bt_l2cap_chan_disconnect(struct bt_l2cap_chan *chan)
```

Disconnect L2CAP channel.

Disconnect L2CAP channel, if the connection is pending it will be canceled and as a result the channel disconnected() callback is called. Regarding to input parameter, to get details see reference description to `bt_l2cap_chan_connect()` API above.

Parameters

- `chan` – Channel object.

Returns

0 in case of success or negative value in case of error.

```c
int bt_l2cap_chan_send(struct bt_l2cap_chan *chan, struct net_buf *buf)
```

Send data to L2CAP channel.

Send data from buffer to the channel. If credits are not available, buf will be queued and sent as and when credits are received from peer. Regarding to first input parameter, to get details see reference description to `bt_l2cap_chan_connect()` API above.

When sending L2CAP data over an BR/EDR connection the application is sending L2CAP PDUs. The application is required to have reserved `BT_L2CAP_CHAN_SEND_RESERVE` bytes in the buffer before sending. The application should use the `BT_L2CAP_BUF_SIZE()` helper to correctly size the buffers for the for outgoing buffer pool.

When sending L2CAP data over an LE connection the application is sending L2CAP SDUs. The application shall reserve `BT_L2CAP_SDU_CHAN_SEND_RESERVE` bytes in the buffer before sending.

The application can use the `BT_L2CAP_SDU_BUF_SIZE()` helper to correctly size the buffer to account for the reserved headroom.
When segmenting an L2CAP SDU into L2CAP PDUs the stack will first attempt to allocate buffers from the channel's alloc_seg callback and will fallback on the stack's global buffer pool (sized CONFIG_BT_L2CAP_TX_BUF_COUNT).

**Note:** Buffer ownership is transferred to the stack in case of success, in case of an error the caller retains the ownership of the buffer.

**Returns**

- 0 in case of success or negative value in case of error.

- EINVAL if buf or chan is NULL.

- EINVAL if chan is not either BR/EDR or LE credit-based.

- EINVAL if buffer doesn't have enough bytes reserved to fit header.

- EMSGSIZE if buf is larger than chan's MTU.

- ENOTCONN if underlying conn is disconnected.

- ESHUTDOWN if L2CAP channel is disconnected.

- other (from lower layers) if chan is BR/EDR.

```c
int bt_l2cap_chan_give_credits(struct bt_l2cap_chan *chan, uint16_t additional_credits)
```

Give credits to the remote.

Only available for channels using `bt_l2cap_chan_ops::seg_recv`. CONFIG_BT_L2CAP_SEG_RECV must be enabled to make this function available.

Each credit given allows the peer to send one segment.

This function depends on a valid chan object. Make sure to default-initialize or memset chan when allocating or reusing it for new connections.

Adding zero credits is not allowed.

Credits can be given before entering the `BT_L2CAP_CONNECTING` state. Doing so will adjust the 'initial credits' sent in the connection PDU.

Must not be called while the channel is in `BT_L2CAP_CONNECTING` state.

**Returns**

- 0 in case of success or negative value in case of error.

```c
int bt_l2cap_chan_recv_complete(struct bt_l2cap_chan *chan, struct net_buf *buf)
```

Complete receiving L2CAP channel data.

Complete the reception of incoming data. This shall only be called if the channel recv callback has returned -EINPROGRESS to process some incoming data. The buffer shall contain the original user_data as that is used for storing the credits/segments used by the packet.

**Parameters**

- chan – Channel object.
- buf – Buffer containing the data.
Returns
0 in case of success or negative value in case of error.

struct bt_l2cap_chan
#include <l2cap.h> L2CAP Channel structure.

Public Members

struct bt_conn *conn
   Channel connection reference.

const struct bt_l2cap_chan_ops *ops
   Channel operations reference.

struct bt_l2cap_le_endpoint
#include <l2cap.h> LE L2CAP Endpoint structure.

Public Members

uint16_t cid
   Endpoint Channel Identifier (CID)

uint16_t mtu
   Endpoint Maximum Transmission Unit.

uint16_t mps
   Endpoint Maximum PDU payload Size.

uint16_t init_credits
   Endpoint initial credits.

atomic_t credits
   Endpoint credits.

struct bt_l2cap_le_chan
#include <l2cap.h> LE L2CAP Channel structure.

Public Members

struct bt_l2cap_chan chan
   Common L2CAP channel reference object.

struct bt_l2cap_le_endpoint rx
   Channel Receiving Endpoint.

If the application has set an alloc_buf channel callback for the channel to support receiving segmented L2CAP SDUs the application should initialize the MTU of the
Receiving Endpoint. Otherwise the MTU of the receiving endpoint will be initialized to `BT_L2CAP_SDU_RX_MTU` by the stack.

This is the source of the MTU, MPS and credit values when sending `L2CAP_LE_CREDIT_BASED_CONNECTION_REQ/RSP` and `L2CAP_CONFIGURATION_REQ`.

```c
uint16_t pending_rx_mtu
```

Pending RX MTU on ECFC reconfigure, used internally by stack.

```c
struct bt_l2cap_le_endpoint tx
```

Channel Transmission Endpoint.

This is an image of the remote’s rx.

The MTU and MPS is controlled by the remote by `L2CAP_LE_CREDIT_BASED_CONNECTION_REQ/RSP` or `L2CAP_CONFIGURATION_REQ`.

```c
struct bt_l2cap_br_endpoint
#include <l2cap.h> BREDR L2CAP Endpoint structure.
```

### Public Members

```c
uint16_t cid
```

Endpoint Channel Identifier (CID)

```c
uint16_t mtu
```

Endpoint Maximum Transmission Unit.

```c
struct bt_l2cap_br_chan
#include <l2cap.h> BREDR L2CAP Channel structure.
```

### Public Members

```c
struct bt_l2cap_chan chan
```

Common L2CAP channel reference object.

```c
struct bt_l2cap_br_endpoint rx
```

Channel Receiving Endpoint.

```c
struct bt_l2cap_br_endpoint tx
```

Channel Transmission Endpoint.

```c
uint16_t psm
```

Remote PSM to be connected.

```c
uint8_t ident
```

Helps match request context during CoC.
struct bt_l2cap_chan_ops

#include <l2cap.h> L2CAP Channel operations structure.

Public Members

void (*connected)(struct bt_l2cap_chan *chan)

Channel connected callback.

If this callback is provided it will be called whenever the connection completes.

Param chan

The channel that has been connected

void (*disconnected)(struct bt_l2cap_chan *chan)

Channel disconnected callback.

If this callback is provided it will be called whenever the channel is disconnected,
including when a connection gets rejected.

Param chan

The channel that has been Disconnected

void (*encrypt_change)(struct bt_l2cap_chan *chan, uint8_t hci_status)

Channel encrypt_change callback.

If this callback is provided it will be called whenever the security level changed
(indirectly link encryption done) or authentication procedure fails. In both cases
security initiator and responder got the final status (HCI status) passed by related
to encryption and authentication events from local host's controller.

Param chan

The channel which has made encryption status changed.

Param status

HCI status of performed security procedure caused by channel secu-

rity requirements. The value is populated by HCI layer and set to 0

when success and to non-zero (reference to HCI Error Codes) when se-

curity/authentication failed.

struct net_buf *(*alloc_seg)(struct bt_l2cap_chan *chan)

Channel alloc_seg callback.

If this callback is provided the channel will use it to allocate buffers to store seg-

ments. This avoids wasting big SDU buffers with potentially much smaller PDUs.

If this callback is supplied, it must return a valid buffer.

Param chan

The channel requesting a buffer.

Return

Allocated buffer.

struct net_buf *(*alloc_buf)(struct bt_l2cap_chan *chan)

Channel alloc_buf callback.

If this callback is provided the channel will use it to allocate buffers to store in-

coming data. Channels that requires segmentation must set this callback. If
the application has not set a callback the L2CAP SDU MTU will be truncated to

BT_L2CAP_SDU_RX_MTU.

Param chan

The channel requesting a buffer.
int (*recv)(struct bt_l2cap_chan *chan, struct net_buf *buf)
Channel recv callback.

**Param chan**
The channel receiving data.

**Param buf**
Buffer containing incoming data.

**Return**
0 in case of success or negative value in case of error.

-EINPROGRESS in case where user has to confirm once the data has been processed by calling `bt_l2cap_chan_recv_complete` passing back the buffer received with its original user_data which contains the number of segments/credits used by the packet.

void (*sent)(struct bt_l2cap_chan *chan)
Channel sent callback.

This callback will be called once the controller marks the SDU as completed. When the controller does so is implementation dependent. It could be after the SDU is enqueued for transmission, or after it is sent on air.

**Param chan**
The channel which has sent data.

void (*status)(struct bt_l2cap_chan *chan, atomic_t *status)
Channel status callback.

If this callback is provided it will be called whenever the channel status changes.

**Param chan**
The channel which status changed

**Param status**
The channel status

void (*reconfigured)(struct bt_l2cap_chan *chan)
Channel reconfigured callback.

If this callback is provided it will be called whenever peer or local device requested reconfiguration. Application may check updated MTU and MPS values by inspecting chan->le endpoints.

**Param chan**
The channel which was reconfigured

void (*seg_recv)(struct bt_l2cap_chan *chan, size_t sdu_len, off_t seg_offset, struct net_buf_simple *seg)
Handle L2CAP segments directly.

This is an alternative to `bt_l2cap_chan_ops::recv`. They cannot be used together.

This is called immediately for each received segment.

Unlike with `bt_l2cap_chan_ops::recv`, flow control is explicit. Each time this handler is invoked, the remote has permanently used up one credit. Use `bt_l2cap_chan_give_credits` to give credits.

The start of an SDU is marked by `seg_offset == 0`. The end of an SDU is marked by `seg_offset + seg->len == sdu_len`.

The stack guarantees that:
• The sender had the credit.
• The SDU length does not exceed MTU.
• The segment length does not exceed MPS.

Additionally, the L2CAP protocol is such that:
• Segments come in order.
• SDUs cannot be interleaved or aborted halfway.

**Note:** With this alternative API, the application is responsible for setting the RX MTU and MPS. The MPS must not exceed `BT_L2CAP_RX_MTU`.

```c
Param chan
    The receiving channel.

Param sdu_len
    Byte length of the SDU this segment is part of.

Param seg_offset
    The byte offset of this segment in the SDU.

Param seg
    The segment payload.
```

```c
struct bt_l2cap_server
    #include <l2cap.h> L2CAP Server structure.
```

**Public Members**

```c
uint16_t psm
    Server PSM.
```

Possible values: 0 A dynamic value will be auto-allocated when `bt_l2cap_server_register()` is called.

0x0001-0x007f Standard, Bluetooth SIG-assigned fixed values.

0x0080-0x00ff Dynamically allocated. May be pre-set by the application before server registration (not recommended however), or auto-allocated by the stack if the app gave 0 as the value.

```c
bt_security_t sec_level
    Required minimum security level.
```

```c
int (*accept)(struct bt_conn *conn, struct bt_l2cap_server *server, struct bt_l2cap_chan **chan)
    Server accept callback.
```

This callback is called whenever a new incoming connection requires authorization.

```c
Param conn
    The connection that is requesting authorization

Param server
    Pointer to the server structure this callback relates to

Param chan
    Pointer to received the allocated channel

Return
    0 in case of success or negative value in case of error.

Return
    -ENOMEM if no available space for new channel.
```
Return
-EACCES if application did not authorize the connection.
Return
-EPERM if encryption key size is too short.

Bluetooth Media

API Reference

Media Control Service

group bt_mcs
Media Control Service (MCS)

[Experimental] Users should note that the APIs can change as a part of ongoing development.

Definitions and types related to the Media Control Service and Media Control Profile specifications.

Defines

BT_MCS_ERR_LONG_VAL_CHANGED

BT_MCS_PLAYBACK_SPEED_MIN
Playback speeds.
All values from -128 to 127 allowed, only some defined

BT_MCS_PLAYBACK_SPEED_QUARTER

BT_MCS_PLAYBACK_SPEED_HALF

BT_MCS_PLAYBACK_SPEED_UNITY

BT_MCS_PLAYBACK_SPEED_DOUBLE

BT_MCS_PLAYBACK_SPEED_MAX

BT_MCS_SEEKING_SPEED_FACTOR_MAX
Seeking speed.
The allowed values for seeking speed are the range -64 to -4 (endpoints included), the value 0, and the range 4 to 64 (endpoints included).

BT_MCS_SEEKING_SPEED_FACTOR_MIN

BT_MCS_SEEKING_SPEED_FACTOR_ZERO
BT_MCS_PLAYING_ORDER_SINGLE_ONCE
Playing orders.

BT_MCS_PLAYING_ORDER_SINGLE_REPEAT

BT_MCS_PLAYING_ORDER_INORDER_ONCE

BT_MCS_PLAYING_ORDER_INORDER_REPEAT

BT_MCS_PLAYING_ORDER_OLDEST_ONCE

BT_MCS_PLAYING_ORDER_OLDEST_REPEAT

BT_MCS_PLAYING_ORDER_NEWEST_ONCE

BT_MCS_PLAYING_ORDER_NEWEST_REPEAT

BT_MCS_PLAYING_ORDER_SHUFFLE_ONCE

BT_MCS_PLAYING_ORDER_SHUFFLE_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_SINGLE_ONCE
Playing orders supported.
A bitmap, in the same order as the playing orders above. Note that playing order 1 corresponds to bit 0, and so on.

BT_MCS_PLAYING_ORDERS_SUPPORTED_SINGLE_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_INORDER_ONCE

BT_MCS_PLAYING_ORDERS_SUPPORTED_INORDER_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_OLDEST_ONCE

BT_MCS_PLAYING_ORDERS_SUPPORTED_OLDEST_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_NEWEST_ONCE

BT_MCS_PLAYING_ORDERS_SUPPORTED_NEWEST_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_SHUFFLE_ONCE

BT_MCS_PLAYING_ORDERS_SUPPORTED_SHUFFLE_REPEAT

BT_MCS_MEDIA_STATE_INACTIVE
Media states.
BT_MCS_MEDIA_STATE_PLAYING

BT_MCS_MEDIA_STATE_PAUSED

BT_MCS_MEDIA_STATESEEKING

BT_MCS_MEDIA_STATE_LAST

BT_MCS_OPC_PLAY

Media control point opcodes.

BT_MCS_OPC_PAUSE

BT_MCS_OPC_FAST_REWIND

BT_MCS_OPC_FAST_FORWARD

BT_MCS_OPC_STOP

BT_MCS_OPC_MOVE_RELATIVE

BT_MCS_OPC_PREV_SEGMENT

BT_MCS_OPC_NEXT_SEGMENT

BT_MCS_OPC_FIRST_SEGMENT

BT_MCS_OPC_LAST_SEGMENT

BT_MCS_OPC_GOTO_SEGMENT

BT_MCS_OPC_PREV_TRACK

BT_MCS_OPC_NEXT_TRACK

BT_MCS_OPC_FIRST_TRACK

BT_MCS_OPC_LAST_TRACK

BT_MCS_OPC_GOTO_TRACK

BT_MCS_OPC_PREV_GROUP

BT_MCS_OPC_NEXT_GROUP
BT_MCS_OPC_FIRST_GROUP

BT_MCS_OPC_LAST_GROUP

BT_MCS_OPC_GOTO_GROUP

BT_MCS_OPCODES_SUPPORTED_LEN
Media control point supported opcodes length.

BT_MCS_OPC_SUP_PLAY
Media control point supported opcodes values.

BT_MCS_OPC_SUP_PAUSE

BT_MCS_OPC_SUP_FAST_REWIND

BT_MCS_OPC_SUP_FAST_FORWARD

BT_MCS_OPC_SUP_STOP

BT_MCS_OPC_SUP_MOVE_RELATIVE

BT_MCS_OPC_SUP_PREV_SEGMENT

BT_MCS_OPC_SUP_NEXT_SEGMENT

BT_MCS_OPC_SUP_FIRST_SEGMENT

BT_MCS_OPC_SUP_LAST_SEGMENT

BT_MCS_OPC_SUP_GOTO_SEGMENT

BT_MCS_OPC_SUP_PREV_TRACK

BT_MCS_OPC_SUP_NEXT_TRACK

BT_MCS_OPC_SUP_FIRST_TRACK

BT_MCS_OPC_SUP_LAST_TRACK

BT_MCS_OPC_SUP_GOTO_TRACK

BT_MCS_OPC_SUP_PREV_GROUP

BT_MCS_OPC_SUP_NEXT_GROUP
BT_MCS_OPC_SUP_FIRST_GROUP
BT_MCS_OPC_SUP_LAST_GROUP
BT_MCS_OPC_SUP_GOTO_GROUP

BT_MCS_OPC_NTF_SUCCESS
   Media control point notification result codes.

BT_MCS_OPC_NTF_NOT_SUPPORTED
BT_MCS_OPC_NTF_PLAYER_INACTIVE
BT_MCS_OPC_NTF_CANNOT_BE_COMPLETED

BT_MCS_SEARCH_TYPE_TRACK_NAME
   Search control point type values.

BT_MCS_SEARCH_TYPE_ARTIST_NAME
BT_MCS_SEARCH_TYPE_ALBUM_NAME
BT_MCS_SEARCH_TYPE_GROUP_NAME
BT_MCS_SEARCH_TYPE_EARLIEST_YEAR
BT_MCS_SEARCH_TYPE_LATEST_YEAR
BT_MCS_SEARCH_TYPE_GENRE
BT_MCS_SEARCH_TYPE_ONLY_TRACKS
BT_MCS_SEARCH_TYPE_ONLY_GROUPS

SEARCH_LEN_MIN
   Search control point values.

SEARCH_SCI_LEN_MIN
SEARCH_LEN_MAX
SEARCH_PARAM_MAX

BT_MCS_SCP_NTF_SUCCESS
   Search notification result codes.

6.1. Bluetooth
The media proxy module is the connection point between media players and media controllers.

A media player has (access to) media content and knows how to navigate and play this content. A media controller reads or gets information from a player and controls the player by setting player parameters and giving the player commands.

The media proxy module allows media player implementations to make themselves available to media controllers. And it allows controllers to access, and get updates from, any player.

The media proxy module allows both local and remote control of local player instances: A media controller may be a local application, or it may be a Media Control Service relaying requests from a remote Media Control Client. There may be either local or remote control, or both, or even multiple instances of each.

[Experimental] Users should note that the APIs can change as a part of ongoing development.

Defines

MEDIA_PROXY_PLAYBACK_SPEED_MIN

Playback speed parameters.

All values from -128 to 127 allowed, only some defined

MEDIA_PROXY_PLAYBACK_SPEED_QUARTER

MEDIA_PROXY_PLAYBACK_SPEED_HALF

MEDIA_PROXY_PLAYBACK_SPEED_UNITY

MEDIA_PROXY_PLAYBACK_SPEED_DOUBLE

MEDIA_PROXY_PLAYBACK_SPEED_MAX

MEDIA_PROXY_SEEKING_SPEED_FACTOR_MAX

Seeking speed factors.

The allowed values for seeking speed are the range -64 to -4 (endpoints included), the value 0, and the range 4 to 64 (endpoints included).
MEDIA_PROXY_SEEKING_SPEED_FACTOR_MIN

MEDIA_PROXY_SEEKING_SPEED_FACTOR_ZERO

MEDIA_PROXY_PLAYING_ORDER_SINGLE_ONCE
Playing orders.

MEDIA_PROXY_PLAYING_ORDER_SINGLE_REPEAT

MEDIA_PROXY_PLAYING_ORDER_INORDER_ONCE

MEDIA_PROXY_PLAYING_ORDER_INORDER_REPEAT

MEDIA_PROXY_PLAYING_ORDER_OLDEST_ONCE

MEDIA_PROXY_PLAYING_ORDER_OLDEST_REPEAT

MEDIA_PROXY_PLAYING_ORDER_NEWEST_ONCE

MEDIA_PROXY_PLAYING_ORDER_NEWEST_REPEAT

MEDIA_PROXY_PLAYING_ORDER_SHUFFLE_ONCE

MEDIA_PROXY_PLAYING_ORDER_SHUFFLE_REPEAT

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_SINGLE_ONCE
Playing orders supported.
A bitmap, in the same order as the playing orders above. Note that playing order 1 corresponds to bit 0, and so on.

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_SINGLE_REPEAT

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_INORDER_ONCE

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_INORDER_REPEAT

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_OLDEST_ONCE

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_OLDEST_REPEAT

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_NEWEST_ONCE

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_NEWEST_REPEAT

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_SHUFFLE_ONCE

MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_SHUFFLE_REPEAT

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MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_SHUFFLE_REPEAT

MEDIA_PROXY_STATE_INACTIVE
    Media player states.

MEDIA_PROXY_STATE_PLAYING

MEDIA_PROXY_STATE_PAUSED

MEDIA_PROXY_STATE_SEEKING

MEDIA_PROXY_STATE_LAST

MEDIA_PROXY_OP_PLAY
    Media player command opcodes.

MEDIA_PROXY_OP_PAUSE

MEDIA_PROXY_OP_FAST_REWIND

MEDIA_PROXY_OP_FAST_FORWARD

MEDIA_PROXY_OP_STOP

MEDIA_PROXY_OP_MOVE_RELATIVE

MEDIA_PROXY_OP_PREV_SEGMENT

MEDIA_PROXY_OP_NEXT_SEGMENT

MEDIA_PROXY_OP_FIRST_SEGMENT

MEDIA_PROXY_OP_LAST_SEGMENT

MEDIA_PROXY_OP_GOTO_SEGMENT

MEDIA_PROXY_OP_PREV_TRACK

MEDIA_PROXY_OP_NEXT_TRACK

MEDIA_PROXY_OP_FIRST_TRACK

MEDIA_PROXY_OP_LAST_TRACK

MEDIA_PROXY_OP_GOTO_TRACK
MEDIA_PROXY_OP_PREV_GROUP

MEDIA_PROXY_OP_NEXT_GROUP

MEDIA_PROXY_OP_FIRST_GROUP

MEDIA_PROXY_OP_LAST_GROUP

MEDIA_PROXY_OP_GOTO_GROUP

MEDIA_PROXY_OPCODES_SUPPORTED_LEN
   Media player supported opcodes length.

MEDIA_PROXY_OP_SUP_PLAY
   Media player supported command opcodes.

MEDIA_PROXY_OP_SUP_PAUSE

MEDIA_PROXY_OP_SUP_FAST_REWIND

MEDIA_PROXY_OP_SUP_FAST_FORWARD

MEDIA_PROXY_OP_SUP_STOP

MEDIA_PROXY_OP_SUP_MOVE_RELATIVE

MEDIA_PROXY_OP_SUP_PREV_SEGMENT

MEDIA_PROXY_OP_SUP_NEXT_SEGMENT

MEDIA_PROXY_OP_SUP_FIRST_SEGMENT

MEDIA_PROXY_OP_SUP_LAST_SEGMENT

MEDIA_PROXY_OP_SUP_GOTO_SEGMENT

MEDIA_PROXY_OP_SUP_PREV_TRACK

MEDIA_PROXY_OP_SUP_NEXT_TRACK

MEDIA_PROXY_OP_SUP_FIRST_TRACK

MEDIA_PROXY_OP_SUP_LAST_TRACK

MEDIA_PROXY_OP_SUP_GOTO_TRACK

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MEDIA_PROXY_OP_SUP_PREV_GROUP
MEDIA_PROXY_OP_SUP_NEXT_GROUP
MEDIA_PROXY_OP_SUP_FIRST_GROUP
MEDIA_PROXY_OP_SUP_LAST_GROUP
MEDIA_PROXY_OP_SUP_GOTO_GROUP

MEDIA_PROXY_CMD_SUCCESS
   Media player command result codes.
MEDIA_PROXY_CMD_NOT_SUPPORTED
MEDIA_PROXY_CMD_PLAYER_INACTIVE
MEDIA_PROXY_CMD_CANNOT_BE_COMPLETED

MEDIA_PROXY_SEARCH_TYPE_TRACK_NAME
   Search operation type values.
MEDIA_PROXY_SEARCH_TYPE_ARTIST_NAME
MEDIA_PROXY_SEARCH_TYPE_ALBUM_NAME
MEDIA_PROXY_SEARCH_TYPE_GROUP_NAME
MEDIA_PROXY_SEARCH_TYPE_EARLIEST_YEAR
MEDIA_PROXY_SEARCH_TYPE_LATEST_YEAR
MEDIA_PROXY_SEARCH_TYPE_GENRE
MEDIA_PROXY_SEARCH_TYPE_ONLY_TRACKS
MEDIA_PROXY_SEARCH_TYPE_ONLY_GROUPS

MEDIA_PROXY_SEARCH_SUCCESS
   Search operation result codes.
MEDIA_PROXY_SEARCH_FAILURE
MEDIA_PROXY_GROUP_OBJECT_TRACK_TYPE
MEDIA_PROXY_GROUP_OBJECT_GROUP_TYPE
Functions

```c
int media_proxy_ctrl_register(struct media_proxy_ctrl_cbs *ctrl_cbs)
```

Register a controller with the media_proxy.

**Parameters**
- `ctrl_cbs` – Callbacks to the controller

**Returns**
- 0 if success, errno on failure

```c
int media_proxy_ctrl_discover_player(struct bt_conn *conn)
```

Discover a remote media player.

Discover a remote media player instance. The remote player instance will be discovered, and accessed, using Bluetooth, via the media control client and a remote media control service. This call will start a GATT discovery of the Media Control Service on the peer, and set up handles and subscriptions.

This shall be called once before any other actions can be executed for the remote player. The remote player instance will be returned in the discover_player() callback.

**Parameters**
- `conn` – The connection to do discovery for

**Returns**
- 0 if success, errno on failure

```c
int media_proxy_ctrl_get_player_name(struct media_player *player)
```

Read Media Player Name.

**Parameters**
- `player` – Media player instance pointer

**Returns**
- 0 if success, errno on failure.

```c
int media_proxy_ctrl_get_icon_id(struct media_player *player)
```

Read Icon Object ID.

Get an ID (48 bit) that can be used to retrieve the Icon Object from an Object Transfer Service.

See the Media Control Service spec v1.0 sections 3.2 and 4.1 for a description of the Icon Object.

**Requires Object Transfer Service**

**Parameters**
- `player` – Media player instance pointer

**Returns**
- 0 if success, errno on failure.

```c
int media_proxy_ctrl_get_icon_url(struct media_player *player)
```

Read Icon URL.

Get a URL to the media player's icon.

**Parameters**
- `player` – Media player instance pointer
int media_proxy_ctrl_get_track_title(struct media_player *player)
    Read Track Title.

    **Parameters**
    • player – Media player instance pointer

    **Returns**
    0 if success, errno on failure.

int media_proxy_ctrl_get_track_duration(struct media_player *player)
    Read Track Duration.
    The duration of a track is measured in hundredths of a second.

    **Parameters**
    • player – Media player instance pointer

    **Returns**
    0 if success, errno on failure.

int media_proxy_ctrl_get_track_position(struct media_player *player)
    Read Track Position.
    The position of the player (the playing position) is measured in hundredths of a second
    from the beginning of the track

    **Parameters**
    • player – Media player instance pointer

    **Returns**
    0 if success, errno on failure.

int media_proxy_ctrl_set_track_position(struct media_player *player, int32_t position)
    Set Track Position.
    Set the playing position of the media player in the current track. The position is given
    in in hundredths of a second, from the beginning of the track for positive values, and (backwards) from the end of the track for negative values.

    **Parameters**
    • player – Media player instance pointer
    • position – The track position to set

    **Returns**
    0 if success, errno on failure.

int media_proxy_ctrl_get_playback_speed(struct media_player *player)
    Get Playback Speed.
    The playback speed parameter is related to the actual playback speed as follows: actual
    playback speed = $2^{\text{speed\_parameter}/64}$
    A speed parameter of 0 corresponds to unity speed playback (i.e. playback at “normal”
    speed). A speed parameter of -128 corresponds to playback at one fourth of normal
    speed, 127 corresponds to playback at almost four times the normal speed.

    **Parameters**
    • player – Media player instance pointer

    **Returns**
    0 if success, errno on failure.
int media_proxy_ctrl_set_playback_speed(struct media_player *player, int8_t speed)

Set Playback Speed.

See the get_playback_speed() function for an explanation of the playback speed parameter.

Note that the media player may not support all possible values of the playback speed parameter. If the value given is not supported, and is higher than the current value, the player should set the playback speed to the next higher supported value. (And correspondingly to the next lower supported value for given values lower than the current value.)

Parameters
  • player – Media player instance pointer
  • speed – The playback speed parameter to set

Returns
  0 if success, errno on failure.

int media_proxy_ctrl_get_seeking_speed(struct media_player *player)

Get Seeking Speed.

The seeking speed gives the speed with which the player is seeking. It is a factor, relative to real-time playback speed - a factor four means seeking happens at four times the real-time playback speed. Positive values are for forward seeking, negative values for backwards seeking.

The seeking speed is not settable - a non-zero seeking speed is the result of “fast rewind” of “fast forward” commands.

Parameters
  • player – Media player instance pointer

Returns
  0 if success, errno on failure.

int media_proxy_ctrl_get_track_segments_id(struct media_player *player)

Read Current Track Segments Object ID.

Get an ID (48 bit) that can be used to retrieve the Current Track Segments Object from an Object Transfer Service

See the Media Control Service spec v1.0 sections 3.10 and 4.2 for a description of the Track Segments Object.

Requires Object Transfer Service

Parameters
  • player – Media player instance pointer

Returns
  0 if success, errno on failure.

int media_proxy_ctrl_get_current_track_id(struct media_player *player)

Read Current Track Object ID.

Get an ID (48 bit) that can be used to retrieve the Current Track Object from an Object Transfer Service

See the Media Control Service spec v1.0 sections 3.11 and 4.3 for a description of the Current Track Object.

Requires Object Transfer Service

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_set_current_track_id(struct media_player *player, uint64_t id)
Set Current Track Object ID.
Change the player's current track to the track given by the ID. (Behaves similarly to the
goto track command.)
Requires Object Transfer Service

Parameters
• player – Media player instance pointer
• id – The ID of a track object

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_next_track_id(struct media_player *player)
Read Next Track Object ID.
Get an ID (48 bit) that can be used to retrieve the Next Track Object from an Object
Transfer Service
Requires Object Transfer Service

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_set_next_track_id(struct media_player *player, uint64_t id)
Set Next Track Object ID.
Change the player's next track to the track given by the ID.
Requires Object Transfer Service

Parameters
• player – Media player instance pointer
• id – The ID of a track object

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_parent_group_id(struct media_player *player)
Read Parent Group Object ID.
Get an ID (48 bit) that can be used to retrieve the Parent Track Object from an Object
Transfer Service
The parent group is the parent of the current group.
See the Media Control Service spec v1.0 sections 3.14 and 4.4 for a description of the
Current Track Object.
Requires Object Transfer Service

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.
int media_proxy_ctrl_get_current_group_id(struct media_player *player)
Read Current Group Object ID.
Get an ID (48 bit) that can be used to retrieve the Current Track Object from an Object Transfer Service
See the Media Control Service spec v1.0 sections 3.14 and 4.4 for a description of the Current Group Object.
Requires Object Transfer Service

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_set_current_group_id(struct media_player *player, uint64_t id)
Set Current Group Object ID.
Change the player’s current group to the group given by the ID, and the current track to the first track in that group.
Requires Object Transfer Service

Parameters
• player – Media player instance pointer
• id – The ID of a group object

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_playing_order(struct media_player *player)
Read Playing Order.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_set_playing_order(struct media_player *player, uint8_t order)
Set Playing Order.
Set the media player’s playing order

Parameters
• player – Media player instance pointer
• order – The playing order to set

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_playing_orders_supported(struct media_player *player)
Read Playing Orders Supported.
Read a bitmap containing the media player’s supported playing orders.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.
int media_proxy_ctrl_get_media_state(struct media_player *player)
Read Media State.
Read the media player's state

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_send_command(struct media_player *player, const struct mpl_cmd *command)
Send Command.
Send a command to the media player. Commands may cause the media player to change its state. May result in two callbacks - one for the actual sending of the command to the player, one for the result of the command from the player.

Parameters
• player – Media player instance pointer
• command – The command to send

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_commands_supported(struct media_player *player)
Read Commands Supported.
Read a bitmap containing the media player's supported command opcodes.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_send_search(struct media_player *player, const struct mpl_search *search)
Set Search.
Write a search to the media player. If the search is successful, the search results will be available as a group object in the Object Transfer Service (OTS). May result in up to three callbacks
• one for the actual sending of the search to the player
• one for the result code for the search from the player
• if the search is successful, one for the search results object ID in the OTs
Requires Object Transfer Service

Parameters
• player – Media player instance pointer
• search – The search to write

Returns
0 if success, errno on failure.
int media_proxy_ctrl_get_search_results_id(struct media_player *player)
Read Search Results Object ID.
Get an ID (48 bit) that can be used to retrieve the Search Results Object from an Object Transfer Service
The search results object is a group object. The search results object only exists if a successful search operation has been done.
Requires Object Transfer Service

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

uint8_t media_proxy_ctrl_get_content_ctrl_id(struct media_player *player)
Read Content Control ID.
The content control ID identifies a content control service on a device, and links it to the corresponding audio stream.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_pl_register(struct media_proxy_pl_calls *pl_calls)
Register a player with the media proxy.
Register a player with the media proxy module, for use by media controllers.
The media proxy may call any non-NULL function pointers in the supplied media_proxy_pl_calls structure.

Parameters
• pl_calls – Function pointers to the media player's calls

Returns
0 if success, errno on failure

int media_proxy_pl_init(void)

struct bt_ots *bt_mcs_get_ots(void)

void media_proxy_pl_name_cb(const char *name)
Player name changed callback.
To be called when the player's name is changed.

Parameters
• name – The name of the player

void media_proxy_pl_icon_url_cb(const char *url)
Player icon URL changed callback.
To be called when the player’s icon URL is changed.

Parameters
• url – The URL of the player’s icon
void media_proxy_pl_track_changed_cb(void)
    Track changed callback.
    To be called when the player’s current track is changed

void media_proxy_pl_track_title_cb(char *title)
    Track title callback.
    To be called when the player’s current track is changed

**Parameters**

- `title` – The title of the track

void media_proxy_pl_track_duration_cb(int32_t duration)
    Track duration callback.
    To be called when the current track's duration is changed (e.g. due to a track change)
    The track duration is given in hundredths of a second.

**Parameters**

- `duration` – The track duration

void media_proxy_pl_track_position_cb(int32_t position)
    Track position callback.
    To be called when the media player's position in the track is changed, or when the
    player is paused or similar.

Exception: This callback should not be called when the position changes during regu-
lar playback, i.e. while the player is playing and playback happens at a constant speed.

The track position is given in hundredths of a second from the start of the track.

**Parameters**

- `position` – The media player's position in the track

void media_proxy_plPlayback_speed_cb(int8_t speed)
    Playback speed callback.
    To be called when the playback speed is changed.

**Parameters**

- `speed` – The playback speed parameter

void media_proxy_pl_seeking_speed_cb(int8_t speed)
    Seeking speed callback.
    To be called when the seeking speed is changed.

**Parameters**

- `speed` – The seeking speed factor

void media_proxy_pl_current_track_id_cb(uint64_t id)
    Current track object ID callback.
    To be called when the ID of the current track is changed (e.g. due to a track change).

**Parameters**

- `id` – The ID of the current track object in the OTS
void media_proxy_pl_next_track_id_cb(uint64_t id)

Next track object ID callback.

To be called when the ID of the current track is changed

Parameters

• id – The ID of the next track object in the OTS

void media_proxy_pl_parent_group_id_cb(uint64_t id)

Parent group object ID callback.

To be called when the ID of the parent group is changed

Parameters

• id – The ID of the parent group object in the OTS

void media_proxy_pl_current_group_id_cb(uint64_t id)

Current group object ID callback.

To be called when the ID of the current group is changed

Parameters

• id – The ID of the current group object in the OTS

void media_proxy_pl_playing_order_cb(uint8_t order)

Playing order callback.

To be called when the playing order is changed

Parameters

• order – The playing order

void media_proxy_pl_media_state_cb(uint8_t state)

Media state callback.

To be called when the media state is changed

Parameters

• state – The media player's state

void media_proxy_pl_command_cb(const struct mpl_cmd_ntf *cmd_ntf)

Command callback.

To be called when a command has been sent, to notify whether the command was successfully performed or not. See the MEDIA_PROXY_CMD_ * result code defines.

Parameters

• cmd_ntf – The result of the command

void media_proxy_pl_commands_supported_cb(uint32_t opcodes)

Commands supported callback.

To be called when the set of commands supported is changed

Parameters

• opcodes – The supported commands opcodes

void media_proxy_pl_search_cb(uint8_t result_code)

Search callback.

To be called when a search has been set to notify whether the search was successfully performed or not. See the MEDIA_PROXY_SEARCH_ * result code defines.

The actual results of the search, if successful, can be found in the search results object.
Parameters

- **result_code** – The result (success or failure) of the search

```c
void media_proxy_pl_search_results_id_cb(uint64_t id)
```

Search Results object ID callback.
To be called when the ID of the search results is changed (typically as the result of a
new successful search).

**Parameters**

- **id** – The ID of the search results object in the OTS

```c
struct mpl_cmd
    #include <media_proxy.h> Media player command.
```

```c
struct mpl_cmd_ntf
    #include <media_proxy.h> Media command notification.
```

```c
struct mpl_sci
    #include <media_proxy.h> Search control item.
```

**Public Members**

```c
uint8_t len
    Length of type and parameter.
```

```c
uint8_t type
    MEDIA_PROXY_SEARCH_TYPE_<...>
```

```c
char param[62]
    Search parameter.
```

```c
struct mpl_search
    #include <media_proxy.h> Search.
```

```c
struct media_proxy_ctrl_cbs
    #include <media_proxy.h> Callbacks to a controller, from the media proxy.
```

Given by a controller when registering

**Public Members**

```c
void (*local_player_instance)(struct media_player *player, int err)
```

Media Player Instance callback.
Called when the local Media Player instance is registered or read (TODO). Also
called if the local player instance is already registered when the controller is reg-
istered. Provides the controller with the pointer to the local player instance.

- **Param player**
  Media player instance pointer

- **Param err**
  Error value. 0 on success, or errno on negative value.
void (*player_name_recv)(struct media_player *player, int err, const char *name)

Media Player Name receive callback.

Called when the Media Player Name is read or changed See also media_proxy_ctrl_name_get()

- **Param player**: Media player instance pointer
- **Param err**: Error value. 0 on success, GATT error on positive value or errno on negative value.
- **Param name**: The name of the media player

void (*icon_id_recv)(struct media_player *player, int err, uint64_t id)

Media Player Icon Object ID receive callback.

Called when the Media Player Icon Object ID is read See also media_proxy_ctrl_get_icon_id()

- **Param player**: Media player instance pointer
- **Param err**: Error value. 0 on success, GATT error on positive value or errno on negative value.
- **Param id**: The ID of the Icon object in the Object Transfer Service (48 bits)

void (*icon_url_recv)(struct media_player *player, int err, const char *url)

Media Player Icon URL receive callback.

Called when the Media Player Icon URL is read See also media_proxy_ctrl_get_icon_url()

- **Param player**: Media player instance pointer
- **Param err**: Error value. 0 on success, GATT error on positive value or errno on negative value.
- **Param url**: The URL of the icon

void (*track_changed_recv)(struct media_player *player, int err)

Track changed receive callback.

Called when the Current Track is changed

- **Param player**: Media player instance pointer
- **Param err**: Error value. 0 on success, GATT error on positive value or errno on negative value.

void (*track_title_recv)(struct media_player *player, int err, const char *title)

Track Title receive callback.

Called when the Track Title is read or changed See also media_proxy_ctrl_get_track_title()

- **Param player**: Media player instance pointer

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PARAM err
   Error value. 0 on success, GATT error on positive value or errno on negative value.

PARAM title
   The title of the current track

void (*track_duration_recv)(struct media_player *player, int err, int32_t duration)
Track Duration receive callback.
Called when the Track Duration is read or changed See also media_proxy_ctrl_get_track_duration()
   Param player
       Media player instance pointer
   Param err
       Error value. 0 on success, GATT error on positive value or errno on negative value.
   Param duration
       The duration of the current track

void (*track_position_recv)(struct media_player *player, int err, int32_t position)
Track Position receive callback.
Called when the Track Position is read or changed See also media_proxy_ctrl_get_track_position() and media_proxy_ctrl_set_track_position()
   Param player
       Media player instance pointer
   Param err
       Error value. 0 on success, GATT error on positive value or errno on negative value.
   Param position
       The player's position in the track

void (*track_position_write)(struct media_player *player, int err, int32_t position)
Track Position write callback.
Called when the Track Position is written See also media_proxy_ctrl_set_track_position()
   Param player
       Media player instance pointer
   Param err
       Error value. 0 on success, GATT error on positive value or errno on negative value.
   Param position
       The position given attempted to write

void (*playback_speed_recv)(struct media_player *player, int err, int8_t speed)
Playback Speed receive callback.
Called when the Playback Speed is read or changed See also media_proxy_ctrl_get_playback_speed() and media_proxy_ctrl_set_playback_speed()
   Param player
       Media player instance pointer
   Param err
       Error value. 0 on success, GATT error on positive value or errno on negative value.
   Param speed
       The playback speed parameter
void (*playback_speed_write)(struct media_player *player, int err, int8_t speed)

Playback Speed write callback.
Called when the Playback Speed is written. See also `media_proxy_ctrl_set_playback_speed()`

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param speed
The playback speed parameter attempted to write

void (*seeking_speed_recv)(struct media_player *player, int err, int8_t speed)

Seeking Speed receive callback.
Called when the Seeking Speed is read or changed. See also `media_proxy_ctrl_get_seeking_speed()`

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param speed
The seeking speed factor

void (*track_segments_id_recv)(struct media_player *player, int err, uint64_t id)

Track Segments Object ID receive callback.
Called when the Track Segments Object ID is read. See also `media_proxy_ctrl_get_track_segments_id()`

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param id
The ID of the track segments object in Object Transfer Service (48 bits)

void (*current_track_id_recv)(struct media_player *player, int err, uint64_t id)

Current Track Object ID receive callback.
Called when the Current Track Object ID is read or changed. See also `media_proxy_ctrl_get_current_track_id()` and `media_proxy_ctrl_set_current_track_id()`

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param id
The ID of the current track object in Object Transfer Service (48 bits)

void (*current_track_id_write)(struct media_player *player, int err, uint64_t id)

Current Track Object ID write callback.
Called when the Current Track Object ID is written. See also `media_proxy_ctrl_set_current_track_id()`

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**Param player**  
Media player instance pointer

**Param err**  
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param id**  
The ID (48 bits) attempted to write

```c
void (*next_track_id_recv)(struct media_player *player, int err, uint64_t id)
```
Next Track Object ID receive callback.

Called when the Next Track Object ID is read or changed See also `media_proxy_ctrl_get_next_track_id()` and `media_proxy_ctrl_set_next_track_id()`

**Param player**  
Media player instance pointer

**Param err**  
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param id**  
The ID of the next track object in Object Transfer Service (48 bits)

```c
void (*next_track_id_write)(struct media_player *player, int err, uint64_t id)
```
Next Track Object ID write callback.

Called when the Next Track Object ID is written See also `media_proxy_ctrl_set_next_track_id()`

**Param player**  
Media player instance pointer

**Param err**  
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param id**  
The ID (48 bits) attempted to write

```c
void (*parent_group_id_recv)(struct media_player *player, int err, uint64_t id)
```
Parent Group Object ID receive callback.

Called when the Parent Group Object ID is read or changed See also `media_proxy_ctrl_get_parent_group_id()`

**Param player**  
Media player instance pointer

**Param err**  
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param id**  
The ID of the parent group object in Object Transfer Service (48 bits)

```c
void (*current_group_id_recv)(struct media_player *player, int err, uint64_t id)
```
Current Group Object ID receive callback.

Called when the Current Group Object ID is read or changed See also `media_proxy_ctrl_get_current_group_id()` and `media_proxy_ctrl_set_current_group_id()`

**Param player**  
Media player instance pointer

**Param err**  
Error value. 0 on success, GATT error on positive value or errno on negative value.
**Param id**

The ID of the current group object in Object Transfer Service (48 bits)

```c
void (*current_group_id_write)(struct media_player *player, int err, uint64_t id)
```

Current Group Object ID write callback. Called when the Current Group Object ID is written. See also `media_proxy_ctrl_set_current_group_id`

- **Param player**
  - Media player instance pointer
- **Param err**
  - Error value. 0 on success, GATT error on positive value or `errno` on negative value.
- **Param id**
  - The ID (48 bits) attempted to write

```c
void (*playing_order_recv)(struct media_player *player, int err, uint8_t order)
```

Playing Order receive callback. Called when the Playing Order is read or changed. See also `media_proxy_ctrl_get_playing_order` and `media_proxy_ctrl_set_playing_order`

- **Param player**
  - Media player instance pointer
- **Param err**
  - Error value. 0 on success, GATT error on positive value or `errno` on negative value.
- **Param order**
  - The playing order

```c
void (*playing_order_write)(struct media_player *player, int err, uint8_t order)
```

Playing Order write callback. Called when the Playing Order is written. See also `media_proxy_ctrl_set_playing_order`

- **Param player**
  - Media player instance pointer
- **Param err**
  - Error value. 0 on success, GATT error on positive value or `errno` on negative value.
- **Param order**
  - The playing order attempted to write

```c
void (*playing_orders_supported_recv)(struct media_player *player, int err, uint16_t orders)
```

Playing Orders Supported receive callback. Called when the Playing Orders Supported is read. See also `media_proxy_ctrl_get_playing_orders_supported`

- **Param player**
  - Media player instance pointer
- **Param err**
  - Error value. 0 on success, GATT error on positive value or `errno` on negative value.
- **Param orders**
  - The playing orders supported

```c
void (*media_state_recv)(struct media_player *player, int err, uint8_t state)
```

Media State receive callback.
Called when the Media State is read or changed. See also `media_proxy_ctrl_get_media_state()` and `media_proxy_ctrl_send_command()`.

**Param player**
- Media player instance pointer

**Param err**
- Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param state**
- The media player state

```c
void (*command_send)(struct media_player *player, int err, const struct mpl_cmd *cmd)
```

Command send callback.

Called when a command has been sent. See also `media_proxy_ctrl_send_command()`.

**Param player**
- Media player instance pointer

**Param err**
- Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param cmd**
- The command sent

```c
void (*command_recv)(struct media_player *player, int err, const struct mpl_cmd_ntf *result)
```

Command result receive callback.

Called when a command result has been received. See also `media_proxy_ctrl_send_command()`.

**Param player**
- Media player instance pointer

**Param err**
- Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param result**
- The result received

```c
void (*commands_supported_recv)(struct media_player *player, int err, uint32_t opcodes)
```

Commands supported receive callback.

Called when the Commands Supported is read or changed. See also `media_proxy_ctrl_get_commands_supported()`.

**Param player**
- Media player instance pointer

**Param err**
- Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param opcodes**
- The supported command opcodes (bitmap)

```c
void (*search_send)(struct media_player *player, int err, const struct mpl_search *search)
```

Search send callback.

Called when a search has been sent. See also `media_proxy_ctrl_send_search()`.

**Param player**
- Media player instance pointer
**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param search**
The search sent

```c
void (*search_recv)(struct media_player *player, int err, uint8_t result_code)
```
Search result code receive callback.

Called when a search result code has been received See also `media_proxy_ctrl_send_search()`

The search result code tells whether the search was successful or not. For a successful search, the actual results of the search (i.e. what was found as a result of the search) can be accessed using the Search Results Object ID. The Search Results Object ID has a separate callback - `search_results_id_recv()`.

**Param player**
Media player instance pointer

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param result_code**
Search result code

```c
void (*search_results_id_recv)(struct media_player *player, int err, uint64_t id)
```
Search Results Object ID receive callback See also `media_proxy_ctrl_get_search_results_id()`

Called when the Search Results Object ID is read or changed

**Param player**
Media player instance pointer

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param id**
The ID of the search results object in Object Transfer Service (48 bits)

```c
void (*content_ctrl_id_recv)(struct media_player *player, int err, uint8_t ccid)
```
Content Control ID receive callback.

Called when the Content Control ID is read See also `media_proxy_ctrl_get_content_ctrl_id()`

**Param player**
Media player instance pointer

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param ccid**
The content control ID

```c
struct media_proxy_pl_calls
```
#include `<media_proxy.h>` Available calls in a player, that the media proxy can call.

Given by a player when registering.

**Public Members**
const char *(*get_player_name)(void)
   Read Media Player Name.
   **Return**
   The name of the media player

uint64_t (*get_icon_id)(void)
   Read Icon Object ID.
   Get an ID (48 bit) that can be used to retrieve the Icon Object from an Object Transfer Service
   See the Media Control Service spec v1.0 sections 3.2 and 4.1 for a description of the Icon Object.
   **Return**
   The Icon Object ID

const char *(*get_icon_url)(void)
   Read Icon URL.
   Get a URL to the media player's icon.
   **Return**
   The URL of the Icon

const char *(*get_track_title)(void)
   Read Track Title.
   **Return**
   The title of the current track

int32_t (*get_track_duration)(void)
   Read Track Duration.
   The duration of a track is measured in hundredths of a second.
   **Return**
   The duration of the current track

int32_t (*get_track_position)(void)
   Read Track Position.
   The position of the player (the playing position) is measured in hundredths of a second from the beginning of the track
   **Return**
   The position of the player in the current track

void (*set_track_position)(int32_t position)
   Set Track Position.
   Set the playing position of the media player in the current track. The position is given in hundredths of a second, from the beginning of the track for positive values, and (backwards) from the end of the track for negative values.
   **Param position**
   The player position to set

int8_t (*get_playback_speed)(void)
   Get Playback Speed.
   The playback speed parameter is related to the actual playback speed as follows: actual playback speed = 2^(speed_parameter/64)
A speed parameter of 0 corresponds to unity speed playback (i.e. playback at “normal” speed). A speed parameter of -128 corresponds to playback at one fourth of normal speed, 127 corresponds to playback at almost four times the normal speed.

Return
The playback speed parameter

```c
void (*set_playback_speed)(int8_t speed)
```
Set Playback Speed.

See the `get_playback_speed()` function for an explanation of the playback speed parameter.

Note that the media player may not support all possible values of the playback speed parameter: If the value given is not supported, and is higher than the current value, the player should set the playback speed to the next higher supported value. (And correspondingly to the next lower supported value for given values lower than the current value.)

**Param speed**
The playback speed parameter to set

```c
int8_t (*get_seeking_speed)(void)
```
Get Seeking Speed.

The seeking speed gives the speed with which the player is seeking. It is a factor, relative to real-time playback speed - a factor four means seeking happens at four times the real-time playback speed. Positive values are for forward seeking, negative values for backwards seeking.

The seeking speed is not settable - a non-zero seeking speed is the result of “fast rewind” of “fast forward” commands.

**Return**
The seeking speed factor

```c
uint64_t (*get_track_segments_id)(void)
```
Read Current Track Segments Object ID.

Get an ID (48 bit) that can be used to retrieve the Current Track Segments Object from an Object Transfer Service

See the Media Control Service spec v1.0 sections 3.10 and 4.2 for a description of the Track Segments Object.

**Return**
The current Track Segments Object ID

```c
uint64_t (*get_current_track_id)(void)
```
Read Current Track Object ID.

Get an ID (48 bit) that can be used to retrieve the Current Track Object from an Object Transfer Service

See the Media Control Service spec v1.0 sections 3.11 and 4.3 for a description of the Current Track Object.

**Return**
The Current Track Object ID

```c
void (*set_current_track_id)(uint64_t id)
```
Set Current Track Object ID.

Change the player’s current track to the track given by the ID. (Behaves similarly to the goto track command.)
**Param id**  
The ID of a track object

```c
uint64_t (*get_next_track_id)(void)
```
Read Next Track Object ID.

Get an ID (48 bit) that can be used to retrieve the Next Track Object from an Object Transfer Service

**Return**  
The Next Track Object ID

```c
void (*set_next_track_id)(uint64_t id)
```
Set Next Track Object ID.

Change the player's next track to the track given by the ID.

**Param id**  
The ID of a track object

```c
uint64_t (*get_parent_group_id)(void)
```
Read Parent Group Object ID.

Get an ID (48 bit) that can be used to retrieve the Parent Track Object from an Object Transfer Service

The parent group is the parent of the current group.

See the Media Control Service spec v1.0 sections 3.14 and 4.4 for a description of the Current Track Object.

**Return**  
The Current Group Object ID

```c
uint64_t (*get_current_group_id)(void)
```
Read Current Group Object ID.

Get an ID (48 bit) that can be used to retrieve the Current Track Object from an Object Transfer Service

See the Media Control Service spec v1.0 sections 3.14 and 4.4 for a description of the Current Group Object.

**Return**  
The Current Group Object ID

```c
void (*set_current_group_id)(uint64_t id)
```
Set Current Group Object ID.

Change the player's current group to the group given by the ID, and the current track to the first track in that group.

**Param id**  
The ID of a group object

```c
uint8_t (*get_playing_order)(void)
```
Read Playing Order.

```c

return The media player's current playing order
```

```c
void (*set_playing_order)(uint8_t order)
```
Set Playing Order.

Set the media player's playing order. See the MEDIA_PROXY_PLAYING_ORDER_* defines.
**Param order**
The playing order to set

```c
uint16_t (*get_playing_orders_supported)(void)
```
Read Playing Orders Supported.

Read a bitmap containing the media player's supported playing orders. See the MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_* defines.

**Return**
The media player's supported playing orders

```c
uint8_t (*get_media_state)(void)
```
Read Media State.

Read the media player's state. See the MEDIA_PROXY_MEDIA_STATE_* defines.

**Return**
The media player's state

```c
void (*send_command)(const struct mpl_cmd *command)
```
Send Command.

Send a command to the media player. For command opcodes (play, pause, ...) - see the MEDIA_PROXY_OP_* defines.

**Param command**
The command to send

```c
uint32_t (*get_commands_supported)(void)
```
Read Commands Supported.

Read a bitmap containing the media player's supported command opcodes. See the MEDIA_PROXY_OP_SUP_* defines.

**Return**
The media player's supported command opcodes

```c
void (*send_search)(const struct mpl_search *search)
```
Set Search.

Write a search to the media player. (For the formatting of a search, see the Media Control Service spec and the mcs.h file.)

**Param search**
The search to write

```c
uint64_t (*get_search_results_id)(void)
```
Read Search Results Object ID.

Get an ID (48 bit) that can be used to retrieve the Search Results Object from an Object Transfer Service.

The search results object is a group object. The search results object only exists if a successful search operation has been done.

**Return**
The Search Results Object ID

```c
uint8_t (*get_content_ctrl_id)(void)
```
Read Content Control ID.

The content control ID identifies a content control service on a device, and links it to the corresponding audio stream.
Media Control Client

`bt_gatt_mcc`

Bluetooth Media Control Client (MCC) interface.

Updated to the Media Control Profile specification revision 1.0

[Experimental] Users should note that the APIs can change as a part of ongoing development.

Typedefs

typedef void (*`bt_mcc_discover_mcs_cb`)(struct bt_conn *conn, int err)

Callback function for `bt_mcc_discover_mcs`

Called when a media control server is discovered

- **Param conn**
  
The connection that was used to initialise the media control client

- **Param err**
  
  Error value. 0 on success, GATT error or errno on fail


typedef void (*`bt_mcc_read_player_name_cb`)(struct bt_conn *conn, int err, const char *name)

Callback function for `bt_mcc_read_player_name`

Called when the player name is read or notified

- **Param conn**
  
  The connection that was used to initialise the media control client

- **Param err**
  
  Error value. 0 on success, GATT error or errno on fail

- **Param name**
  
  Player name


typedef void (*`bt_mcc_read_icon_obj_id_cb`)(struct bt_conn *conn, int err, uint64_t icon_id)

Callback function for `bt_mcc_read_icon_obj_id`

Called when the icon object ID is read

- **Param conn**
  
  The connection that was used to initialise the media control client

- **Param err**
  
  Error value. 0 on success, GATT error or errno on fail

- **Param icon_id**
  
  The ID of the Icon Object. This is a UINT48 in a uint64_t


typedef void (*`bt_mcc_read_icon_url_cb`)(struct bt_conn *conn, int err, const char *icon_url)

Callback function for `bt_mcc_read_icon_url`

Called when the icon URL is read
Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param icon_url
The URL of the Icon

typedef void (*bt_mcc_track_changed_ntf_cb)(struct bt_conn *conn, int err)
Callback function for track changed notifications.
Called when a track change is notified.
The track changed characteristic is a special case. It can not be read or set, it can only be notified.

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

typedef void (*bt_mcc_read_track_title_cb)(struct bt_conn *conn, int err, const char *title)
Callback function for bt_mcc_read_track_title()
Called when the track title is read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param title
The title of the track

typedef void (*bt_mcc_read_track_duration_cb)(struct bt_conn *conn, int err, int32_t dur)
Callback function for bt_mcc_read_track_duration()
Called when the track duration is read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param dur
The duration of the track

typedef void (*bt_mcc_read_track_position_cb)(struct bt_conn *conn, int err, int32_t pos)
Callback function for bt_mcc_read_track_position()
Called when the track position is read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param pos
The Track Position

6.1. Bluetooth
typedef void (*bt_mcc_set_track_position_cb)(struct bt_conn *conn, int err, int32_t pos)
Callback function for bt_mcc_set_track_position()
Called when the track position is set

Param conn
   The connection that was used to initialise the media control client

Param err
   Error value. 0 on success, GATT error or errno on fail

Param pos
   The Track Position set (or attempted to set)

typedef void (*bt_mcc_read_playback_speed_cb)(struct bt_conn *conn, int err, int8_t speed)
Callback function for bt_mcc_read_playback_speed()
Called when the playback speed is read or notified

Param conn
   The connection that was used to initialise the media control client

Param err
   Error value. 0 on success, GATT error or errno on fail

Param speed
   The Playback Speed

typedef void (*bt_mcc_set_playback_speed_cb)(struct bt_conn *conn, int err, int8_t speed)
Callback function for bt_mcc_set_playback_speed()
Called when the playback speed is set

Param conn
   The connection that was used to initialise the media control client

Param err
   Error value. 0 on success, GATT error or errno on fail

Param speed
   The Playback Speed set (or attempted to set)

typedef void (*bt_mcc_read_seeking_speed_cb)(struct bt_conn *conn, int err, int8_t speed)
Callback function for bt_mcc_read_seeking_speed()
Called when the seeking speed is read or notified

Param conn
   The connection that was used to initialise the media control client

Param err
   Error value. 0 on success, GATT error or errno on fail

Param speed
   The Seeking Speed

typedef void (*bt_mcc_read_segments_obj_id_cb)(struct bt_conn *conn, int err, uint64_t id)
Callback function for bt_mcc_read_segments_obj_id()
Called when the track segments object ID is read
**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param id**
The Track Segments Object ID (UINT48)

typedef void (*bt_mcc_read_current_track_obj_id_cb)(struct bt_conn *conn, int err, uint64_t id)

Callback function for `<bt_mcc_read_current_track_obj_id()>`
Called when the current track object ID is read or notified

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param id**
The Current Track Object ID (UINT48)

typedef void (*bt_mcc_set_current_track_obj_id_cb)(struct bt_conn *conn, int err, uint64_t id)

Callback function for `<bt_mcc_set_current_track_obj_id()>`
Called when the current track object ID is set

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param id**
The Object ID (UINT48) set (or attempted to set)

typedef void (*bt_mcc_read_next_track_obj_id_cb)(struct bt_conn *conn, int err, uint64_t id)

Callback function for `<bt_mcc_read_next_track_obj_id()>`
Called when the next track object ID is read or notified

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param id**
The Next Track Object ID (UINT48)

typedef void (*bt_mcc_set_next_track_obj_id_cb)(struct bt_conn *conn, int err, uint64_t id)

Callback function for `<bt_mcc_set_next_track_obj_id()>`
Called when the next track object ID is set

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

6.1. Bluetooth
Param id
The Object ID (UINT48) set (or attempted to set)

typedef void (*bt_mcc_read_parent_group_obj_id_cb)(struct bt_conn *conn, int err, uint64_t id)
Callback function for bt_mcc_read_parent_group_obj_id()
Called when the parent group object ID is read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param id
The Parent Group Object ID (UINT48)

typedef void (*bt_mcc_read_current_group_obj_id_cb)(struct bt_conn *conn, int err, uint64_t id)
Callback function for bt_mcc_read_current_group_obj_id()
Called when the current group object ID is read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param id
The Current Group Object ID (UINT48)

typedef void (*bt_mcc_set_current_group_obj_id_cb)(struct bt_conn *conn, int err, uint64_t obj_id)
Callback function for bt_mcc_set_current_group_obj_id()
Called when the current group object ID is set

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param obj_id
The Object ID (UINT48) set (or attempted to set)

typedef void (*bt_mcc_read_playing_order_cb)(struct bt_conn *conn, int err, uint8_t order)
Callback function for bt_mcc_read_playing_order()
Called when the playing order is read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param order
The playback order
typedef void (*bt_mcc_set_playing_order_cb)(struct bt_conn *conn, int err, uint8_t order)
Callback function for \textit{bt_mcc_set_playing_order()}
Called when the playing order is set

- **Param conn**
  The connection that was used to initialise the media control client

- **Param err**
  Error value. 0 on success, GATT error or errno on fail

- **Param order**
  The Playing Order set (or attempted to set)

typedef void (*bt_mcc_read_playing_orders_supported_cb)(struct bt_conn *conn, int err, uint16_t orders)
Callback function for \textit{bt_mcc_read_playing_orders_supported()}
Called when the supported playing orders are read or notified

- **Param conn**
  The connection that was used to initialise the media control client

- **Param err**
  Error value. 0 on success, GATT error or errno on fail

- **Param orders**
  The playing orders supported (bitmap)

typedef void (*bt_mcc_read_media_state_cb)(struct bt_conn *conn, int err, uint8_t state)
Callback function for \textit{bt_mcc_read_media_state()}
Called when the media state is read or notified

- **Param conn**
  The connection that was used to initialise the media control client

- **Param err**
  Error value. 0 on success, GATT error or errno on fail

- **Param state**
  The Media State

typedef void (*bt_mcc_send_cmd_cb)(struct bt_conn *conn, int err, const struct mpl_cmd *cmd)
Callback function for \textit{bt_mcc_send_cmd()}
Called when a command is sent, i.e. when the media control point is set

- **Param conn**
  The connection that was used to initialise the media control client

- **Param err**
  Error value. 0 on success, GATT error or errno on fail

- **Param cmd**
  The command sent

typedef void (*bt_mcc_cmd_ntf_cb)(struct bt_conn *conn, int err, const struct mpl_cmd_ntf *ntf)
Callback function for command notifications.
Called when the media control point is notified

6.1. Bluetooth
Notifications for commands (i.e. for writes to the media control point) use a different parameter structure than what is used for sending commands (writing to the media control point)

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param ntf**
The command notification

```c
typedef void (*bt_mcc_read_opcodes_supported_cb)(struct bt_conn *conn, int err, uint32_t opcodes)
```

Callback function for `bt_mcc_read_opcodes_supported()`
Called when the supported opcodes (commands) are read or notified

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param opcodes**
The supported opcodes

```c
typedef void (*bt_mcc_send_search_cb)(struct bt_conn *conn, int err, const struct mpl_search *search)
```

Callback function for `bt_mcc_send_search()`
Called when a search is sent, i.e. when the search control point is set

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param search**
The search set (or attempted to set)

```c
typedef void (*bt_mcc_search_ntf_cb)(struct bt_conn *conn, int err, uint8_t result_code)
```

Callback function for search notifications.
Called when the search control point is notified

Notifications for searches (i.e. for writes to the search control point) use a different parameter structure than what is used for sending searches (writing to the search control point)

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param result_code**
The search notification

```c
typedef void (*bt_mcc_read_search_results_obj_id_cb)(struct bt_conn *conn, int err, uint64_t id)
```
Callback function for `bt_mcc_read_search_results_obj_id()`
Called when the search results object ID is read or notified

Note that the Search Results Object ID value may be zero, in case the characteristic does not exist on the server. (This will be the case if there has not been a successful search.)

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param id**
The Search Results Object ID (UINT48)

typedef void (*bt_mcc_read_content_control_id_cb)(struct bt_conn *conn, int err, uint8_t ccid)

Callback function for `bt_mcc_read_content_control_id()`
Called when the content control ID is read

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param ccid**
The Content Control ID

typedef void (*bt_mcc_otc_obj_selected_cb)(struct bt_conn *conn, int err)

Callback function for object selected.
Called when an object is selected

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

typedef void (*bt_mcc_otc_obj_metadata_cb)(struct bt_conn *conn, int err)

Callback function for `bt_mcc_otc_read_object_metadata()`
Called when object metadata is read

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

typedef void (*bt_mcc_otc_read_icon_object_cb)(struct bt_conn *conn, int err, struct net_buf_simple *buf)

Callback function for `bt_mcc_otc_read_icon_object()`
Called when the icon object is read

If err is EMSGSIZE, the object contents have been truncated.
Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param buf
Buffer containing the object contents

typedef void (*bt_mcc_otc_read_track_segments_object_cb)(struct bt_conn *conn, int err, struct net_buf_simple *buf)
Callback function for bt_mcc_otc_read_track_segments_object()
Called when the track segments object is read

If err is EMSGSIZE, the object contents have been truncated.

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param buf
Buffer containing the object contents

typedef void (*bt_mcc_otc_read_current_track_object_cb)(struct bt_conn *conn, int err, struct net_buf_simple *buf)
Callback function for bt_mcc_otc_read_current_track_object()
Called when the current track object is read

If err is EMSGSIZE, the object contents have been truncated.

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param buf
Buffer containing the object contents

typedef void (*bt_mcc_otc_read_next_track_object_cb)(struct bt_conn *conn, int err, struct net_buf_simple *buf)
Callback function for bt_mcc_otc_read_next_track_object()
Called when the next track object is read

If err is EMSGSIZE, the object contents have been truncated.
typedef void (*bt_mcc_otc_read_parent_group_object_cb)(struct bt_conn *conn, int err, struct net_buf_simple *buf)

Callback function for \texttt{bt\_mcc\_otc\_read\_parent\_group\_object()}

Called when the parent group object is read.

If \texttt{err} is EMSGSIZE, the object contents have been truncated.

\textbf{Param conn}
\hspace{1em}The connection that was used to initialise the media control client

\textbf{Param err}
\hspace{1em}Error value. 0 on success, GATT error or errno on fail

\textbf{Param buf}
\hspace{1em}Buffer containing the object contents

typedef void (*bt_mcc_otc_read_current_group_object_cb)(struct bt_conn *conn, int err, struct net_buf_simple *buf)

Callback function for \texttt{bt\_mcc\_otc\_read\_current\_group\_object()}

Called when the current group object is read.

If \texttt{err} is EMSGSIZE, the object contents have been truncated.

\textbf{Param conn}
\hspace{1em}The connection that was used to initialise the media control client

\textbf{Param err}
\hspace{1em}Error value. 0 on success, GATT error or errno on fail

\textbf{Param buf}
\hspace{1em}Buffer containing the object contents

\section*{Functions}

\texttt{int bt\_mcc\_init(struct \texttt{bt\_mcc\_cb} *cb)}

Initialize Media Control Client.

\textbf{Parameters}
\hspace{1em}• \texttt{cb} – Callbacks to be used

\textbf{Returns}
\hspace{1em}0 if success, errno on failure.

\texttt{int bt\_mcc\_discover\_mcs(struct bt\_conn *conn, bool subscribe)}

Discover Media Control Service.

Discover Media Control Service (MCS) on the server given by the connection Optionally subscribe to notifications.

Shall be called once, after media control client initialization and before using other media control client functionality.

\textbf{Parameters}
\hspace{1em}• \texttt{conn} – Connection to the peer device
\hspace{1em}• \texttt{subscribe} – Whether to subscribe to notifications
int bt_mcc_read_player_name(struct bt_conn *conn)
Read Media Player Name.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_icon_obj_id(struct bt_conn *conn)
Read Icon Object ID.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_icon_url(struct bt_conn *conn)
Read Icon Object URL.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_track_title(struct bt_conn *conn)
Read Track Title.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_track_duration(struct bt_conn *conn)
Read Track Duration.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_track_position(struct bt_conn *conn)
Read Track Position.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_set_track_position(struct bt_conn *conn, int32_t pos)
Set Track position.

Parameters
• conn – Connection to the peer device
• **pos** – Track position

**Returns**
0 if success, errno on failure.

int `bt_mcc_read_playback_speed`(struct bt_conn *conn)
Read Playback speed.

**Parameters**
• **conn** – Connection to the peer device

**Returns**
0 if success, errno on failure.

int `bt_mcc_set_playback_speed`(struct bt_conn *conn, int8_t speed)
Set Playback Speed.

**Parameters**
• **conn** – Connection to the peer device
• **speed** – Playback speed

**Returns**
0 if success, errno on failure.

int `bt_mcc_read_seeking_speed`(struct bt_conn *conn)
Read Seeking speed.

**Parameters**
• **conn** – Connection to the peer device

**Returns**
0 if success, errno on failure.

int `bt_mcc_read_segments_obj_id`(struct bt_conn *conn)
Read Track Segments Object ID.

**Parameters**
• **conn** – Connection to the peer device

**Returns**
0 if success, errno on failure.

int `bt_mcc_read_current_track_obj_id`(struct bt_conn *conn)
Read Current Track Object ID.

**Parameters**
• **conn** – Connection to the peer device

**Returns**
0 if success, errno on failure.

int `bt_mcc_set_current_track_obj_id`(struct bt_conn *conn, uint64_t id)
Set Current Track Object ID.

Set the Current Track to the the track given by the id parameter

**Parameters**
• **conn** – Connection to the peer device
• **id** – Object Transfer Service ID (UINT48) of the track to set as the current track

**Returns**
0 if success, errno on failure.
int bt_mcc_read_next_track_obj_id(struct bt_conn *conn)
Read Next Track Object ID.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_set_next_track_obj_id(struct bt_conn *conn, uint64_t id)
Set Next Track Object ID.
Set the Next Track to the the track given by the id parameter

Parameters
• conn – Connection to the peer device
• id – Object Transfer Service ID (UINT48) of the track to set as the next track

Returns
0 if success, errno on failure.

int bt_mcc_read_current_group_obj_id(struct bt_conn *conn)
Read Current Group Object ID.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_set_current_group_obj_id(struct bt_conn *conn, uint64_t id)
Set Current Group Object ID.
Set the Current Group to the the group given by the id parameter

Parameters
• conn – Connection to the peer device
• id – Object Transfer Service ID (UINT48) of the group to set as the current group

Returns
0 if success, errno on failure.

int bt_mcc_read_parent_group_obj_id(struct bt_conn *conn)
Read Parent Group Object ID.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_playing_order(struct bt_conn *conn)
Read Playing Order.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.
int bt_mcc_set_playing_order(struct bt_conn *conn, uint8_t order)
Set Playing Order.

Parameters
- conn – Connection to the peer device
- order – Playing order

Returns
0 if success, errno on failure.

int bt_mcc_read_playing_orders_supported(struct bt_conn *conn)
Read Playing Orders Supported.

Parameters
- conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_media_state(struct bt_conn *conn)
Read Media State.

Parameters
- conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_send_cmd(struct bt_conn *conn, const struct mpl_cmd *cmd)
Send a command.

Parameters
- conn – Connection to the peer device
- cmd – The command to send

Returns
0 if success, errno on failure.

int bt_mcc_read_opcodes_supported(struct bt_conn *conn)
Read Opcodes Supported.

Parameters
- conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_send_search(struct bt_conn *conn, const struct mpl_search *search)
Send a Search command.

Parameters
- conn – Connection to the peer device
- search – The search

Returns
0 if success, errno on failure.
int bt_mcc_read_search_results_obj_id(struct bt_conn *conn)
Search Results Group Object ID.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_content_control_id(struct bt_conn *conn)
Read Content Control ID.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_otc_read_object_metadata(struct bt_conn *conn)
Read the current object metadata.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_otc_read_icon_object(struct bt_conn *conn)
Read the Icon Object.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_otc_read_track_segments_object(struct bt_conn *conn)
Read the Track Segments Object.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_otc_read_current_track_object(struct bt_conn *conn)
Read the Current Track Object.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_otc_read_next_track_object(struct bt_conn *conn)
Read the Next Track Object.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.
int bt_mcc_otc_read_current_group_object(struct bt_conn *conn)
Read the Current Group Object.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_otc_read_parent_group_object(struct bt_conn *conn)
Read the Parent Group Object.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

struct bt_ots_client *bt_mcc_otc_inst(struct bt_conn *conn)
Look up MCC OTC instance.

Parameters
• conn – The connection to the MCC server.

Returns
Pointer to a MCC OTC instance if found else NULL.

struct bt_mcc_cb
#include <mcc.h> Media control client callbacks.

Bluetooth Mesh Profile

The Bluetooth Mesh profile adds secure wireless multi-hop communication for Bluetooth Low Energy. This module implements the Bluetooth Mesh Protocol Specification v1.1.
Read more about Bluetooth Mesh on the Bluetooth SIG Website.

Core
The core provides functionality for managing the general Bluetooth Mesh state.

Low Power Node
The Low Power Node (LPN) role allows battery powered devices to participate in a mesh network as a leaf node. An LPN interacts with the mesh network through a Friend node, which is responsible for relaying any messages directed to the LPN. The LPN saves power by keeping its radio turned off, and only wakes up to either send messages or poll the Friend node for any incoming messages.

The radio control and polling is managed automatically by the mesh stack, but the LPN API allows the application to trigger the polling at any time through bt_mesh_lpn_poll(). The LPN operation parameters, including poll interval, poll event timing and Friend requirements is controlled through the CONFIG_BT_MESH_LOW_POWER option and related configuration options.

When using the LPN feature with logging, it is strongly recommended to only use the CONFIG_LOG_MODE_DEFERRED option. Log modes other than the deferred may cause unintended delays during processing of log messages. This in turns will affect scheduling of the receive delay and receive window. The same limitation applies for the CONFIG_BT_MESH_FRIEND option.
Replay Protection List  The Replay Protection List (RPL) is used to hold recently received sequence numbers from elements within the mesh network to perform protection against replay attacks.

To keep a node protected against replay attacks after reboot, it needs to store the entire RPL in the persistent storage before it is powered off. Depending on the amount of traffic in a mesh network, storing recently seen sequence numbers can make flash wear out sooner or later. To mitigate this, `CONFIG_BT_MESH_RPL_STORE_TIMEOUT` can be used. This option postpones storing of RPL entries in the persistent storage.

This option, however, doesn't completely solve the issue as the node may get powered off before the timer to store the RPL is fired. To ensure that messages can not be replayed, the node can initiate storage of the pending RPL entry (or entries) at any time (or sufficiently before power loss) by calling `bt_mesh_rpl_pending_store()`. This is up to the node to decide, which RPL entries are to be stored in this case.

Setting `CONFIG_BT_MESH_RPL_STORE_TIMEOUT` to -1 allows to completely switch off the timer, which can help to significantly reduce flash wear out. This moves the responsibility of storing RPL to the user application and requires that sufficient power backup is available from the time this API is called until all RPL entries are written to the flash.

Finding the right balance between `CONFIG_BT_MESH_RPL_STORE_TIMEOUT` and calling `bt_mesh_rpl_pending_store()` may reduce a risk of security vulnerability and flash wear out.

Persistent storage  The mesh stack uses the Settings Subsystem for storing the device configuration persistently. When the stack configuration changes and the change needs to be stored persistently, the stack schedules a work item. The delay between scheduling the work item and submitting it to the workqueue is defined by the `CONFIG_BT_MESH_STORE_TIMEOUT` option. Once storing of data is scheduled, it can not be rescheduled until the work item is processed. Exceptions are made in certain cases as described below.

When IV index, Sequence Number or CDB configuration have to be stored, the work item is submitted to the workqueue without the delay. If the work item was previously scheduled, it will be rescheduled without the delay.

The Replay Protection List uses the same work item to store RPL entries. If storing of RPL entries is requested and no other configuration is pending to be stored, the delay is set to `CONFIG_BT_MESH_RPL_STORE_TIMEOUT`. If other stack configuration has to be stored, the delay defined by the `CONFIG_BT_MESH_STORE_TIMEOUT` option is less than `CONFIG_BT_MESH_RPL_STORE_TIMEOUT`, and the work item was scheduled by the Replay Protection List, the work item will be rescheduled.

When the work item is running, the stack will store all pending configuration, including the RPL entries.

Work item execution context  The `CONFIG_BT_MESH_SETTINGS_WORKQ` option configures the context from which the work item is executed. This option is enabled by default, and results in stack using a dedicated cooperative thread to process the work item. This allows the stack to process other incoming and outgoing messages, as well as other work items submitted to the system workqueue, while the stack configuration is being stored.

When this option is disabled, the work item is submitted to the system workqueue. This means that the system workqueue is blocked for the time it takes to store the stack's configuration. It is not recommended to disable this option as this will make the device non-responsive for a noticeable amount of time.

Advertisement identity  All mesh stack bearers advertise data with the `BT_ID_DEFAULT` local identity. The value is preset in the mesh stack implementation. When Bluetooth® Low Energy
(LE) and Bluetooth Mesh coexist on the same device, the application should allocate and configure another local identity for Bluetooth LE purposes before starting the communication.

**API reference**

*group bt_mesh*

Bluetooth Mesh.

**Defines**

- **BT_MESH_NET_PRIMARY**
  Primary Network Key index.

- **BT_MESH_FEAT_RELAY**
  Relay feature.

- **BT_MESH_FEAT_PROXY**
  GATT Proxy feature.

- **BT_MESH_FEAT_FRIEND**
  Friend feature.

- **BT_MESH_FEAT_LOW_POWER**
  Low Power Node feature.

- **BT_MESH_FEAT_SUPPORTED**
  Supported heartbeat publication features.

- **BT_MESH_LPN_CB_DEFINE(_name)**
  Register a callback structure for Friendship events.

  **Parameters**

  - `_name` – Name of callback structure.

- **BT_MESH_FRIEND_CB_DEFINE(_name)**
  Register a callback structure for Friendship events.

  Registers a callback structure that will be called whenever Friendship gets established or terminated.

  **Parameters**

  - `_name` – Name of callback structure.

**Functions**

- **int bt_mesh_init(const struct bt_mesh_prov *prov, const struct bt_mesh_comp *comp)**

  Initialize Mesh support.

  After calling this API, the node will not automatically advertise as unprovisioned, rather the `bt_mesh_prov_enable()` API needs to be called to enable unprovisioned advertising on one or more provisioning bearers.

  **Parameters**
• **prov** – Node provisioning information.
  • **comp** – Node Composition.

**Returns**
Zero on success or (negative) error code otherwise.

```c
void bt_mesh_reset(void)
```
Reset the state of the local Mesh node.

Resets the state of the node, which means that it needs to be reprovisioned to become an active node in a Mesh network again.

After calling this API, the node will not automatically advertise as unprovisioned, rather the `bt_mesh_prov_enable()` API needs to be called to enable unprovisioned advertising on one or more provisioning bearers.

```c
int bt_mesh_suspend(void)
```
Suspend the Mesh network temporarily.

This API can be used for power saving purposes, but the user should be aware that leaving the local node suspended for a long period of time may cause it to become permanently disconnected from the Mesh network. If at all possible, the Friendship feature should be used instead, to make the node into a Low Power Node.

**Note:** Should not be called from work queue due to undefined behavior. This is due to `k_work_flush_delayable()` being used in disabling of the extended advertising.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_resume(void)
```
Resume a suspended Mesh network.

This API resumes the local node, after it has been suspended using the `bt_mesh_suspend()` API.

**Returns**
0 on success, or (negative) error code on failure.

```c
void bt_mesh_iv_update_test(bool enable)
```
Toggle the IV Update test mode.

This API is only available if the IV Update test mode has been enabled in Kconfig. It is needed for passing most of the IV Update qualification test cases.

**Parameters**
• **enable** – true to enable IV Update test mode, false to disable it.

```c
bool bt_mesh_iv_update(void)
```
Toggle the IV Update state.

This API is only available if the IV Update test mode has been enabled in Kconfig. It is needed for passing most of the IV Update qualification test cases.

**Returns**
true if IV Update In Progress state was entered, false otherwise.

```c
int bt_mesh_lpn_set(bool enable)
```
Toggle the Low Power feature of the local device.

Enables or disables the Low Power feature of the local device. This is exposed as a runtime feature, since the device might want to change this e.g. based on being plugged into a stable power source or running from a battery power source.
Parameters
• **enable** – true to enable LPN functionality, false to disable it.

Returns
Zero on success or (negative) error code otherwise.

```c
int bt_mesh_lpn_poll(void)
```
Send out a Friend Poll message.
Send a Friend Poll message to the Friend of this node. If there is no established Friendship the function will return an error.

Returns
Zero on success or (negative) error code otherwise.

```c
int bt_mesh_friend_terminate(uint16_t lpn_addr)
```
Terminate Friendship.
Terminated Friendship for given LPN.

Parameters
• **lpn_addr** – Low Power Node address.

Returns
Zero on success or (negative) error code otherwise.

```c
void bt_mesh_rpl_pending_store(uint16_t addr)
```
Store pending RPL entry(ies) in the persistent storage.
This API allows the user to store pending RPL entry(ies) in the persistent storage without waiting for the timeout.

Note: When flash is used as the persistent storage, calling this API too frequently may wear it out.

Parameters
• **addr** – Address of the node which RPL entry needs to be stored or `BT_MESH_ADDR_ALL_NODES` to store all pending RPL entries.

```c
const uint8_t *bt_mesh_va_uuid_get(uint16_t addr, const uint8_t *uuid, uint16_t *retaddr)
```
Iterate stored Label UUIDs.
When `addr` is `BT_MESH_ADDR_UNASSIGNED`, this function iterates over all available addresses starting with `uuid`. In this case, use `retaddr` to get virtual address representation of the returned Label UUID. When `addr` is a virtual address, this function returns next Label UUID corresponding to the `addr`. When `uuid` is NULL, this function returns the first available UUID. If `uuid` is previously returned uuid, this function returns following uuid.

Parameters
• **addr** – Virtual address to search for, or `BT_MESH_ADDR_UNASSIGNED`.
• **uuid** – Pointer to the previously returned Label UUID or NULL.
• **retaddr** – Pointer to a memory where virtual address representation of the returning UUID is to be stored to.

Returns
Pointer to Label UUID, or NULL if no more entries found.

6.1. Bluetooth
struct bt_mesh_lpn_cb
#include <main.h> Low Power Node callback functions.

Public Members

void (*established)(uint16_t net_idx, uint16_t friend_addr, uint8_t queue_size, uint8_t recv_window)
Friendship established.
This callback notifies the application that friendship has been successfully established.
  
  **Param net_idx**
  NetKeyIndex used during friendship establishment.
  
  **Param friend_addr**
  Friend address.
  
  **Param queue_size**
  Friend queue size.
  
  **Param recv_window**
  Low Power Node's listens duration for Friend response.

void (*terminated)(uint16_t net_idx, uint16_t friend_addr)
Friendship terminated.
This callback notifies the application that friendship has been terminated.
  
  **Param net_idx**
  NetKeyIndex used during friendship establishment.
  
  **Param friend_addr**
  Friend address.

void (*polled)(uint16_t net_idx, uint16_t friend_addr, bool retry)
Local Poll Request.
This callback notifies the application that the local node has polled the friend node.
This callback will be called before `bt_mesh_lpn_cb::established` when attempting to establish a friendship.
  
  **Param net_idx**
  NetKeyIndex used during friendship establishment.
  
  **Param friend_addr**
  Friend address.
  
  **Param retry**
  Retry or first poll request for each transaction.

struct bt_mesh_friend_cb
#include <main.h> Friend Node callback functions.

Public Members

void (*established)(uint16_t net_idx, uint16_t lpn_addr, uint8_t recv_delay, uint32_t polltimeout)
Friendship established.
This callback notifies the application that friendship has been successfully established.
**Param net_idx**  
NetKeyIndex used during friendship establishment.

**Param lpn_addr**  
Low Power Node address.

**Param recv_delay**  
Receive Delay in units of 1 millisecond.

**Param polltimeout**  
PollTimeout in units of 1 millisecond.

```c
void (*terminated)(uint16_t net_idx, uint16_t lpn_addr)
```

Friendship terminated.

This callback notifies the application that friendship has been terminated.

- **Param net_idx**  
  NetKeyIndex used during friendship establishment.

- **Param lpn_addr**  
  Low Power Node address.

```c
void (*polled)(uint16_t net_idx, uint16_t lpn_addr)
```

Friend Poll Request.

This callback notifies the application that the low power node has polled the friend node.

This callback will be called before `bt_mesh_friend_cb::established` when attempting to establish a friendship.

- **Param net_idx**  
  NetKeyIndex used during friendship establishment.

- **Param lpn_addr**  
  LPN address.

---

**Access layer**  
The access layer is the application's interface to the Bluetooth Mesh network. The access layer provides mechanisms for compartmentalizing the node behavior into elements and models, which are implemented by the application.

**Mesh models**  
The functionality of a mesh node is represented by models. A model implements a single behavior the node supports, like being a light, a sensor or a thermostat. The mesh models are grouped into *elements*. Each element is assigned its own unicast address, and may only contain one of each type of model. Conventionally, each element represents a single aspect of the mesh node behavior. For instance, a node that contains a sensor, two lights and a power outlet would spread this functionality across four elements, with each element instantiating all the models required for a single aspect of the supported behavior.

The node's element and model structure is specified in the node composition data, which is passed to `bt_mesh_init()` during initialization. The Bluetooth SIG have defined a set of foundation models (see *Mesh models*) and a set of models for implementing common behavior in the *Bluetooth Mesh Model Specification*. All models not specified by the Bluetooth SIG are vendor models, and must be tied to a Company ID.

Mesh models have several parameters that can be configured either through initialization of the mesh stack or with the *Configuration Server*:

**Opcode list**  
The opcode list contains all message opcodes the model can receive, as well as the minimum acceptable payload length and the callback to pass them to. Models can support any number of opcodes, but each opcode can only be listed by one model in each element.
The full opcode list must be passed to the model structure in the composition data, and cannot be changed at runtime. The end of the opcode list is determined by the special `BT_MESH_MODEL_OP_END` entry. This entry must always be present in the opcode list, unless the list is empty. In that case, `BT_MESH_MODEL_NO_OPS` should be used in place of a proper opcode list definition.

**AppKey list**  The AppKey list contains all the application keys the model can receive messages on. Only messages encrypted with application keys in the AppKey list will be passed to the model.

The maximum number of supported application keys each model can hold is configured with the `CONFIG_BT_MESH_MODEL_KEY_COUNT` configuration option. The contents of the AppKey list is managed by the Configuration Server.

**Subscription list**  A model will process all messages addressed to the unicast address of their element (given that the utilized application key is present in the AppKey list). Additionally, the model will process packets addressed to any group or virtual address in its subscription list. This allows nodes to address multiple nodes throughout the mesh network with a single message.

The maximum number of supported addresses in the Subscription list each model can hold is configured with the `CONFIG_BT_MESH_MODEL_GROUP_COUNT` configuration option. The contents of the subscription list is managed by the Configuration Server.

**Model publication**  The models may send messages in two ways:

- By specifying a set of message parameters in a `bt_mesh_msg_ctx`, and calling `bt_mesh_model_send()`.
- By setting up a `bt_mesh_model_pub` structure and calling `bt_mesh_model_publish()`.

When publishing messages with `bt_mesh_model_publish()`, the model will use the publication parameters configured by the Configuration Server. This is the recommended way to send un-prompted model messages, as it passes the responsibility of selecting message parameters to the network administrator, which likely knows more about the mesh network than the individual nodes will.

To support publishing with the publication parameters, the model must allocate a packet buffer for publishing, and pass it to `bt_mesh_model_pub.msg`. The Config Server may also set up period publication for the publication message. To support this, the model must populate the `bt_mesh_model_pub.update` callback. The `bt_mesh_model_pub.update` callback will be called right before the message is published, allowing the model to change the payload to reflect its current state.

By setting `bt_mesh_model_pub.retr_update` to 1, the model can configure the `bt_mesh_model_pub.update` callback to be triggered on every retransmission. This can, for example, be used by models that make use of a Delay parameter, which can be adjusted for every retransmission. The `bt_mesh_model_pub_is_retransmission()` function can be used to differentiate a first publication and a retransmission. The `BT_MESH_PUB_MSG_TOTAL` and `BT_MESH_PUB_MSG_NUM` macros can be used to return total number of transmissions and the retransmission number within one publication interval.

**Extended models**  The Bluetooth Mesh specification allows the mesh models to extend each other. When a model extends another, it inherits that model's functionality, and extension can be used to construct complex models out of simple ones, leveraging the existing model functionality to avoid defining new opcodes. Models may extend any number of models, from any element. When one model extends another in the same element, the two models will share subscription lists. The mesh stack implements this by merging the subscription lists of the two models into one, combining the number of subscriptions the models can have in total. Models may extend...
models that extend others, creating an “extension tree”. All models in an extension tree share a single subscription list per element it spans.

Model extensions are done by calling `bt_mesh_model_extend()` during initialization. A model can only be extended by one other model, and extensions cannot be circular. Note that binding of node states and other relationships between the models must be defined by the model implementations.

The model extension concept adds some overhead in the access layer packet processing, and must be explicitly enabled with `CONFIG_BT_MESH_MODEL_EXTENSIONS` to have any effect.

**Model data storage**  Mesh models may have data associated with each model instance that needs to be stored persistently. The access API provides a mechanism for storing this data, leveraging the internal model instance encoding scheme. Models can store one user defined data entry per instance by calling `bt_mesh_model_data_store()`. To be able to read out the data the next time the device reboots, the model’s `bt_mesh_model_cb.settings_set` callback must be populated. This callback gets called when model specific data is found in the persistent storage. The model can retrieve the data by calling the `read_cb` passed as a parameter to the callback. See the *Settings* module documentation for details.

When model data changes frequently, storing it on every change may lead to increased wear of flash. To reduce the wear, the model can postpone storing of data by calling `bt_mesh_model_data_store_schedule()`. The stack will schedule a work item with delay defined by the `CONFIG_BT_MESH_STORE_TIMEOUT` option. When the work item is running, the stack will call the `bt_mesh_model_cb.pending_store` callback for every model that has requested storing of data. The model can then call `bt_mesh_model_data_store()` to store the data.

If `CONFIG_BT_MESH_SETTINGS_WORKQ` is enabled, the `bt_mesh_model_cb.pending_store` callback is called from a dedicated thread. This allows the stack to process other incoming and outgoing messages while model data is being stored. It is recommended to use this option and the `bt_mesh_model_data_store_schedule()` function when large amount of data needs to be stored.

**Composition Data**  The Composition Data provides information about a mesh device. A device’s Composition Data holds information about the elements on the device, the models that it supports, and other features. The Composition Data is split into different pages, where each page contains specific feature information about the device. In order to access this information, the user may use the *Configuration Server* model or, if supported, the *Large Composition Data Server* model.

**Composition Data Page 0**  Composition Data Page 0 provides the fundamental information about a device, and is mandatory for all mesh devices. It contains the element and model composition, the supported features, and manufacturer information.

**Composition Data Page 1**  Composition Data Page 1 provides information about the relationships between models, and is mandatory for all mesh devices. A model may extend and/or correspond to one or more models. A model can extend another model by calling `bt_mesh_model_extend()`, or correspond to another model by calling `bt_mesh_model_correspond()`. `CONFIG_BT_MESH_MODEL_EXTENSION_LIST_SIZE` specifies how many model relations can be stored in the composition on a device, and this number should reflect the number of `bt_mesh_model_extend()` and `bt_mesh_model_correspond()` calls.

**Composition Data Page 2**  Composition Data Page 2 provides information for supported mesh profiles. Mesh profile specifications define product requirements for devices that want to support a specific Bluetooth SIG defined profile. Currently supported profiles can be found in section 3.12 in *Bluetooth SIG Assigned Numbers*. Composition Data Page 2 is only mandatory for devices that claim support for one or more mesh profile(s).
Composition Data Pages 128, 129 and 130
Composition Data Pages 0, 1 and 2 respectively. They are used to represent the new content of the mirrored pages when the Composition Data will change after a firmware update. See Composition Data and Models Metadata for details.

Delayable messages
The delayable message functionality is enabled with Kconfig option CONFIG_BT_MESH_ACCESS_DELAYABLE_MSG. This is an optional functionality that implements specification recommendations for messages that are transmitted by a model in a response to a received message, also called response messages.

Response messages should be sent with the following random delays:
- Between 20 and 50 milliseconds if the received message was sent to a unicast address
- Between 20 and 500 milliseconds if the received message was sent to a group or virtual address

The delayable message functionality is triggered if the bt_mesh_msg_ctx.rnd_delay flag is set. The delayable message functionality stores messages in the local memory while they are waiting for the random delay expiration.

If the transport layer doesn’t have sufficient memory to send a message at the moment the random delay expires, the message is postponed for another 10 milliseconds. If the transport layer cannot send a message for any other reason, the delayable message functionality raises the bt_mesh_send_cb.start callback with a transport layer error code.

If the delayable message functionality cannot find enough free memory to store an incoming message, it will send messages with delay close to expiration to free memory.

When the mesh stack is suspended or reset, messages not yet sent are removed and the bt_mesh_send_cb.start callback is raised with an error code.

Note: When a model sends several messages in a row, it may happen that the messages are not sent in the order they were passed to the access layer. This is because some messages can be delayed for a longer time than the others.

Disable the randomization by setting the bt_mesh_msg_ctx.rnd_delay to false, when a set of messages originated by the same model needs to be sent in a certain order.

Delayable publications
The delayable publication functionality implements the specification recommendations for message publication delays in the following cases:
- Between 20 to 500 milliseconds when the Bluetooth Mesh stack starts or when the publication is triggered by the bt_mesh_model_publish() function
- Between 20 to 50 milliseconds for periodically published messages

This feature is optional and enabled with the CONFIG_BT_MESH_DELAYABLE_PUBLICATION Kconfig option. When enabled, each model can enable or disable the delayable publication by setting the bt_mesh_model_pub.delayable bit field to 1 or 0 correspondingly. This bit field can be changed at any time.

API reference

group bt_mesh_access
Access layer.
Group addresses

BT_MESH_ADDR_UNASSIGNED
    unassigned

BT_MESH_ADDR_ALL_NODES
    all-nodes

BT_MESH_ADDR_RELAYS
    all-relays

BT_MESH_ADDR_FRIENDS
    all-friends

BT_MESH_ADDR_PROXIES
    all-proxies

BT_MESH_ADDR_DFW_NODES
    all-directed-forwarding-nodes

BT_MESH_ADDR_IP_NODES
    all-ipt-nodes

BT_MESH_ADDR_IP_BR_ROUTERS
    all-ipt-border-routers

Predefined key indexes

BT_MESH_KEY_UNUSED
    Key unused.

BT_MESH_KEY_ANY
    Any key index.

BT_MESH_KEY_DEV
    Device key.

BT_MESH_KEY_DEV_LOCAL
    Local device key.

BT_MESH_KEY_DEV_REMOTE
    Remote device key.

BT_MESH_KEY_DEV_ANY
    Any device key.
Foundation Models

**BT_MESH_MODEL_ID_CFG_SRV**
Configuration Server.

**BT_MESH_MODEL_ID_CFG_CLI**
Configuration Client.

**BT_MESH_MODEL_ID_HEALTH_SRV**
Health Server.

**BT_MESH_MODEL_ID_HEALTH_CLI**
Health Client.

**BT_MESH_MODEL_ID_REMOTE_PROV_SRV**
Remote Provisioning Server.

**BT_MESH_MODEL_ID_REMOTE_PROV_CLI**
Remote Provisioning Client.

**BT_MESH_MODEL_ID_PRIV_BEACON_SRV**
Private Beacon Server.

**BT_MESH_MODEL_ID_PRIV_BEACON_CLI**
Private Beacon Client.

**BT_MESH_MODEL_ID_SAR_CFG_SRV**
SAR Configuration Server.

**BT_MESH_MODEL_ID_SAR_CFG_CLI**
SAR Configuration Client.

**BT_MESH_MODEL_ID_OP_AGG_SRV**
Opcodes Aggregator Server.

**BT_MESH_MODEL_ID_OP_AGG_CLI**
Opcodes Aggregator Client.

**BT_MESH_MODEL_ID_LARGE_COMP_DATA_SRV**
Large Composition Data Server.

**BT_MESH_MODEL_ID_LARGE_COMP_DATA_CLI**
Large Composition Data Client.

**BT_MESH_MODEL_ID_SOL_PDU_RPL_SRV**
Solicitation PDU RPL Configuration Server.

**BT_MESH_MODEL_ID_SOL_PDU_RPL_CLI**
Solicitation PDU RPL Configuration Client.
Models from the Mesh Model Specification

**BT_MESH_MODEL_ID_ON_DEMAND_PROXY_SRV**
Private Proxy Server.

**BT_MESH_MODEL_ID_ON_DEMAND_PROXY_CLI**
Private Proxy Client.

**BT_MESH_MODEL_ID_GEN_ONOFF_SRV**
Generic OnOff Server.

**BT_MESH_MODEL_ID_GEN_ONOFF_CLI**
Generic OnOff Client.

**BT_MESH_MODEL_ID_GEN_LEVEL_SRV**
Generic Level Server.

**BT_MESH_MODEL_ID_GEN_LEVEL_CLI**
Generic Level Client.

**BT_MESH_MODEL_ID_GEN_DEF_TRANS_TIME_SRV**
Generic Default Transition Time Server.

**BT_MESH_MODEL_ID_GEN_DEF_TRANS_TIME_CLI**
Generic Default Transition Time Client.

**BT_MESH_MODEL_ID_GEN_POWER_ONOFF_SRV**
Generic Power OnOff Server.

**BT_MESH_MODEL_ID_GEN_POWER_ONOFF_SETUP_SRV**
Generic Power OnOff Setup Server.

**BT_MESH_MODEL_ID_GEN_POWER_ONOFF_CLI**
Generic Power OnOff Client.

**BT_MESH_MODEL_ID_GEN_POWER_LEVEL_SRV**
Generic Power Level Server.

**BT_MESH_MODEL_ID_GEN_POWER_LEVEL_SETUP_SRV**
Generic Power Level Setup Server.

**BT_MESH_MODEL_ID_GEN_POWER_LEVEL_CLI**
Generic Power Level Client.

**BT_MESH_MODEL_ID_GEN_BATTERY_SRV**
Generic Battery Server.
BT_MESH_MODEL_ID_GEN_BATTERY_CLI
Generic Battery Client.

BT_MESH_MODEL_ID_GEN_LOCATION_SRV
Generic Location Server.

BT_MESH_MODEL_ID_GEN_LOCATION_SETUPSRV
Generic Location Setup Server.

BT_MESH_MODEL_ID_GEN_LOCATION_CLI
Generic Location Client.

BT_MESH_MODEL_ID_GEN_ADMIN_PROP_SRV
Generic Admin Property Server.

BT_MESH_MODEL_ID_GEN_MANUFACTURER_PROP_SRV
Generic Manufacturer Property Server.

BT_MESH_MODEL_ID_GEN_USER_PROP_SRV
Generic User Property Server.

BT_MESH_MODEL_ID_GEN_CLIENT_PROP_SRV
Generic Client Property Server.

BT_MESH_MODEL_ID_GEN_PROP_CLI
Generic Property Client.

BT_MESH_MODEL_ID_SENSOR_SRV
Sensor Server.

BT_MESH_MODEL_ID_SENSOR_SETUP_SRV
Sensor Setup Server.

BT_MESH_MODEL_ID_SENSOR_CLI
Sensor Client.

BT_MESH_MODEL_ID_TIME_SRV
Time Server.

BT_MESH_MODEL_ID_TIME_SETUP_SRV
Time Setup Server.

BT_MESH_MODEL_ID_TIME_CLI
Time Client.

BT_MESH_MODEL_ID_SCENE_SRV
Scene Server.
BT_MESH_MODEL_ID_SCENE_SETUP_SRV
Scene Setup Server.

BT_MESH_MODEL_ID_SCENE_CLI
Scene Client.

BT_MESH_MODEL_ID_SCHEDULER_SRV
Scheduler Server.

BT_MESH_MODEL_ID_SCHEDULER_SETUP_SRV
Scheduler Setup Server.

BT_MESH_MODEL_ID_SCHEDULER_CLI
Scheduler Client.

BT_MESH_MODEL_ID_LIGHT_LIGHTNESS_SRV
Light Lightness Server.

BT_MESH_MODEL_ID_LIGHT_LIGHTNESS_SETUP_SRV
Light Lightness Setup Server.

BT_MESH_MODEL_ID_LIGHT_LIGHTNESS_CLI
Light Lightness Client.

BT_MESH_MODEL_ID_LIGHT_CTL_SRV
Light CTL Server.

BT_MESH_MODEL_ID_LIGHT_CTL_SETUP_SRV
Light CTL Setup Server.

BT_MESH_MODEL_ID_LIGHT_CTL_CLI
Light CTL Client.

BT_MESH_MODEL_ID_LIGHT_CTL_TEMP_SRV
Light CTL Temperature Server.

BT_MESH_MODEL_ID_LIGHT_HSL_SRV
Light HSL Server.

BT_MESH_MODEL_ID_LIGHT_HSL_SETUP_SRV
Light HSL Setup Server.

BT_MESH_MODEL_ID_LIGHT_HSL_CLI
Light HSL Client.

BT_MESH_MODEL_ID_LIGHT_HSL_HUE_SRV
Light HSL Hue Server.
BT_MESH_MODEL_ID_LIGHT_HSL_SAT_SRV
Light HSL Saturation Server.

BT_MESH_MODEL_ID_LIGHT_XYL_SRV
Light xyL Server.

BT_MESH_MODEL_ID_LIGHT_XYL_SETUP_SRV
Light xyL Setup Server.

BT_MESH_MODEL_ID_LIGHT_XYL_CLI
Light xyL Client.

BT_MESH_MODEL_ID_LIGHT_LC_SRV
Light LC Server.

BT_MESH_MODEL_ID_LIGHT_LC_SETUP_SRV
Light LC Setup Server.

BT_MESH_MODEL_ID_LIGHT_LC_CLI
Light LC Client.

Models from the Mesh Binary Large Object Transfer Model Specification

BT_MESH_MODEL_ID_BLOB_SRV
BLOB Transfer Server.

BT_MESH_MODEL_ID_BLOB_CLI
BLOB Transfer Client.

Models from the Mesh Device Firmware Update Model Specification

BT_MESH_MODEL_ID_DFU_SRV
Firmware Update Server.

BT_MESH_MODEL_ID_DFU_CLI
Firmware Update Client.

BT_MESH_MODEL_ID_DFD_SRV
Firmware Distribution Server.

BT_MESH_MODEL_ID_DFD_CLI
Firmware Distribution Client.

Defines
BT_MESH_ADDR_IS_UNICAST(addr)
    Check if a Bluetooth Mesh address is a unicast address.

BT_MESH_ADDR_IS_GROUP(addr)
    Check if a Bluetooth Mesh address is a group address.

BT_MESH_ADDR_IS_FIXED_GROUP(addr)
    Check if a Bluetooth Mesh address is a fixed group address.

BT_MESH_ADDR_IS_VIRTUAL(addr)
    Check if a Bluetooth Mesh address is a virtual address.

BT_MESH_ADDR_IS_RFU(addr)
    Check if a Bluetooth Mesh address is an RFU address.

BT_MESH_IS_DEV_KEY(key)
    Check if a Bluetooth Mesh key is a device key.

BT_MESH_APP_SEG_SDU_MAX
    Maximum size of an access message segment (in octets).

BT_MESH_APP_UNSEG_SDU_MAX
    Maximum payload size of an unsegmented access message (in octets).

BT_MESH_RX_SEG_MAX
    Maximum number of segments supported for incoming messages.

BT_MESH_TX_SEG_MAX
    Maximum number of segments supported for outgoing messages.

BT_MESH_TX_SDU_MAX
    Maximum possible payload size of an outgoing access message (in octets).

BT_MESH_RX_SDU_MAX
    Maximum possible payload size of an incoming access message (in octets).

BT_MESH_ELEM(_loc, _mods, _vnd_mods)
    Helper to define a mesh element within an array.
    In case the element has no SIG or Vendor models the helper macro
    BT_MESH_MODEL_NONE can be given instead.

    Parameters
    • _loc – Location Descriptor.
    • _mods – Array of models.
    • _vnd_mods – Array of vendor models.

BT_MESH_MODEL_OP_1(b0)
BT_MESH_MODEL_OP_2(b0, b1)
BT_MESH_MODEL_OP_3(b0, cid)

BT_MESH_LEN_EXACT(len)
    Macro for encoding exact message length for fixed-length messages.
**BT_MESH_LEN_MIN(len)**

Macro for encoding minimum message length for variable-length messages.

**BT_MESH_MODEL_OP_END**

End of the opcode list.

Must always be present.

**BT_MESH_MODEL_NO_OPS**

Helper to define an empty opcode list.

This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

**BT_MESH_MODEL_NONE**

Helper to define an empty model array.

This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

**BT_MESH_MODEL_CNT_CB(_id, _op, _pub, _user_data, _keys, _grps, _cb)**

Composition data SIG model entry with callback functions with specific number of keys & groups.

This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

**Parameters**

- _id – Model ID.
- _op – Array of model opcode handlers.
- _pub – Model publish parameters.
- _user_data – User data for the model.
- _keys – Number of keys that can be bound to the model. Shall not exceed CONFIG_BT_MESH_MODEL_KEY_COUNT.
- _grps – Number of addresses that the model can be subscribed to. Shall not exceed CONFIG_BT_MESH_MODEL_GROUP_COUNT.
- _cb – Callback structure, or NULL to keep no callbacks.

**BT_MESH_MODEL_CNT_VND_CB(_company, _id, _op, _pub, _user_data, _keys, _grps, _cb)**

Composition data vendor model entry with callback functions with specific number of keys & groups.

This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

**Parameters**

- _company – Company ID.
- _id – Model ID.
- _op – Array of model opcode handlers.
- _pub – Model publish parameters.
- _user_data – User data for the model.
- _keys – Number of keys that can be bound to the model. Shall not exceed CONFIG_BT_MESH_MODEL_KEY_COUNT.
• _grps – Number of addresses that the model can be subscribed to. Shall not exceed CONFIG_BT_MESH_MODEL_GROUP_COUNT.
• _cb – Callback structure, or NULL to keep no callbacks.

BT_MESH_MODEL_CB(_id, _op, _pub, _user_data, _cb)
Composition data SIG model entry with callback functions.
This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

Parameters
• _id – Model ID.
• _op – Array of model opcode handlers.
• _pub – Model publish parameters.
• _user_data – User data for the model.
• _cb – Callback structure, or NULL to keep no callbacks.

BT_MESH_MODEL_METADATA_CB(_id, _op, _pub, _user_data, _cb, _metadata)
Composition data SIG model entry with callback functions and metadata.
This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

Parameters
• _id – Model ID.
• _op – Array of model opcode handlers.
• _pub – Model publish parameters.
• _user_data – User data for the model.
• _cb – Callback structure, or NULL to keep no callbacks.
• _metadata – Metadata structure.

BT_MESH_MODEL_VND_CB(_company, _id, _op, _pub, _user_data, _cb)
Composition data vendor model entry with callback functions.
This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

Parameters
• _company – Company ID.
• _id – Model ID.
• _op – Array of model opcode handlers.
• _pub – Model publish parameters.
• _user_data – User data for the model.
• _cb – Callback structure, or NULL to keep no callbacks.

BT_MESH_MODEL_VND_METADATA_CB(_company, _id, _op, _pub, _user_data, _cb, _metadata)
Composition data vendor model entry with callback functions and metadata.
This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

Parameters
• _company – Company ID.
- _id – Model ID.
- _op – Array of model opcode handlers.
- _pub – Model publish parameters.
- _user_data – User data for the model.
- _cb – Callback structure, or NULL to keep no callbacks.
- _metadata – Metadata structure.

**BT_MESH_MODEL(_id, _op, _pub, _user_data)**
Composition data SIG model entry.

This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

**Parameters**
- _id – Model ID.
- _op – Array of model opcode handlers.
- _pub – Model publish parameters.
- _user_data – User data for the model.

**BT_MESH_MODEL_VND(_company, _id, _op, _pub, _user_data)**
Composition data vendor model entry.

This macro uses compound literal feature of C99 standard and thus is available only from C, not C++.

**Parameters**
- _company – Company ID.
- _id – Model ID.
- _op – Array of model opcode handlers.
- _pub – Model publish parameters.
- _user_data – User data for the model.

**BT_MESH_TRANSMIT(count, int_ms)**
Encode transmission count & interval steps.

**Parameters**
- count – Number of retransmissions (first transmission is excluded).
- int_ms – Interval steps in milliseconds. Must be greater than 0, less than or equal to 320, and a multiple of 10.

**Returns**
Mesh transmit value that can be used e.g. for the default values of the configuration model data.

**BT_MESH_TRANSMIT_COUNT(transmit)**
Decode transmit count from a transmit value.

**Parameters**
- transmit – Encoded transmit count & interval value.

**Returns**
Transmission count (actual transmissions is N + 1).
**BT_MESH_TRANSMIT_INT**\( (\text{transmit}) \)
Decode transmit interval from a transmit value.

**Parameters**
- \( \text{transmit} \) – Encoded transmit count & interval value.

**Returns**
Transmission interval in milliseconds.

**BT_MESH_PUB_TRANSMIT**\( (\text{count}, \text{int\_ms}) \)
Encode Publish Retransmit count & interval steps.

**Parameters**
- \( \text{count} \) – Number of retransmissions (first transmission is excluded).
- \( \text{int\_ms} \) – Interval steps in milliseconds. Must be greater than 0 and a multiple of 50.

**Returns**
Mesh transmit value that can be used e.g. for the default values of the configuration model data.

**BT_MESH_PUB_TRANSMIT_COUNT**\( (\text{transmit}) \)
Decode Publish Retransmit count from a given value.

**Parameters**
- \( \text{transmit} \) – Encoded Publish Retransmit count & interval value.

**Returns**
Retransmission count (actual transmissions is \( N + 1 \)).

**BT_MESH_PUB_TRANSMIT_INT**\( (\text{transmit}) \)
Decode Publish Retransmit interval from a given value.

**Parameters**
- \( \text{transmit} \) – Encoded Publish Retransmit count & interval value.

**Returns**
Transmission interval in milliseconds.

**BT_MESH_PUB_MSG_TOTAL**\( (\text{pub}) \)
Get total number of messages within one publication interval including initial publication.

**Parameters**
- \( \text{pub} \) – Model publication context.

**Returns**
total number of messages.

**BT_MESH_PUB_MSG_NUM**\( (\text{pub}) \)
Get message number within one publication interval.
Meant to be used inside \texttt{bt\_mesh\_model\_pub::update}.

**Parameters**
- \( \text{pub} \) – Model publication context.

**Returns**
message number starting from 1.
BT_MESH_MODEL_PUB_DEFINE(_name, _update, _msg_len)
Define a model publication context.

Parameters

• _name – Variable name given to the context.
• _update – Optional message update callback (may be NULL).
• _msg_len – Length of the publication message.

BT_MESH_MODELS_METADATA_ENTRY(_len, _id, _data)
Initialize a Models Metadata entry structure in a list.

Parameters

• _len – Length of the metadata entry.
• _id – ID of the Models Metadata entry.
• _data – Pointer to a contiguous memory that contains the metadata.

BT_MESH_MODELS_METADATA_NONE
Helper to define an empty Models metadata array.

BT_MESH_MODELS_METADATA_END
End of the Models Metadata list.
Must always be present.

BT_MESH_TTL_DEFAULT
Special TTL value to request using configured default TTL.

BT_MESH_TTL_MAX
Maximum allowed TTL value.

Functions

int bt_mesh_model_send(const struct bt_mesh_model *model, struct bt_mesh_msg_ctx *ctx, struct net_buf_simple *msg, const struct bt_mesh_send_cb *cb, void *cb_data)
Send an Access Layer message.

Parameters

• model – Mesh (client) Model that the message belongs to.
• ctx – Message context, includes keys, TTL, etc.
• msg – Access Layer payload (the actual message to be sent).
• cb – Optional “message sent” callback.
• cb_data – User data to be passed to the callback.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_model_publish(const struct bt_mesh_model *model)
Send a model publication message.

Before calling this function, the user needs to ensure that the model publication message (bt_mesh_model_pub::msg) contains a valid message to be sent. Note that this API
is only to be used for non-period publishing. For periodic publishing the app only needs to make sure that `bt_mesh_model_pub::msg` contains a valid message whenever the `bt_mesh_model_pub::update` callback is called.

**Parameters**
- **model** – Mesh (client) Model that’s publishing the message.

**Returns**
- 0 on success, or (negative) error code on failure.

```c
static inline bool bt_mesh_model_pub_is_retransmission(const struct bt_mesh_model *model)
```

Check if a message is being retransmitted.

Meant to be used inside the `bt_mesh_model_pub::update` callback.

**Parameters**
- **model** – Mesh Model that supports publication.

**Returns**
- true if this is a retransmission, false if this is a first publication.

```c
const struct bt_mesh_elem *bt_mesh_model_elem(const struct bt_mesh_model *mod)
```

Get the element that a model belongs to.

**Parameters**
- **mod** – Mesh model.

**Returns**
- Pointer to the element that the given model belongs to.

```c
const struct bt_mesh_model *bt_mesh_model_find(const struct bt_mesh_elem *elem, uint16_t id)
```

Find a SIG model.

**Parameters**
- **elem** – Element to search for the model in.
- **id** – Model ID of the model.

**Returns**
- A pointer to the Mesh model matching the given parameters, or NULL if no SIG model with the given ID exists in the given element.

```c
const struct bt_mesh_model *bt_mesh_model_find_vnd(const struct bt_mesh_elem *elem, uint16_t id)
```

Find a vendor model.

**Parameters**
- **elem** – Element to search for the model in.
- **company** – Company ID of the model.
- **id** – Model ID of the model.

**Returns**
- A pointer to the Mesh model matching the given parameters, or NULL if no vendor model with the given ID exists in the given element.

```c
static inline bool bt_mesh_model_in_primary(const struct bt_mesh_model *mod)
```

Get whether the model is in the primary element of the device.

**Parameters**
- **mod** – Mesh model.
Returns
true if the model is on the primary element, false otherwise.

int bt_mesh_model_data_store(const struct bt_mesh_model *mod, bool vnd, const char *name, const void *data, size_t data_len)

Immediately store the model's user data in persistent storage.

Parameters
• mod – Mesh model.
• vnd – This is a vendor model.
• name – Name/key of the settings item. Only SETTINGS_MAX_DIR_DEPTH bytes will be used at most.
• data – Model data to store, or NULL to delete any model data.
• data_len – Length of the model data.

Returns
0 on success, or (negative) error code on failure.

void bt_mesh_model_data_store_schedule(const struct bt_mesh_model *mod)

Schedule the model's user data store in persistent storage.

This function triggers the bt_mesh_model_cb::pending_store callback for the corresponding model after delay defined by CONFIG_BT_MESH_STORE_TIMEOUT.

The delay is global for all models. Once scheduled, the callback can not be re-scheduled until previous schedule completes.

Parameters
• mod – Mesh model.

int bt_mesh_model_extend(const struct bt_mesh_model *extending_mod, const struct bt_mesh_model *base_mod)

Let a model extend another.

Mesh models may be extended to reuse their functionality, forming a more complex model. A Mesh model may extend any number of models, in any element. The extensions may also be nested, ie a model that extends another may itself be extended.

A set of models that extend each other form a model extension list.

All models in an extension list share one subscription list per element. The access layer will utilize the combined subscription list of all models in an extension list and element, giving the models extended subscription list capacity.

If CONFIG_BT_MESH_COMP_PAGE_1 is enabled, it is not allowed to call this function before the bt_mesh_model_cb::init callback is called for both models, except if it is called as part of the final callback.

Parameters
• extending_mod – Mesh model that is extending the base model.
• base_mod – The model being extended.

Return values
0 – Successfully extended the base_mod model.

int bt_mesh_model_correspond(const struct bt_mesh_model *corresponding_mod, const struct bt_mesh_model *base_mod)

Let a model correspond to another.

Mesh models may correspond to each other, which means that if one is present, other must be present too. A Mesh model may correspond to any number of models, in any
element. All models connected together via correspondence form single Correspondence Group, which has it's unique Correspondence ID. Information about Correspondence is used to construct Composition Data Page 1.

This function must be called on already initialized base_mod. Because this function is designed to be called in corresponding_mod initializer, this means that base_mod shall be initialized before corresponding_mod is initialized.

Parameters

- **corresponding_mod** – Mesh model that is corresponding to the base model.
- **base_mod** – The model being corresponded to.

Return values

- **0** – Successfully saved correspondence to the base_mod model.
- **-ENOMEM** – There is no more space to save this relation.
- **-ENOTSUP** – Composition Data Page 1 is not supported.

```c
bool bt_mesh_model_is_extended(const struct bt_mesh_model *model)
```

Check if model is extended by another model.

Parameters

- **model** – The model to check.

Return values

- **true** – If model is extended by another model, otherwise false

```c
int bt_mesh_comp_change_prepare(void)
```

Indicate that the composition data will change on next bootup.

Tell the config server that the composition data is expected to change on the next bootup, and the current composition data should be backed up.

Returns

- Zero on success or (negative) error code otherwise.

```c
int bt_mesh_models_metadata_change_prepare(void)
```

Indicate that the metadata will change on next bootup.

Tell the config server that the models metadata is expected to change on the next bootup, and the current models metadata should be backed up.

Returns

- Zero on success or (negative) error code otherwise.

```c
int bt_mesh_comp2_register(const struct bt_mesh_comp2 *comp2)
```

Register composition data page 2 of the device.

Register Mesh Profiles information (Ref section 3.12 in Bluetooth SIG Assigned Numbers) for composition data page 2 of the device.

**Note:** There must be at least one record present in comp2

Parameters

- **comp2** – Pointer to composition data page 2.

Returns

- Zero on success or (negative) error code otherwise.
struct bt_mesh_elem
   "include <access.h>" Abstraction that describes a Mesh Element.

Public Members

const uint16_t loc
   Location Descriptor (GATT Bluetooth Namespace Descriptors)

const uint8_t model_count
   The number of SIG models in this element.

const uint8_t vnd_model_count
   The number of vendor models in this element.

const struct bt_mesh_model *const models
   The list of SIG models in this element.

const struct bt_mesh_model *const vnd_models
   The list of vendor models in this element.

struct bt_mesh_elem_rt_ctx
   "include <access.h>" Mesh Element runtime information.

Public Members

uint16_t addr
   Unicast Address.
   Set at runtime during provisioning.

struct bt_mesh_model_op
   "include <access.h>" Model opcode handler.

Public Members

const uint32_t opcode
   OpCode encoded using the BT_MESH_MODEL_OP_* macros.

const ssize_t len
   Message length.
   If the message has variable length then this value indicates minimum message
   length and should be positive. Handler function should verify precise length based
   on the contents of the message. If the message has fixed length then this value
   should be negative. Use BT_MESH_LEN_* macros when defining this value.
int (*const func)(const struct bt_mesh_model *model, struct bt_mesh_msg_ctx *ctx, 
            struct net_buf_simple *buf)

Handler function for this opcode.

  **Param** model
  Model instance receiving the message.

  **Param** ctx
  Message context for the message.

  **Param** buf
  Message buffer containing the message payload, not including the opcode.

  **Return**
  Zero on success or (negative) error code otherwise.

struct bt_mesh_model_pub
#include <access.h> Model publication context.
  The context should primarily be created using the BT_MESH_MODEL_PUB_DEFINE 
  macro.

  **Public Members**

const struct bt_mesh_model *mod
  The model the context belongs to.
  Initialized by the stack.

  **uint16_t addr**
  Publish Address.

const uint8_t *uuid
  Label UUID if Publish Address is Virtual Address.

  **uint16_t key**
  Publish AppKey Index.

  **uint16_t cred**
  Friendship Credentials Flag.

  **uint16_t send_rel**
  Force reliable sending (segment acks)

  **uint16_t fast_period**
  Use FastPeriodDivisor.

  **uint16_t retr_update**
  Call update callback on every retransmission.

  **uint8_t ttl**
  Publish Time to Live.
uint8_t retransmit
  Retransmit Count & Interval Steps.

uint8_t period
  Publish Period.

uint8_t period_div
  Divisor for the Period.

uint8_t count
  Transmissions left.

uint8_t delayable
  Use random delay for publishing.

uint32_t period_start
  Start of the current period.

struct net_buf_simple *msg
  Publication buffer, containing the publication message.
  This will get correctly created when the publication context has been defined using
  the BT_MESH_MODEL_PUB_DEFINE macro.

  BT_MESH_MODEL_PUB_DEFINE(name, update, size);

int (*update)(const struct bt_mesh_model *mod)
  Callback for updating the publication buffer.
  When set to NULL, the model is assumed not to support periodic publishing. When
  set to non-NULL the callback will be called periodically and is expected to update
  bt_mesh_model_pub::msg with a valid publication message.
  If the callback returns non-zero, the publication is skipped and will resume on the
  next periodic publishing interval.
  When bt_mesh_model_pub::retr_update is set to 1, the callback will be called on
  every retransmission.

  Param mod
  The Model the Publication Context belongs to.
  Return
  Zero on success or (negative) error code otherwise.

struct k_work_delayable timer
  Publish Period Timer.
  Only for stack-internal use.

struct bt_mesh_models_metadata_entry
  #include <access.h> Models Metadata Entry struct.
  The struct should primarily be created using the BT_MESH_MODELS_METADATA_ENTRY
  macro.

struct bt_mesh_model_cb
  #include <access.h> Model callback functions.
Public Members

```c
int (*const settings_set)(const struct bt_mesh_model *model, const char *name,
                          size_t len_rd, settings_read_cb read_cb, void *cb_arg)
```

Set value handler of user data tied to the model.

See also:
```
settings_handler::h_set
```

- **Param model**
  Model to set the persistent data of.
- **Param name**
  Name/key of the settings item.
- **Param len_rd**
  The size of the data found in the backend.
- **Param read_cb**
  Function provided to read the data from the backend.
- **Param cb_arg**
  Arguments for the read function provided by the backend.

**Return**

0 on success, error otherwise.

```c
int (*const start)(const struct bt_mesh_model *model)
```

Callback called when the mesh is started.

This handler gets called after the node has been provisioned, or after all mesh data has been loaded from persistent storage.

When this callback fires, the mesh model may start its behavior, and all Access APIs are ready for use.

- **Param model**
  Model this callback belongs to.

**Return**

0 on success, error otherwise.

```c
int (*const init)(const struct bt_mesh_model *model)
```

Model init callback.

Called on every model instance during mesh initialization.

If any of the model init callbacks return an error, the Mesh subsystem initialization will be aborted, and the error will be returned to the caller of `bt_mesh_init`.

- **Param model**
  Model to be initialized.

**Return**

0 on success, error otherwise.

```c
void (*const reset)(const struct bt_mesh_model *model)
```

Model reset callback.

Called when the mesh node is reset. All model data is deleted on reset, and the model should clear its state.

**Note:** If the model stores any persistent data, this needs to be erased manually.
**Param model**
Model this callback belongs to.

```c
void (*const pending_store)(const struct bt_mesh_model *model)
```

Callback used to store pending model's user data.

Triggered by `bt_mesh_model_data_store_schedule`.

To store the user data, call `bt_mesh_model_data_store`.

**Param model**
Model this callback belongs to.

```c
struct bt_mesh_mod_id_vnd
#include <access.h> Vendor model ID.
```

**Public Members**

```c
uint16_t company
Vendor's company ID.
```

```c
uint16_t id
Model ID.
```

```c
struct bt_mesh_model
#include <access.h> Abstraction that describes a Mesh Model instance.
```

**Public Members**

```c
const uint16_t id
SIG model ID.
```

```c
const struct bt_mesh_mod_id_vnd vnd
Vendor model ID.
```

```c
struct bt_mesh_model_pub *const pub
Model Publication.
```

```c
uint16_t *const keys
AppKey List.
```

```c
uint16_t *const groups
Subscription List (group or virtual addresses)
```

```c
const uint8_t **const uuids
List of Label UUIDs the model is subscribed to.
```

```c
const struct bt_mesh_model_op *const op
Opcode handler list.
```
const struct bt_mesh_model_cb *const cb
    Model callback structure.

struct bt_mesh_model_rt_ctx
    #include <access.h>

Public Members

void *user_data
    Model-specific user data.

struct bt_mesh_send_cb
    #include <access.h> Callback structure for monitoring model message sending.

Public Members

void (*start)(uint16_t duration, int err, void *cb_data)
    Handler called at the start of the transmission.
    Param duration
        The duration of the full transmission.
    Param err
        Error occurring during sending.
    Param cb_data
        Callback data, as passed to the send API.

void (*end)(int err, void *cb_data)
    Handler called at the end of the transmission.
    Param err
        Error occurring during sending.
    Param cb_data
        Callback data, as passed to the send API.

struct bt_mesh_comp
    #include <access.h> Node Composition.

Public Members

uint16_t cid
    Company ID.

uint16_t pid
    Product ID.

uint16_t vid
    Version ID.
size_t elem_count
    The number of elements in this device.

const struct bt_mesh_elem *elem
    List of elements.

struct bt_mesh_comp2_record
    #include <access.h> Composition data page 2 record.

Public Members

uint16_t id
    Mesh profile ID.

uint8_t x
    Major version.

uint8_t y
    Minor version.

uint8_t z
    Z version.

struct bt_mesh_comp2_record version
    Mesh Profile Version.

uint8_t elem_offset_cnt
    Element offset count.

cost uint8_t *elem_offset
    Element offset list.

uint16_t data_len
    Length of additional data.

cost void *data
    Additional data.

struct bt_mesh_comp2
    #include <access.h> Node Composition data page 2.

Public Members

size_t record_cnt
    The number of Mesh Profile records on a device.

const struct bt_mesh_comp2_record *record
    List of records.
Mesh models

Foundation models The Bluetooth Mesh specification defines foundation models that can be used by network administrators to configure and diagnose mesh nodes.

Configuration Client The Configuration Client model is a foundation model defined by the Bluetooth Mesh specification. It provides functionality for configuring most parameters of a mesh node, including encryption keys, model configuration and feature enabling.

The Configuration Client model communicates with a Configuration Server model using the device key of the target node. The Configuration Client model may communicate with servers on other nodes or self-configure through the local Configuration Server model.

All configuration functions in the Configuration Client API have net_idx and addr as their first parameters. These should be set to the network index and primary unicast address that the target node was provisioned with.

The Configuration Client model is optional, and it must only be instantiated on the primary element if present in the Composition Data.

API reference

group bt_mesh_cfg_cli

  Configuration Client Model.

Defines

BT_MESH_MODEL_CFG_CLI(cli_data)

  Generic Configuration Client model composition data entry.

  Parameters

  • cli_data – Pointer to a Configuration Client Model instance.

BT_MESH_PUB_PERIOD_100MS(steps)

  Helper macro to encode model publication period in units of 100ms.

  Parameters

  • steps – Number of 100ms steps.

  Returns

  Encoded value that can be assigned to bt_mesh_cfg_cli_mod_pub.period

BT_MESH_PUB_PERIOD_SEC(steps)

  Helper macro to encode model publication period in units of 1 second.

  Parameters

  • steps – Number of 1 second steps.

  Returns

  Encoded value that can be assigned to bt_mesh_cfg_cli_mod_pub.period

BT_MESH_PUB_PERIOD_10SEC(steps)

  Helper macro to encode model publication period in units of 10 seconds.

  Parameters

  • steps – Number of 10 second steps.
Returns
Encoded value that can be assigned to `bt_mesh_cfg_cli_mod_pub.period`

**BT_MESH_PUB_PERIOD_10MIN(steps)**
Helper macro to encode model publication period in units of 10 minutes.

Parameters
• **steps** – Number of 10 minute steps.

Returns
Encoded value that can be assigned to `bt_mesh_cfg_cli_mod_pub.period`

Functions

```c
int bt_mesh_cfg_cli_node_reset(uint16_t net_idx, uint16_t addr, bool *status)
```
Reset the target node and remove it from the network.

Parameters
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **status** – Status response parameter

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_comp_data_get(uint16_t net_idx, uint16_t addr, uint8_t page, uint8_t *rsp, struct net_buf_simple *comp)
```
Get the target node’s composition data.

If the other device does not have the given composition data page, it will return the largest page number it supports that is less than the requested page index. The actual page the device responds with is returned in `rsp`.

This method can be used asynchronously by setting `rsp` and `comp` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **page** – Composition data page, or `0xff` to request the first available page.
• **rsp** – Return parameter for the returned page number, or NULL.
• **comp** – Composition data buffer to fill.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_beacon_get(uint16_t net_idx, uint16_t addr, uint8_t *status)
```
Get the target node’s network beacon state.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **status** – Status response parameter. Returns one of `BT_MESH_BEACON_DISABLED` or `BT_MESH_BEACON_ENABLED` on success.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_krp_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx,
                            uint8_t *status, uint8_t *phase)
```

Get the target node's network key refresh phase state.

This method can be used asynchronously by setting `status` and `phase` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `key_net_idx` – Network key index.
- `status` – Status response parameter.
- `phase` – Pointer to the Key Refresh variable to fill.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_krp_set(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx,
                            uint8_t transition, uint8_t *status, uint8_t *phase)
```

Set the target node's network key refresh phase parameters.

This method can be used asynchronously by setting `status` and `phase` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `key_net_idx` – Network key index.
- `transition` – Transition parameter.
- `status` – Status response parameter.
- `phase` – Pointer to the new Key Refresh phase. Will return the actual Key Refresh phase after updating.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_beacon_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)
```

Set the target node's network beacon state.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
• **val** – New network beacon state, should be one of `BT_MESH_BEACON_DISABLED` or `BT_MESH_BEACON_ENABLED`.

• **status** – Status response parameter. Returns one of `BT_MESH_BEACON_DISABLED` or `BT_MESH_BEACON_ENABLED` on success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_ttl_get(uint16_t net_idx, uint16_t addr, uint8_t *ttl)
```

Get the target node's Time To Live value.

This method can be used asynchronously by setting `ttl` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **ttl** – TTL response buffer.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_ttl_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *ttl)
```

Set the target node's Time To Live value.

This method can be used asynchronously by setting `ttl` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **val** – New Time To Live value.

• **ttl** – TTL response buffer.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_friend_get(uint16_t net_idx, uint16_t addr, uint8_t *status)
```

Get the target node's Friend feature status.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **status** – Status response parameter. Returns one of `BT_MESH_FRIEND_DISABLED`, `BT_MESH_FRIEND_ENABLED` or `BT_MESH_FRIEND_NOT_SUPPORTED` on success.

**Returns**

0 on success, or (negative) error code on failure.
int bt_mesh_cfg_cli_friend_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)

Set the target node's Friend feature state.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **val** – New Friend feature state. Should be one of **BT_MESH_FRIEND_DISABLED** or **BT_MESH_FRIEND_ENABLED**.
- **status** – Status response parameter. Returns one of **BT_MESH_FRIEND_DISABLED**, **BT_MESH_FRIEND_ENABLED** or **BT_MESH_FRIEND_NOT_SUPPORTED** on success.

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_gatt_proxy_get(uint16_t net_idx, uint16_t addr, uint8_t *status)

Get the target node's Proxy feature state.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **status** – Status response parameter. Returns one of **BT_MESH_GATT_PROXY_DISABLED**, **BT_MESH_GATT_PROXY_ENABLED** or **BT_MESH_GATT_PROXY_NOT_SUPPORTED** on success.

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_gatt_proxy_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)

Set the target node's Proxy feature state.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **val** – New Proxy feature state. Must be one of **BT_MESH_GATT_PROXY_DISABLED** or **BT_MESH_GATT_PROXY_ENABLED**.
- **status** – Status response parameter. Returns one of **BT_MESH_GATT_PROXY_DISABLED**, **BT_MESH_GATT_PROXY_ENABLED** or **BT_MESH_GATT_PROXY_NOT_SUPPORTED** on success.

Returns

0 on success, or (negative) error code on failure.
int bt_mesh_cfg_cli_net_transmit_get(uint16_t net_idx, uint16_t addr, uint8_t *transmit)

Get the target node's network_transmit state.
This method can be used asynchronously by setting transmit as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• transmit – Network transmit response parameter. Returns the encoded network transmission parameters on success. Decoded with BT_MESH_TRANSMIT_COUNT and BT_MESH_TRANSMIT_INT.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_net_transmit_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *transmit)

Set the target node's network transmit parameters.
This method can be used asynchronously by setting transmit as NULL. This way the method will not wait for response and will return immediately after sending the command.

See also:
BT_MESH_TRANSMIT.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• val – New encoded network transmit parameters.
• transmit – Network transmit response parameter. Returns the encoded network transmission parameters on success. Decoded with BT_MESH_TRANSMIT_COUNT and BT_MESH_TRANSMIT_INT.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_relay_get(uint16_t net_idx, uint16_t addr, uint8_t *status, uint8_t *transmit)

Get the target node's Relay feature state.
This method can be used asynchronously by setting status and transmit as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• status – Status response parameter. Returns one of BT_MESH_RELAY_DISABLED, BT_MESH_RELAY_ENABLED or BT_MESH_RELAY_NOT_SUPPORTED on success.
• **transmit** – Transmit response parameter. Returns the encoded relay transmission parameters on success. Decoded with `BT_MESH_TRANSMIT_COUNT` and `BT_MESH_TRANSMIT_INT`.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_relay_set(uint16_t net_idx, uint16_t addr, uint8_t new_relay,
                           uint8_t new_transmit, uint8_t *status, uint8_t *transmit)
```

Set the target node's Relay parameters.

This method can be used asynchronously by setting `status` and `transmit` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**See also:**

`BT_MESH_TRANSMIT`.

**Parameters**

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **new_relay** – New relay state. Must be one of `BT_MESH_RELAY_DISABLED` or `BT_MESH_RELAY_ENABLED`.
- **new_transmit** – New encoded relay transmit parameters.
- **status** – Status response parameter. Returns one of `BT_MESH_RELAY_DISABLED`, `BT_MESH_RELAY_ENABLED` or `BT_MESH_RELAY_NOT_SUPPORTED` on success.
- **transmit** – Transmit response parameter. Returns the encoded relay transmission parameters on success. Decoded with `BT_MESH_TRANSMIT_COUNT` and `BT_MESH_TRANSMIT_INT`.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_net_key_add(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx,
                               const uint8_t net_key[16], uint8_t *status)
```

Add a network key to the target node.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **key_net_idx** – Network key index.
- **net_key** – Network key.
- **status** – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.
int bt_mesh_cfg_cli_net_key_get(uint16_t net_idx, uint16_t addr, uint16_t *keys, size_t *key_cnt)

Get a list of the target node's network key indexes.

This method can be used asynchronously by setting keys or key_cnt as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• keys – Net key index list response parameter. Will be filled with all the returned network key indexes it can fill.
• key_cnt – Net key index list length. Should be set to the capacity of the keys list when calling. Will return the number of returned network key indexes upon success.

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_net_key_del(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status)

Delete a network key from the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index.
• status – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_app_key_add(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint16_t key_app_idx, const uint8_t app_key[16], uint8_t *status)

Add an application key to the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index the application key belongs to.
• key_app_idx – Application key index.
• app_key – Application key.
• status – Status response parameter.

Returns

0 on success, or (negative) error code on failure.
int bt_mesh_cfg_cli_app_key_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status, uint16_t *keys, size_t *key_cnt)

Get a list of the target node's application key indexes for a specific network key.

This method can be used asynchronously by setting status and (keys or key_cnt) as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index to request the app key indexes of.
• status – Status response parameter.
• keys – App key index list response parameter. Will be filled with all the returned application key indexes it can fill.
• key_cnt – App key index list length. Should be set to the capacity of the keys list when calling. Will return the number of returned application key indexes upon success.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_app_key_del(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint16_t key_app_idx, uint8_t *status)

Delete an application key from the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index the application key belongs to.
• key_app_idx – Application key index.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_app_bind(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_app_idx, uint16_t mod_id, uint8_t *status)

Bind an application to a SIG model on the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to bind.
• mod_id – Model ID.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_app_unbind(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
uint16_t mod_app_idx, uint16_t mod_id, uint8_t *status)

Unbind an application from a SIG model on the target node.
This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to unbind.
• mod_id – Model ID.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_app_bind_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_app_idx, uint16_t mod_id, uint16_t cid, uint8_t *status)

Bind an application to a vendor model on the target node.
This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to bind.
• mod_id – Model ID.
• cid – Company ID of the model.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_app_unbind_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_app_idx, uint16_t mod_id, uint16_t cid, uint8_t *status)

Unbind an application from a vendor model on the target node.
This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.
Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **mod_app_idx** – Application index to unbind.
- **mod_id** – Model ID.
- **cid** – Company ID of the model.
- **status** – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_app_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint8_t *status, uint16_t *apps, size_t *app_cnt)
```

Get a list of all applications bound to a SIG model on the target node.

This method can be used asynchronously by setting `status` and `(apps or app_cnt)` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **mod_id** – Model ID.
- **status** – Status response parameter.
- **apps** – App index list response parameter. Will be filled with all the returned application key indexes it can fill.
- **app_cnt** – App index list length. Should be set to the capacity of the `apps` list when calling. Will return the number of returned application key indexes upon success.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_app_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, uint8_t *status, uint16_t *apps, size_t *app_cnt)
```

Get a list of all applications bound to a vendor model on the target node.

This method can be used asynchronously by setting `status` and `(apps or app_cnt)` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **mod_id** – Model ID.
- **cid** – Company ID of the model.
• **status** – Status response parameter.

• **apps** – App index list response parameter. Will be filled with all the returned application key indexes it can fill.

• **app_cnt** – App index list length. Should be set to the capacity of the apps list when calling. Will return the number of returned application key indexes upon success.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_pub_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                uint16_t mod_id, struct bt_mesh_cfg_cli_mod_pub *pub,
                                uint8_t *status)
```

Get publish parameters for a SIG model on the target node.
This method can be used asynchronously by setting status and pub as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **elem_addr** – Element address the model is in.

• **mod_id** – Model ID.

• **pub** – Publication parameter return buffer.

• **status** – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_pub_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                    uint16_t mod_id, uint16_t cid, struct bt_mesh_cfg_cli_mod_pub *pub,
                                    uint8_t *status)
```

Get publish parameters for a vendor model on the target node.
This method can be used asynchronously by setting status and pub as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **elem_addr** – Element address the model is in.

• **mod_id** – Model ID.

• **cid** – Company ID of the model.

• **pub** – Publication parameter return buffer.

• **status** – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_pub_set(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                 uint16_t mod_id, struct bt_mesh_cfg_cli_mod_pub *pub,
                                 uint8_t *status)
```
Set publish parameters for a SIG model on the target node.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

pub shall not be NULL.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `pub` – Publication parameters.
- `status` – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_pub_set_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, struct bt_mesh_cfg_cli_mod_pub *pub, uint8_t *status)
```

Set publish parameters for a vendor model on the target node.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

pub shall not be NULL.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `cid` – Company ID of the model.
- `pub` – Publication parameters.
- `status` – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_sub_add(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint8_t *status)
```

Add a group address to a SIG model's subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
• **sub_addr** – Group address to add to the subscription list.
• **mod_id** – Model ID.
• **status** – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_add_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint16_t cid, uint8_t *status)
```

Add a group address to a vendor model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **elem_addr** – Element address the model is in.
• **sub_addr** – Group address to add to the subscription list.
• **mod_id** – Model ID.
• **cid** – Company ID of the model.
• **status** – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_del(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint16_t cid, uint8_t *status)
```

Delete a group address in a SIG model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **elem_addr** – Element address the model is in.
• **sub_addr** – Group address to add to the subscription list.
• **mod_id** – Model ID.
• **status** – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_del_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint16_t cid, uint8_t *status)
```

Delete a group address in a vendor model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.
Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **sub_addr** – Group address to add to the subscription list.
- **mod_id** – Model ID.
- **cid** – Company ID of the model.
- **status** – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_overwrite(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint8_t *status)
```

Overwrite all addresses in a SIG model's subscription list with a group address.

Deletes all subscriptions in the model's subscription list, and adds a single group address instead.

This method can be used asynchronously by setting **status** as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **sub_addr** – Group address to add to the subscription list.
- **mod_id** – Model ID.
- **status** – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_overwrite_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint16_t cid, uint8_t *status)
```

Overwrite all addresses in a vendor model's subscription list with a group address.

Deletes all subscriptions in the model's subscription list, and adds a single group address instead.

This method can be used asynchronously by setting **status** as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **sub_addr** – Group address to add to the subscription list.
- **mod_id** – Model ID.
• cid – Company ID of the model.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_va_add(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
const uint8_t label[16], uint16_t mod_id, uint16_t *virt_addr, uint8_t *status)
```

Add a virtual address to a SIG model's subscription list.
This method can be used asynchronously by setting status and virt_addr as NULL.
This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_va_add_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
const uint8_t label[16], uint16_t mod_id, uint16_t cid, uint16_t *virt_addr,
uint8_t *status)
```

Add a virtual address to a vendor model's subscription list.
This method can be used asynchronously by setting status and virt_addr as NULL.
This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• cid – Company ID of the model.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_va_del(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
const uint8_t label[16], uint16_t mod_id, uint16_t *virt_addr, uint8_t *status)
```
Delete a virtual address in a SIG model’s subscription list.

This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address parameter to add to the subscription list.
• mod_id – Model ID.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_sub_va_del_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, const uint8_t label[16], uint16_t mod_id, uint16_t cid, uint16_t *virt_addr, uint8_t *status)
```

Delete a virtual address in a vendor model’s subscription list.

This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• cid – Company ID of the model.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_sub_va_overwrite(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, const uint8_t label[16], uint16_t mod_id, uint16_t *virt_addr, uint8_t *status)
```

Overwrite all addresses in a SIG model’s subscription list with a virtual address.

Deletes all subscriptions in the model’s subscription list, and adds a single group address instead.

This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

6.1. Bluetooth 1949
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_sub_va_overwrite_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, const uint8_t label[16], uint16_t mod_id, uint16_t cid, uint16_t *virt_addr, uint8_t *status)

Overwrite all addresses in a vendor model's subscription list with a virtual address.
Deletes all subscriptions in the model's subscription list, and adds a single group address instead.
This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• cid – Company ID of the model.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_sub_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint8_t *status, uint16_t *subs, size_t *sub_cnt)

Get the subscription list of a SIG model on the target node.
This method can be used asynchronously by setting status and (subs or sub_cnt) as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_id – Model ID.
• status – Status response parameter.
• **subs** – Subscription list response parameter. Will be filled with all the returned subscriptions it can fill.

• **sub_cnt** – Subscription list element count. Should be set to the capacity of the subs list when calling. Will return the number of returned subscriptions upon success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_sub_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, uint8_t *status, uint16_t *subs, size_t *sub_cnt)
```

Get the subscription list of a vendor model on the target node.

This method can be used asynchronously by setting `status` and (`subs` or `sub_cnt`) as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **elem_addr** – Element address the model is in.

• **mod_id** – Model ID.

• **cid** – Company ID of the model.

• **status** – Status response parameter.

• **subs** – Subscription list response parameter. Will be filled with all the returned subscriptions it can fill.

• **sub_cnt** – Subscription list element count. Should be set to the capacity of the subs list when calling. Will return the number of returned subscriptions upon success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_hb_sub_set(uint16_t net_idx, uint16_t addr, struct bt_mesh_cfg_cli_hb_sub *sub, uint8_t *status)
```

Set the target node’s Heartbeat subscription parameters.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

`sub` shall not be null.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **sub** – New Heartbeat subscription parameters.

• **status** – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.
int bt_mesh_cfg_cli_hb_sub_get(uint16_t net_idx, uint16_t addr, struct 
    bt_mesh_cfg_cli_hb_sub *sub, uint8_t *status)

Get the target node's Heartbeat subscription parameters.
This method can be used asynchronously by setting status and sub as NULL. This way the
method will not wait for response and will return immediately after sending the
command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• sub – Heartbeat subscription parameter return buffer.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_hb_pub_set(uint16_t net_idx, uint16_t addr, const struct 
    bt_mesh_cfg_cli_hb_pub *pub, uint8_t *status)

Set the target node's Heartbeat publication parameters.

This method can be used asynchronously by setting status as NULL. This way the
method will not wait for response and will return immediately after sending the
command.
pub shall not be NULL;

Note: The target node must already have received the specified network key.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• pub – New Heartbeat publication parameters.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_hb_pub_get(uint16_t net_idx, uint16_t addr, struct 
    bt_mesh_cfg_cli_hb_pub *pub, uint8_t *status)

Get the target node's Heartbeat publication parameters.
This method can be used asynchronously by setting status and pub as NULL. This way the
method will not wait for response and will return immediately after sending the
command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• pub – Heartbeat publication parameter return buffer.
• status – Status response parameter.
Returns
0 on success, or (negative) error code on failure.

`int bt_mesh_cfg_cli_mod_sub_del_all(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint8_t *status)`

Delete all group addresses in a SIG model's subscription list.
This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `status` – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

`int bt_mesh_cfg_cli_mod_sub_del_all_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, uint8_t *status)`

Delete all group addresses in a vendor model's subscription list.
This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `cid` – Company ID of the model.
- `status` – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

`int bt_mesh_cfg_cli_net_key_update(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, const uint8_t net_key[16], uint8_t *status)`

Update a network key to the target node.
This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `key_net_idx` – Network key index.
- `net_key` – Network key.
• **status** – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_app_key_update(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint16_t key_app_idx, const uint8_t app_key[16], uint8_t *status)
```

Update an application key to the target node.
This method can be used asynchronously by setting **status** as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **key_net_idx** – Network key index the application key belongs to.
- **key_app_idx** – Application key index.
- **app_key** – Application key.
- **status** – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_node_identity_set(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t new_identity, uint8_t *status, uint8_t *identity)
```

Set the Node Identity parameters.
This method can be used asynchronously by setting **status** and **identity** as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **new_identity** – New identity state. Must be one of **BT_MESH_NODE_IDENTITY_STOPPED** or **BT_MESH_NODE_IDENTITY_RUNNING**
- **key_net_idx** – Network key index the application key belongs to.
- **status** – Status response parameter.
- **identity** – Identity response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_node_identity_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status, uint8_t *identity)
```

Get the Node Identity parameters.
This method can be used asynchronously by setting **status** and **identity** as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **key_net_idx** – Network key index the application key belongs to.
• **status** – Status response parameter.
• **identity** – Identity response parameter. Must be one of **BT_MESH_NODE_IDENTITY_STOPPED** or **BT_MESH_NODE_IDENTITY_RUNNING**

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_lpn_timeout_get(uint16_t net_idx, uint16_t addr, uint16_t unicast_addr, int32_t *polltimeout)
```

Get the Low Power Node Polltimeout parameters.

This method can be used asynchronously by setting `polltimeout` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **unicast_addr** – LPN unicast address.
• **polltimeout** – Poll timeout response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```c
int32_t bt_mesh_cfg_cli_timeout_get(void)
```

Get the current transmission timeout value.

**Returns**
The configured transmission timeout in milliseconds.

```c
void bt_mesh_cfg_cli_timeout_set(int32_t timeout)
```

Set the transmission timeout value.

**Parameters**
• **timeout** – The new transmission timeout.

```c
int bt_mesh_comp_p0_get(struct bt_mesh_comp_p0 *comp, struct net_buf_simple *buf)
```

Create a composition data page 0 representation from a buffer.

The composition data page object will take ownership over the buffer, which should not be manipulated directly after this call.

This function can be used in combination with `bt_mesh_cfg_cli_comp_data_get` to read out composition data page 0 from other devices:

```c
NET_BUF_SIMPLE_DEFINE(buf, BT_MESH_RX_SDU_MAX);
struct bt_mesh_comp_p0 comp;

err = bt_mesh_cfg_cli_comp_data_get(net_idx, addr, 0, &page, &buf);
if (!err) {
    bt_mesh_comp_p0_get(&comp, &buf);
}
```

**Parameters**
• **buf** – Network buffer containing composition data.

---

6.1. Bluetooth
• comp – Composition data structure to fill.

**Returns**
0 on success, or (negative) error code on failure.

```c
struct bt_mesh_comp_p0_elem *bt_mesh_comp_p0_elem_pull(const struct bt_mesh_comp_p0 *comp, struct bt_mesh_comp_p0_elem *elem)
```

Pull a composition data page 0 element from a composition data page 0 instance. Each call to this function will pull out a new element from the composition data page, until all elements have been pulled.

**Parameters**
• comp – Composition data page
• elem – Element to fill.

**Returns**
A pointer to elem on success, or NULL if no more elements could be pulled.

```c
uint16_t bt_mesh_comp_p0_elem_mod(struct bt_mesh_comp_p0_elem *elem, int idx)
```

Get a SIG model from the given composition data page 0 element.

**Parameters**
• elem – Element to read the model from.
• idx – Index of the SIG model to read.

**Returns**
The Model ID of the SIG model at the given index, or 0xffff if the index is out of bounds.

```c
struct bt_mesh_mod_id_vnd bt_mesh_comp_p0_elem_mod_vnd(struct bt_mesh_comp_p0_elem *elem, int idx)
```

Get a vendor model from the given composition data page 0 element.

**Parameters**
• elem – Element to read the model from.
• idx – Index of the vendor model to read.

**Returns**
The model ID of the vendor model at the given index, or {0xffff, 0xffff} if the index is out of bounds.

```c
struct bt_mesh_comp_p1_elem *bt_mesh_comp_p1_elem_pull(struct net_buf_simple *buf, struct bt_mesh_comp_p1_elem *elem)
```

Pull a Composition Data Page 1 Element from a composition data page 1 instance. Each call to this function will pull out a new element from the composition data page, until all elements have been pulled.

**Parameters**
• buf – Composition data page 1 buffer
• elem – Element to fill.
Returns
A pointer to elem on success, or NULL if no more elements could be pulled.

struct bt_mesh_comp_p1_model_item *bt_mesh_comp_p1_item_pull(struct
  bt_mesh_comp_p1_elem *elem, struct
  bt_mesh_comp_p1_model_item *item)

Pull a Composition Data Page 1 Model Item from a Composition Data Page 1 Element.
Each call to this function will pull out a new item from the Composition Data Page 1
Element, until all items have been pulled.

Parameters
• elem – Composition data page 1 Element
• item – Model Item to fill.

Returns
A pointer to item on success, or NULL if no more elements could be pulled.

struct bt_mesh_comp_p1_ext_item *bt_mesh_comp_p1_pull_ext_item(struct
  bt_mesh_comp_p1_model_item *item, struct
  bt_mesh_comp_p1_ext_item *ext_item)

Pull Extended Model Item contained in Model Item.
Each call to this function will pull out a new element from the Extended Model Item,
until all elements have been pulled.

Parameters
• item – Model Item to pull Extended Model Items from
• ext_item – Extended Model Item to fill

Returns
A pointer to ext_item on success, or NULL if item could not be pulled.

struct bt_mesh_comp_p2_record *bt_mesh_comp_p2_record_pull(struct
  net_buf_simple *buf, struct
  bt_mesh_comp_p2_record *record)

Pull a Composition Data Page 2 Record from a composition data page 2 instance.
Each call to this function will pull out a new element from the composition data page,
until all elements have been pulled.

Parameters
• buf – Composition data page 2 buffer
• record – Record to fill.

Returns
A pointer to record on success, or NULL if no more elements could be

int bt_mesh_key_idx_unpack_list(struct net_buf_simple *buf, uint16_t *dst_arr, size_t *dst_cnt)

Unpack a list of key index entries from a buffer.
On success, dst_cnt is set to the amount of unpacked key index entries.

Parameters
buf – Message buffer containing encoded AppKey or NetKey Indexes.

dst_arr – Destination array for the unpacked list.

dst_cnt – Size of the destination array.

Returns
0 on success.

Returns
-EMSGSIZE if dst_arr size is too small to parse full message.

struct bt_mesh_cfg_cli_cb
#include <cfg_cli.h> Mesh Configuration Client Status messages callback.

Public Members

void (*comp_data)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t page, struct net_buf_simple *buf)
Optional callback for Composition data messages.
Handles received Composition data messages from a server.

Note: For decoding buf, please refer to bt_mesh_comp_p0_get and bt_mesh_comp_p1_elem_pull.

Param cli
Client that received the status message.

Param addr
Address of the sender.

Param page
Composition data page.

Param buf
Composition data buffer.

void (*mod_pub_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status,
uint16_t elem_addr, uint16_t mod_id, uint16_t cid, struct bt_mesh_cfg_cli_mod_pub *pub)
Optional callback for Model Pub status messages.
Handles received Model Pub status messages from a server.

Param cli
Client that received the status message.

Param addr
Address of the sender.

Param status
Status code for the message.

Param elem_addr
Address of the element.

Param mod_id
Model ID.

Param cid
Company ID.

Param pub
Publication configuration parameters.
void (*mod_sub_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t elem_addr, uint16_t sub_addr, uint32_t mod_id)

Optional callback for Model Sub Status messages.
Handles received Model Sub Status messages from a server.
  
  **Param cli**
  Client that received the status message.
  
  **Param addr**
  Address of the sender.
  
  **Param status**
  Status Code for requesting message.
  
  **Param elem_addr**
  The unicast address of the element.
  
  **Param sub_addr**
  The sub address.
  
  **Param mod_id**
  The model ID within the element.

Note:  The buf parameter should be decoded using net_buf_simple_pull_le16 in iteration, as long as buf->len is greater than or equal to 2.

void (*mod_sub_list)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, struct net_buf_simple *buf)

Optional callback for Model Sub list messages.
Handles received Model Sub list messages from a server.

  
  **Param cli**
  Client that received the status message.
  
  **Param addr**
  Address of the sender.
  
  **Param status**
  Status code for the message.
  
  **Param elem_addr**
  Address of the element.
  
  **Param mod_id**
  Model ID.
  
  **Param cid**
  Company ID.
  
  **Param buf**
  Message buffer containing subscription addresses.

void (*node_reset_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr)

Optional callback for Node Reset Status messages.
Handles received Node Reset Status messages from a server.
  
  **Param cli**
  Client that received the status message.
  
  **Param addr**
  Address of the sender.

void (*beacon_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)

Optional callback for Beacon Status messages.
Handles received Beacon Status messages from a server.
  
  **Param cli**
  Client that received the status message.
**Param addr**  
Address of the sender.

**Param status**  
Status Code for requesting message.

```c
void (*ttl_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
```

Optional callback for Default TTL Status messages.

Handles received Default TTL Status messages from a server.

**Param cli**  
Client that received the status message.

**Param addr**  
Address of the sender.

**Param status**  
Status Code for requesting message.

```c
void (*friend_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
```

Optional callback for Friend Status messages.

Handles received Friend Status messages from a server.

**Param cli**  
Client that received the status message.

**Param addr**  
Address of the sender.

**Param status**  
Status Code for requesting message.

```c
void (*gatt_proxy_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
```

Optional callback for GATT Proxy Status messages.

Handles received GATT Proxy Status messages from a server.

**Param cli**  
Client that received the status message.

**Param addr**  
Address of the sender.

**Param status**  
Status Code for requesting message.

```c
void (*network_transmit_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
```

Optional callback for Network Transmit Status messages.

Handles received Network Transmit Status messages from a server.

**Param cli**  
Client that received the status message.

**Param addr**  
Address of the sender.

**Param status**  
Status Code for requesting message.

```c
void (*relay_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint8_t transmit)
```

Optional callback for Relay Status messages.

Handles received Relay Status messages from a server.

**Param cli**  
Client that received the status message.
**Param addr**
Address of the sender.

**Param status**
Status Code for requesting message.

**Param transmit**
The relay retransmit count and interval steps.

```c
void (*net_key_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t net_idx)
```
Optional callback for NetKey Status messages.
Handles received NetKey Status messages from a server.

**Param cli**
Client that received the status message.

**Param addr**
Address of the sender.

**Param status**
Status Code for requesting message.

**Param net_idx**
The index of the NetKey.

```c
void (*net_key_list)(struct bt_mesh_cfg_cli *cli, uint16_t addr, struct net_buf_simple *buf)
```
Optional callback for Netkey list messages.
Handles received Netkey list messages from a server.

---

**Note:** The `buf` parameter should be decoded using the `bt_mesh_key_idx_unpack_list` helper function.

```c
void (*app_key_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t net_idx, uint16_t app_idx)
```
Optional callback for AppKey Status messages.
Handles received AppKey Status messages from a server.

**Param cli**
Client that received the status message.

**Param addr**
Address of the sender.

**Param status**
Status Code for requesting message.

**Param net_idx**
The index of the NetKey.

**Param app_idx**
The index of the AppKey.

```c
void (*app_key_list)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t net_idx, struct net_buf_simple *buf)
```
Optional callback for Appkey list messages.
Handles received Appkey list messages from a server.

**Note:** The `buf` parameter should be decoded using the `bt_mesh_key_idx_unpack_list` helper function.

```c
void (*mod_app_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t elem_addr, uint16_t app_idx, uint32_t mod_id)
```

Optional callback for Model App Status messages.

Handles received Model App Status messages from a server.

- **Param cli**
  - Client that received the status message.
- **Param addr**
  - Address of the sender.
- **Param status**
  - Status code for the message.
- **Param net_idx**
  - The index of the NetKey.
- **Param buf**
  - Message buffer containing key indexes.

```c
void (*mod_app_list)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, struct net_buf_simple *buf)
```

Optional callback for Model App list messages.

Handles received Model App list messages from a server.

**Note:** The `buf` parameter should be decoded using the `bt_mesh_key_idx_unpack_list` helper function.

```c
void (*mod_app_list)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, struct net_buf_simple *buf)
```

Optional callback for Model App list messages.

Handles received Model App list messages from a server.

- **Param cli**
  - Client that received the status message.
- **Param addr**
  - Address of the sender.
- **Param status**
  - Status code for the message.
- **Param elem_addr**
  - The unicast address of the element.
- **Param app_idx**
  - The sub address.
- **Param mod_id**
  - The model ID within the element.
- **Param cid**
  - Company ID.
**Param buf**
Message buffer containing key indexes.

```c
void (*node_identity_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t net_idx, uint8_t identity)
```
Optional callback for Node Identity Status messages.
Handles received Node Identity Status messages from a server.

- **Param cli**
  Client that received the status message.

- **Param addr**
  Address of the sender.

- **Param status**
  Status Code for requesting message.

- **Param net_idx**
  The index of the NetKey.

- **Param identity**
  The node identity state.

```c
void (*lpn_timeout_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint16_t elem_addr, uint32_t timeout)
```
Optional callback for LPN PollTimeout Status messages.
Handles received LPN PollTimeout Status messages from a server.

- **Param cli**
  Client that received the status message.

- **Param addr**
  Address of the sender.

- **Param elem_addr**
  The unicast address of the LPN.

- **Param timeout**
  Current value of PollTimeout timer of the LPN.

```c
void (*krp_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t net_idx, uint8_t phase)
```
Optional callback for Key Refresh Phase status messages.
Handles received Key Refresh Phase status messages from a server.

- **Param cli**
  Client that received the status message.

- **Param addr**
  Address of the sender.

- **Param status**
  Status code for the message.

- **Param net_idx**
  The index of the NetKey.

- **Param phase**
  Phase of the KRP.

```c
void (*hb_pub_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, struct bt_mesh_cfg_cli_hb_pub *pub)
```
Optional callback for Heartbeat pub status messages.
Handles received Heartbeat pub status messages from a server.

- **Param cli**
  Client that received the status message.

- **Param addr**
  Address of the sender.
### void (*hb_sub_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, struct bt_mesh_cfg_cli_hb_sub *sub)

Optional callback for Heartbeat Sub status messages. Handles received Heartbeat Sub status messages from a server.

- **Param cli**: Client that received the status message.
- **Param addr**: Address of the sender.
- **Param status**: Status code for the message.
- **Param sub**: HB subscription configuration parameters.

```c
struct bt_mesh_cfg_cli
#include <cfg_cli.h> // Mesh Configuration Client Model Context.
```

### Public Members

```c
const struct bt_mesh_model *model
// Composition data model entry pointer.
```

```c
const struct bt_mesh_cfg_cli_cb *cb
// Optional callback for Mesh Configuration Client Status messages.
```

```c
struct bt_mesh_cfg_cli_mod_pub
#include <cfg_cli.h> // Model publication configuration parameters.
```

### Public Members

```c
uint16_t addr
// Publication destination address.
```

```c
const uint8_t *uuid
// Virtual address UUID, or NULL if this is not a virtual address.
```

```c
uint16_t app_idx
// Application index to publish with.
```

```c
bool cred_flag
// Friendship credential flag.
```

```c
uint8_t ttl
// Time To Live to publish with.
```
uint8_t period
    Encoded publish period.

See also:
    BT_MESH_PUB_PERIOD_100MS, BT_MESH_PUB_PERIOD_SEC,
    BT_MESH_PUB_PERIOD_10SEC, BT_MESH_PUB_PERIOD_10MIN

uint8_t transmit
    Encoded transmit parameters.

See also:
    BT_MESH_TRANSMIT

struct bt_mesh_cfg_cli_hb_sub
#define include <cfg_cli.h> Heartbeat subscription configuration parameters.

Public Members

uint16_t src
    Source address to receive Heartbeat messages from.

uint16_t dst
    Destination address to receive Heartbeat messages on.

uint8_t period
    Logarithmic subscription period to keep listening for.
    The decoded subscription period is (1 « (period - 1)) seconds, or 0 seconds if period
    is 0.

uint8_t count
    Logarithmic Heartbeat subscription receive count.
    The decoded Heartbeat count is (1 « (count - 1)) if count is between 1 and 0xfe, 0 if
    count is 0 and 0xffff if count is 0xff.
    Ignored in Heartbeat subscription set.

uint8_t min
    Minimum hops in received messages, ie the shortest registered path from the publish-
    ing node to the subscribing node.
    A Heartbeat received from an immediate neighbor has hop count = 1.
    Ignored in Heartbeat subscription set.

uint8_t max
    Maximum hops in received messages, ie the longest registered path from the publish-
    ing node to the subscribing node.
    A Heartbeat received from an immediate neighbor has hop count = 1.
Ignored in Heartbeat subscription set.

```c
struct bt_mesh_cfg_cli_hb_pub
#include <cfg_cli.h> Heartbeat publication configuration parameters.
```

**Public Members**

```c
tuint16_t dst
    Heartbeat destination address.
```

```c
tuint8_t count
    Logarithmic Heartbeat count.
    Decoded as (1 << (count - 1)) if count is between 1 and 0x11, 0 if count is 0, or “indefinitely” if count is 0xff.
    When used in Heartbeat publication set, this parameter denotes the number of Heartbeat messages to send.
    When returned from Heartbeat publication get, this parameter denotes the number of Heartbeat messages remaining to be sent.
```

```c
tuint8_t period
    Logarithmic Heartbeat publication transmit interval in seconds.
    Decoded as (1 << (period - 1)) if period is between 1 and 0x11. If period is 0, Heartbeat publication is disabled.
```

```c
tuint8_t ttl
    Publication message Time To Live value.
```

```c
tuint16_t feat
    Bitmap of features that trigger Heartbeat publications.
    Legal values are
    `BT_MESH_FEAT_RELAY`, `BT_MESH_FEAT_PROXY`,
    `BT_MESH_FEAT_FRIEND` and `BT_MESH_FEAT_LOW_POWER`
```

```c
tuint16_t net_idx
    Network index to publish with.
```

```c
struct bt_mesh_comp_p0
#include <cfg_cli.h> Parsed Composition data page 0 representation.
Should be pulled from the return buffer passed to `bt_mesh_cfg_cli_comp_data_get` using `bt_mesh_comp_p0_get`.
```

**Public Members**

```c
tuint16_t cid
    Company ID.
```

```c
tuint16_t pid
    Product ID.
```
uint16_t vid
   Version ID.

uint16_t crpl
   Replay protection list size.

uint16_t feat
   Supported features, see BT_MESH_FEAT_SUPPORTED.

struct bt_mesh_comp_p0_elem
   #include <cfg_cli.h> Composition data page 0 element representation.

   Public Members

   uint16_t loc
      Element location.

   size_t nsig
      The number of SIG models in this element.

   size_t nvnd
      The number of vendor models in this element.

struct bt_mesh_comp_p1_elem
   #include <cfg_cli.h> Composition data page 1 element representation.

   Public Members

   size_t nsig
      The number of SIG models in this element.

   size_t nvnd
      The number of vendor models in this element.

struct bt_mesh_comp_p1_model_item
   #include <cfg_cli.h> Composition data page 1 model item representation.

   Public Members

   bool cor_present
      Corresponding_Group_ID field indicator.

   bool format
      Determines the format of Extended Model Item.

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uint8_t ext_item_cnt
    Number of items in Extended Model Items.

uint8_t cor_id
    Buffer containing Extended Model Items.
    If cor_present is set to 1 it starts with Corresponding_Group_ID

struct bt_mesh_comp_p1_item_short
    #include <cfg_cli.h> Extended Model Item in short representation.

    Public Members

    uint8_t elem_offset
        Element address modifier.

    uint8_t mod_item_idx
        Model Index.

struct bt_mesh_comp_p1_item_long
    #include <cfg_cli.h> Extended Model Item in long representation.

    Public Members

    uint8_t elem_offset
        Element address modifier.

    uint8_t mod_item_idx
        Model Index.

struct bt_mesh_comp_p1_ext_item
    #include <cfg_cli.h> Extended Model Item.

    Public Members

    struct bt_mesh_comp_p1_item_short short_item
        Item in short representation.

    struct bt_mesh_comp_p1_item_long long_item
        Item in long representation.

struct bt_mesh_comp_p2_record
    #include <cfg_cli.h> Composition data page 2 record parsing structure.
Public Members

`uint16_t id`
Mesh profile ID.

`uint8_t x`
Major version.

`uint8_t y`
Minor version.

`uint8_t z`
Z version.

`struct bt_mesh_comp_p2_record version`
Mesh Profile Version.

`struct net_buf_simple *elem_buf`
Element offset buffer.

`struct net_buf_simple *data_buf`
Additional data buffer.

Configuration Server  The Configuration Server model is a foundation model defined by the Bluetooth Mesh specification. The Configuration Server model controls most parameters of the mesh node. It does not have an API of its own, but relies on a Configuration Client to control it.

---

**Note:** The `bt_mesh_cfg_srv` structure has been deprecated. The initial values of the Relay, Beacon, Friend, Network transmit and Relay retransmit should be set through Kconfig, and the Heartbeat feature should be controlled through the Heartbeat API.

---

The Configuration Server model is mandatory on all Bluetooth Mesh nodes, and must only be instantiated on the primary element.

API reference

`group bt_mesh_cfg_srv`
Configuration Server Model.

Defines

`BT_MESH_MODEL_CFG_SRV`
Generic Configuration Server model composition data entry.
Health Client  The Health Client model interacts with a Health Server model to read out diagnostics and control the node's attention state.

All message passing functions in the Health Client API have cli as their first parameter. This is a pointer to the client model instance to be used in this function call. The second parameter is the ctx or message context. Message context contains netkey index, appkey index and unicast address that the target node uses.

The Health Client model is optional, and may be instantiated on any element. However, if a Health Client model is instantiated on an element other than the primary, an instance must also be present on the primary element.

See Health faults for a list of specification defined fault values.

API reference

group bt_mesh_health_cli
Health Client Model.

Defines

BT_MESH_MODEL_HEALTH_CLI(cli_data)
Generic Health Client model composition data entry.

Parameters

• cli_data – Pointer to a Health Client Model instance.

Functions

int bt_mesh_health_cli_fault_get(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint16_t cid, uint8_t *test_id, uint8_t *faults, size_t *fault_count)
Get the registered fault state for the given Company ID.

This method can be used asynchronously by setting test_id and (faults or fault_count) as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the fault_status callback in bt_mesh_health_cli struct.

See also:
Health faults

Parameters

• cli – Client model to send on.
• ctx – Message context, or NULL to use the configured publish parameters.
• cid – Company ID to get the registered faults of.
• test_id – Test ID response buffer.
• faults – Fault array response buffer.
• fault_count – Fault count response buffer.
Returns
0 on success, or (negative) error code on failure.

int bt_mesh_health_cli_fault_clear(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint16_t cid, uint8_t *test_id, uint8_t *faults, size_t *fault_count)

Clear the registered faults for the given Company ID.

This method can be used asynchronously by setting test_id and (faults or fault_count) as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the fault_status callback in bt_mesh_health_cli struct.

See also:
Health faults

Parameters
• cli – Client model to send on.
• ctx – Message context, or NULL to use the configured publish parameters.
• cid – Company ID to clear the registered faults for.
• test_id – Test ID response buffer.
• faults – Fault array response buffer.
• fault_count – Fault count response buffer.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_health_cli_fault_clear_unack(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint16_t cid)

Clear the registered faults for the given Company ID (unacked).

See also:
Health faults

Parameters
• cli – Client model to send on.
• ctx – Message context, or NULL to use the configured publish parameters.
• cid – Company ID to clear the registered faults for.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_health_cli_fault_test(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint16_t cid, uint8_t test_id, uint8_t *faults, size_t *fault_count)
Invoke a self-test procedure for the given Company ID.

This method can be used asynchronously by setting faults or fault_count as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the fault_status callback in bt_mesh_health_cli struct.

**Parameters**
- cli – Client model to send on.
- ctx – Message context, or NULL to use the configured publish parameters.
- cid – Company ID to invoke the test for.
- test_id – Test ID response buffer.
- faults – Fault array response buffer.
- fault_count – Fault count response buffer.

**Returns**
- 0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_fault_test_unack(
    struct bt_mesh_health_cli *cli,
    struct bt_mesh_msg_ctx *ctx,
    uint16_t cid,
    uint8_t test_id)
```

Invoke a self-test procedure for the given Company ID (unacked).

**Parameters**
- cli – Client model to send on.
- ctx – Message context, or NULL to use the configured publish parameters.
- cid – Company ID to invoke the test for.
- test_id – Test ID response buffer.

**Returns**
- 0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_period_get(
    struct bt_mesh_health_cli *cli,
    struct bt_mesh_msg_ctx *ctx,
    uint8_t *divisor)
```

Get the target node's Health fast period divisor.

The health period divisor is used to increase the publish rate when a fault is registered. Normally, the Health server will publish with the period in the configured publish parameters. When a fault is registered, the publish period is divided by (1 << divisor). For example, if the target node's Health server is configured to publish with a period of 16 seconds, and the Health fast period divisor is 5, the Health server will publish with an interval of 500 ms when a fault is registered.

This method can be used asynchronously by setting divisor as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the period_status callback in bt_mesh_health_cli struct.

**Parameters**
- cli – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `divisor` – Health period divisor response buffer.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_period_set(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t divisor, uint8_t *updated_divisor)
```

Set the target node’s Health fast period divisor.

The health period divisor is used to increase the publish rate when a fault is registered. Normally, the Health server will publish with the period in the configured publish parameters. When a fault is registered, the publish period is divided by \((1 \times \text{divisor})\). For example, if the target node’s Health server is configured to publish with a period of 16 seconds, and the Health fast period divisor is 5, the Health server will publish with an interval of 500 ms when a fault is registered.

This method can be used asynchronously by setting `updated_divisor` as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the `period_status` callback in `bt_mesh_health_cli` struct.

**Parameters**

- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `divisor` – New Health period divisor.
- `updated_divisor` – Health period divisor response buffer.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_period_set_unack(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t divisor)
```

Set the target node’s Health fast period divisor (unacknowledged).

This is an unacknowledged version of this API.

**Parameters**

- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `divisor` – New Health period divisor.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_attention_get(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t *attention)
```

Get the current attention timer value.

This method can be used asynchronously by setting `attention` as NULL. This way the method will not wait for response and will return immediately after sending the command.
To process the response arguments of an async method, register the `attention_status` callback in `bt_mesh_health_cli` struct.

**Parameters**
- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `attention` – Attention timer response buffer, measured in seconds.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_attention_set(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t attention, uint8_t *updated_attention)
```

Set the attention timer.
This method can be used asynchronously by setting `updated_attention` as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the `attention_status` callback in `bt_mesh_health_cli` struct.

**Parameters**
- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `attention` – New attention timer time, in seconds.
- `updated_attention` – Attention timer response buffer, measured in seconds.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_attention_set_unack(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t attention)
```

Set the attention timer (unacknowledged).

**Parameters**
- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `attention` – New attention timer time, in seconds.

**Returns**
0 on success, or (negative) error code on failure.

```c
int32_t bt_mesh_health_cli_timeout_get(void)
```

Get the current transmission timeout value.

**Returns**
The configured transmission timeout in milliseconds.

```c
void bt_mesh_health_cli_timeout_set(int32_t timeout)
```

Set the transmission timeout value.

**Parameters**
• timeout – The new transmission timeout.

```c
struct bt_mesh_health_cli
#include <health_cli.h> Health Client Model Context.
```

### Public Members

```c
cconst struct bt_mesh_model *model
Composition data model entry pointer.
```

```c
struct bt_mesh_model_pub pub
Publication structure instance.
```

```c
struct net_buf_simple pub_buf
Publication buffer.
```

```c
uint8_t pub_data[BT_MESH_MODEL_BUF_LEN(BT_MESH_MODEL_OP_2(0x80, 0x32), 3)]
Publication data.
```

```c
void (*period_status)(struct bt_mesh_health_cli *cli, uint16_t addr, uint8_t divisor)
Optional callback for Health Period Status messages.
Handles received Health Period Status messages from a Health server. The divisor param represents the period divisor value.
```

- **Param cli**
  - Health client that received the status message.

- **Param addr**
  - Address of the sender.

- **Param divisor**
  - Health Period Divisor value.

```c
void (*attention_status)(struct bt_mesh_health_cli *cli, uint16_t addr, uint8_t attention)
Optional callback for Health Attention Status messages.
Handles received Health Attention Status messages from a Health server. The attention param represents the current attention value.
```

- **Param cli**
  - Health client that received the status message.

- **Param addr**
  - Address of the sender.

- **Param attention**
  - Current attention value.

```c
void (*fault_status)(struct bt_mesh_health_cli *cli, uint16_t addr, uint8_t test_id, uint16_t cid, uint8_t *faults, size_t fault_count)
Optional callback for Health Fault Status messages.
Handles received Health Fault Status messages from a Health server. The fault array represents all faults that are currently present in the server’s element.
```

6.1. Bluetooth
See also:

Health faults

Param cli
Health client that received the status message.

Param addr
Address of the sender.

Param test_id
Identifier of a most recently performed test.

Param cid
Company Identifier of the node.

Param faults
Array of faults.

Param fault_count
Number of faults in the fault array.

void (*current_status)(struct bt_mesh_health_cli *cli, uint16_t addr, uint8_t test_id, uint16_t cid, uint8_t *faults, size_t fault_count)

Optional callback for Health Current Status messages.

Handles received Health Current Status messages from a Health server. The fault array represents all faults that are currently present in the server’s element.

See also:

Health faults

Health Server
The Health Server model provides attention callbacks and node diagnostics for Health Client models. It is primarily used to report faults in the mesh node and map the mesh nodes to their physical location.

If present, the Health Server model must be instantiated on the primary element.

Faults

The Health Server model may report a list of faults that have occurred in the device’s lifetime. Typically, the faults are events or conditions that may alter the behavior of the node, like power outages or faulty peripherals. Faults are split into warnings and errors. Warnings indicate conditions that are close to the limits of what the node is designed to withstand, but not necessarily damaging to the device. Errors indicate conditions that are outside of the node’s design limits, and may have caused invalid behavior or permanent damage to the device.

Fault values 0x01 to 0x7f are reserved for the Bluetooth Mesh specification, and the full list of specification defined faults are available in Health faults. Fault values 0x80 to 0xff are vendor specific. The list of faults are always reported with a company ID to help interpreting the vendor specific faults.
**Attention state**  The attention state is used to make the device call attention to itself through some physical behavior like blinking, playing a sound or vibrating. The attention state may be used during provisioning to let the user know which device they're provisioning, as well as through the Health models at runtime.

The attention state is always assigned a timeout in the range of one to 255 seconds when enabled. The Health Server API provides two callbacks for the application to run their attention calling behavior: `bt_mesh_health_srv_cb.attn_on` is called at the beginning of the attention period, `bt_mesh_health_srv_cb.attn_off` is called at the end.

The remaining time for the attention period may be queried through `bt_mesh_health_srv.attn_timer`.

**API reference**

```
group bt_mesh_health_srv

Health Server Model.
```

**Defines**

```
BT_MESH_HEALTH_PUB_DEFINE(_name, _max_faults)

A helper to define a health publication context.

**Parameters**

- `_name` – Name given to the publication context variable.
- `_max_faults` – Maximum number of faults the element can have.
```

```
BT_MESH_MODEL_HEALTH_SRV(srv, pub)

Define a new health server model.

Note that this API needs to be repeated for each element that the application wants to have a health server model on. Each instance also needs a unique `bt_mesh_health_srv` and `bt_mesh_model_pub` context.

**Parameters**

- `srv` – Pointer to a unique struct `bt_mesh_health_srv`.
- `pub` – Pointer to a unique struct `bt_mesh_model_pub`.

**Returns**

New mesh model instance.
```

```
BT_MESH_HEALTH_TEST_INFO_METADATA_ID

Health Test Information Metadata ID.
```

```
BT_MESH_HEALTH_TEST_INFO_METADATA(tests)

Define a Health Test Info Metadata array.

**Parameters**

- `tests` – A comma separated list of tests.

**Returns**

A comma separated list of values that make Health Test Info Metadata
```
Functions

```c
int bt_mesh_health_srv_fault_update(const struct bt_mesh_elem *elem)
```

Notify the stack that the fault array state of the given element has changed. This prompts the Health server on this element to publish the current fault array if periodic publishing is disabled.

**Parameters**
- `elem` – Element to update the fault state of.

**Returns**
- 0 on success, or (negative) error code otherwise.

```c
struct bt_mesh_health_srv_cb
```

#include <health_srv.h> Callback function for the Health Server model.

**Public Members**

```c
int (*fault_get_cur)(const struct bt_mesh_model *model, uint8_t *test_id, uint16_t *company_id, uint8_t *faults, uint8_t *fault_count)
```

Callback for fetching current faults.

Fault values may either be defined by the specification, or by a vendor. Vendor specific faults should be interpreted in the context of the accompanying Company ID. Specification defined faults may be reported for any Company ID, and the same fault may be presented for multiple Company IDs.

All faults shall be associated with at least one Company ID, representing the device vendor or some other vendor whose vendor specific fault values are used.

If there are multiple Company IDs that have active faults, return only the faults associated with one of them at the time. To report faults for multiple Company IDs, interleave which Company ID is reported for each call.

**Param model**
- Health Server model instance to get faults of.

**Param test_id**
- Test ID response buffer.

**Param company_id**
- Company ID response buffer.

**Param faults**
- Array to fill with current faults.

**Param fault_count**
- The number of faults the fault array can fit. Should be updated to reflect the number of faults copied into the array.

**Return**
- 0 on success, or (negative) error code otherwise.

```c
int (*fault_get_reg)(const struct bt_mesh_model *model, uint16_t company_id, uint8_t *test_id, uint8_t *faults, uint8_t *fault_count)
```

Callback for fetching all registered faults.

Registered faults are all past and current faults since the last call to fault_clear. Only faults associated with the given Company ID should be reported.

Fault values may either be defined by the specification, or by a vendor. Vendor specific faults should be interpreted in the context of the accompanying Company
ID. Specification defined faults may be reported for any Company ID, and the same fault may be presented for multiple Company IDs.

**Param model**
Health Server model instance to get faults of.

**Param company_id**
Company ID to get faults for.

**Param test_id**
Test ID response buffer.

**Param faults**
Array to fill with registered faults.

**Param fault_count**
The number of faults the fault array can fit. Should be updated to reflect the number of faults copied into the array.

**Return**
0 on success, or (negative) error code otherwise.

```c
int (*fault_clear)(const struct bt_mesh_model *model, uint16_t company_id)
```
Clear all registered faults associated with the given Company ID.

**Param model**
Health Server model instance to clear faults of.

**Param company_id**
Company ID to clear faults for.

**Return**
0 on success, or (negative) error code otherwise.

```c
int (*fault_test)(const struct bt_mesh_model *model, uint8_t test_id, uint16_t company_id)
```
Run a self-test.

The Health server may support up to 256 self-tests for each Company ID. The behavior for all test IDs are vendor specific, and should be interpreted based on the accompanying Company ID. Test failures should result in changes to the fault array.

**Param model**
Health Server model instance to run test for.

**Param test_id**
Test ID to run.

**Param company_id**
Company ID to run test for.

**Return**
0 if the test execution was started successfully, or (negative) error code otherwise. Note that the fault array will not be reported back to the client if the test execution didn’t start.

```c
void (*attn_on)(const struct bt_mesh_model *model)
```
Start calling attention to the device.

The attention state is used to map an element address to a physical device. When this callback is called, the device should start some physical procedure meant to call attention to itself, like blinking, buzzing, vibrating or moving. If there are multiple Health server instances on the device, the attention state should also help identify the specific element the server is in.

The attention calling behavior should continue until the `attn_off` callback is called.

**Param model**
Health Server model to start the attention state of.
void (*attn_off)(const struct bt_mesh_model *model)
    Stop the attention state.
    Any physical activity started to call attention to the device should be stopped.

Param model

struct bt_mesh_health_srv
    #include <health_srv.h> Mesh Health Server Model Context.

Public Members

const struct bt_mesh_model *model
    Composition data model entry pointer.

cnst struct bt_mesh_health_srv_cb *cb
    Optional callback struct.

struct k_work_delayable attn_timer
    Attention Timer state.

Health faults  Fault values defined by the Bluetooth Mesh specification.

group bt_mesh_health_faults
    List of specification defined Health fault values.

Defines

BT_MESH_HEALTH_FAULT_NO_FAULT
    No fault has occurred.

BT_MESH_HEALTH_FAULT_BATTERY_LOW_WARNING

BT_MESH_HEALTH_FAULT_BATTERY_LOW_ERROR

BT_MESH_HEALTH_FAULT_SUPPLY_VOLTAGE_TOO_LOW_WARNING

BT_MESH_HEALTH_FAULT_SUPPLY_VOLTAGE_TOO_LOW_ERROR

BT_MESH_HEALTH_FAULT_SUPPLY_VOLTAGE_TOO_HIGH_WARNING

BT_MESH_HEALTH_FAULT_SUPPLY_VOLTAGE_TOO_HIGH_ERROR

BT_MESH_HEALTH_FAULT_POWER_SUPPLY_INTERRUPTED_WARNING

BT_MESH_HEALTH_FAULT_POWER_SUPPLY_INTERRUPTED_ERROR
BT_MESH_HEALTH_FAULT_NO_LOAD_WARNING
BT_MESH_HEALTH_FAULT_NO_LOAD_ERROR
BT_MESH_HEALTH_FAULT_OVERLOAD_WARNING
BT_MESH_HEALTH_FAULT_OVERLOAD_ERROR
BT_MESH_HEALTH_FAULT_OVERHEAT_WARNING
BT_MESH_HEALTH_FAULT_OVERHEAT_ERROR
BT_MESH_HEALTH_FAULT_CONDENSATION_WARNING
BT_MESH_HEALTH_FAULT_CONDENSATION_ERROR
BT_MESH_HEALTH_FAULT_VIBRATION_WARNING
BT_MESH_HEALTH_FAULT_VIBRATION_ERROR
BT_MESH_HEALTH_FAULT_CONFIGURATION_WARNING
BT_MESH_HEALTH_FAULT_CONFIGURATION_ERROR
BT_MESH_HEALTH_FAULT_ELEMENT_NOT_CALIBRATED_WARNING
BT_MESH_HEALTH_FAULT_ELEMENT_NOT_CALIBRATED_ERROR
BT_MESH_HEALTH_FAULT_MEMORY_WARNING
BT_MESH_HEALTH_FAULT_MEMORY_ERROR
BT_MESH_HEALTH_FAULT_SELF_TEST_WARNING
BT_MESH_HEALTH_FAULT_SELF_TEST_ERROR
BT_MESH_HEALTH_FAULT_INPUT_TOO_LOW_WARNING
BT_MESH_HEALTH_FAULT_INPUT_TOO_LOW_ERROR
BT_MESH_HEALTH_FAULT_INPUT_TOO_HIGH_WARNING
BT_MESH_HEALTH_FAULT_INPUT_TOO_HIGH_ERROR
BT_MESH_HEALTH_FAULT_INPUT_NO_CHANGE_WARNING
BT_MESH_HEALTH_FAULT_INPUT_NO_CHANGE_ERROR
BT_MESH_HEALTH_FAULT_ACTUATOR_BLOCKED_WARNING
BT_MESH_HEALTH_FAULT_ACTUATOR_BLOCKED_ERROR
BT_MESH_HEALTH_FAULT_HOUSING_OPENED.WARNING
BT_MESH_HEALTH_FAULT_HOUSING_OPENED_ERROR
BT_MESH_HEALTH_FAULT_TAMPER_WARNING
BT_MESH_HEALTH_FAULT_TAMPER_ERROR
BT_MESH_HEALTH_FAULT_DEVICE_MOVED_WARNING
BT_MESH_HEALTH_FAULT_DEVICE_MOVED_ERROR
BT_MESH_HEALTH_FAULT_DEVICE_DROPPED_WARNING
BT_MESH_HEALTH_FAULT_DEVICE_DROPPED_ERROR
BT_MESH_HEALTH_FAULT_OVERFLOW_WARNING
BT_MESH_HEALTH_FAULT_OVERFLOW_ERROR
BT_MESH_HEALTH_FAULT_EMPTY_WARNING
BT_MESH_HEALTH_FAULT_EMPTY_ERROR
BT_MESH_HEALTH_FAULT_INTERNAL_BUS.WARNING
BT_MESH_HEALTH_FAULT_INTERNAL_BUS_ERROR
BT_MESH_HEALTH_FAULT_MECHANISM_JAMMED_WARNING
BT_MESH_HEALTH_FAULT_MECHANISM_JAMMED_ERROR

BT_MESH_HEALTH_FAULT_VENDOR_SPECIFIC_START
Start of the vendor specific fault values.
All values below this are reserved for the Bluetooth Specification.
**Large Composition Data Client** The Large Composition Data Client model is a foundation model defined by the Bluetooth Mesh specification. The model is optional, and is enabled through the `CONFIG_BT_MESH_LARGE_COMP_DATA_CLI` option.

The Large Composition Data Client model was introduced in the Bluetooth Mesh Protocol Specification version 1.1, and supports the functionality of reading pages of Composition Data that do not fit in a Config Composition Data Status message and reading the metadata of the model instances on a node that supports the *Large Composition Data Server* model.

The Large Composition Data Client model communicates with a Large Composition Data Server model using the device key of the node containing the target Large Composition Data Server model instance.

If present, the Large Composition Data Client model must only be instantiated on the primary element.

**API reference**

*group bt_mesh_large_comp_data_cli*

**Defines**

`BT_MESH_MODEL_LARGE_COMP_DATA_CLI(cli_data)`

Large Composition Data Client model Composition Data entry.

**Parameters**

- `cli_data` – Pointer to a Large Composition Data Client model instance.

**Functions**

`int bt_mesh_large_comp_data_get(uint16_t net_idx, uint16_t addr, uint8_t page, size_t offset, struct bt_mesh_large_comp_data_rsp *rsp)`

Send Large Composition Data Get message.

This API is used to read a portion of a Composition Data Page.

This API can be used asynchronously by setting `rsp` as NULL. This way, the method will not wait for a response and will return immediately after sending the command.

When `rsp` is set, the user is responsible for providing a buffer for the Composition Data in `bt_mesh_large_comp_data_rsp::data`. If a buffer is not provided, the metadata won’t be copied.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node element address.
- `page` – Composition Data Page to read.
- `offset` – Offset within the Composition Data Page.
- `rsp` – Pointer to a struct storing the received response from the server, or NULL to not wait for a response.

**Returns**

0 on success, or (negative) error code on failure.
int bt_mesh_models_metadata_get(uint16_t net_idx, uint16_t addr, uint8_t page, size_t offset, struct bt_mesh_large_comp_data_rsp *rsp)

Send Models Metadata Get message.

This API is used to read a portion of a Models Metadata Page.

This API can be used asynchronously by setting \texttt{rsp} as NULL. This way, the method will not wait for a response and will return immediately after sending the command.

When \texttt{rsp} is set, a user is responsible for providing a buffer for metadata in \texttt{bt_mesh_large_comp_data_rsp::data}. If a buffer is not provided, the metadata won't be copied.

\textbf{Parameters}

- \texttt{net_idx} – Network index to encrypt with.
- \texttt{addr} – Target node element address.
- \texttt{page} – Models Metadata Page to read.
- \texttt{offset} – Offset within the Models Metadata Page.
- \texttt{rsp} – Pointer to a struct storing the received response from the server, or NULL to not wait for a response.

\textbf{Returns}

0 on success, or (negative) error code on failure.

\textbf{struct bt_mesh_large_comp_data_rsp}

\texttt{#include <large_comp_data_cli.h>} Large Composition Data response.

\textbf{Public Members}

- \texttt{uint8_t page}
  
  Page number.

- \texttt{uint16_t offset}
  
  Offset within the page.

- \texttt{uint16_t total_size}
  
  Total size of the page.

- \texttt{struct net_buf_simple *data}
  
  Pointer to allocated buffer for storing received data.

\textbf{struct bt_mesh_large_comp_data_cli_cb}

\texttt{#include <large_comp_data_cli.h>} Large Composition Data Status messages callbacks.

\textbf{Public Members}

- \texttt{void (*large_comp_data_status)(struct bt_mesh_large_comp_data_cli *cli, uint16_t addr, struct bt_mesh_large_comp_data_rsp *rsp)}

  Optional callback for Large Composition Data Status message.

  Handles received Large Composition Data Status messages from a Large Composition Data Server.
If the content of `rsp` is needed after exiting this callback, a user should deep copy it.

**Param cli**
Large Composition Data Client context.

**Param addr**
Address of the sender.

**Param rsp**
Response received from the server.

```c
void (*models_metadata_status)(struct bt_mesh_large_comp_data_cli *cli, uint16_t addr, struct bt_mesh_large_comp_data_rsp *rsp)
```

Optional callback for Models Metadata Status message.

Handles received Models Metadata Status messages from a Large Composition Data Server.

If the content of `rsp` is needed after exiting this callback, a user should deep copy it.

**Param cli**
Large Composition Data Client context.

**Param addr**
Address of the sender.

**Param rsp**
Response received from the server.

```c
struct bt_mesh_large_comp_data_cli
#include <large_comp_data_cli.h> Large Composition Data Client model context.
```

**Public Members**

```c
const struct bt_mesh_model *model
Model entry pointer.
```

```c
struct bt_mesh_msg_ack_ctx ack_ctx
Internal parameters for tracking message responses.
```

```c
const struct bt_mesh_large_comp_data_cli_cb *cb
Optional callback for Large Composition Data Status messages.
```

**Large Composition Data Server**

The Large Composition Data Server model is a foundation model defined by the Bluetooth Mesh specification. The model is optional, and is enabled through the `CONFIG_BT_MESH_LARGE_COMP_DATA_SRV` option.

The Large Composition Data Server model was introduced in the Bluetooth Mesh Protocol Specification version 1.1, and is used to support the functionality of exposing pages of Composition Data that do not fit in a Config Composition Data Status message and to expose metadata of the model instances.

The Large Composition Data Server does not have an API of its own and relies on a **Large Composition Data Client** to control it. The model only accepts messages encrypted with the node's device key.

If present, the Large Composition Data Server model must only be instantiated on the primary element.
Models metadata  The Large Composition Data Server model allows each model to have a list of model's specific metadata that can be read by the Large Composition Data Client model. The metadata list can be associated with the `bt_mesh_model` through the `bt_mesh_model.metadata` field. The metadata list consists of one or more entries defined by the `bt_mesh_models_metadata_entry` structure. Each entry contains the length and ID of the metadata, and a pointer to the raw data. Entries can be created using the `BT_MESH_MODELS_METADATA_ENTRY` macro. The `BT_MESH_MODELS_METADATA_END` macro marks the end of the metadata list and must always be present. If the model has no metadata, the helper macro `BT_MESH_MODELS_METADATA_NONE` can be used instead.

API reference

`group bt_mesh_large_comp_data_srv`

`BT_MESH_MODEL_LARGE_COMP_DATA_SRV`
Large Composition Data Server model composition data entry.

On-Demand Private Proxy Client  The On-Demand Private Proxy Client model is a foundation model defined by the Bluetooth Mesh specification. The model is optional, and is enabled with the `CONFIG_BT_MESH_OD_PRIV_PROXY_CLI` option.

The On-Demand Private Proxy Client model was introduced in the Bluetooth Mesh Protocol Specification version 1.1, and is used to set and retrieve the On-Demand Private GATT Proxy state. The state defines how long a node will advertise Mesh Proxy Service with Private Network Identity type after it receives a Solicitation PDU.

The On-Demand Private Proxy Client model communicates with an On-Demand Private Proxy Server model using the device key of the node containing the target On-Demand Private Proxy Server model instance.

If present, the On-Demand Private Proxy Client model must only be instantiated on the primary element.

Configurations  The On-Demand Private Proxy Client model behavior can be configured with the transmission timeout option `CONFIG_BT_MESH_OD_PRIV_PROXY_CLI_TIMEOUT`. The `CONFIG_BT_MESH_OD_PRIV_PROXY_CLI_TIMEOUT` controls how long the Client waits for a state response message to arrive in milliseconds. This value can be changed at runtime using `bt_mesh_od_priv_proxy_cli_timeout_set()`.

API reference

`group bt_mesh_od_priv_proxy_cli`

`BT_MESH_MODEL_OD_PRIV_PROXY_CLI(cli_data)`
On-Demand Private Proxy Client model composition data entry.
Functions

int bt_mesh_od_priv_proxy_cli_get(uint16_t net_idx, uint16_t addr, uint8_t *val_rsp)
Get the target's On-Demand Private GATT Proxy state.

This method can be used asynchronously by setting val_rsp as NULL. This way the
method will not wait for response and will return immediately after sending the com-
mand.

To process the response arguments of an async method, register the od_status callback
in `bt_mesh_od_priv_proxy_cli` struct.

Parameters
  • net_idx – Network index to encrypt with.
  • addr – Target node address.
  • val_rsp – Response buffer for On-Demand Private GATT Proxy value.

Returns
  0 on success, or (negative) error code otherwise.

int bt_mesh_od_priv_proxy_cli_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t*
val_rsp)
Set the target's On-Demand Private GATT Proxy state.

This method can be used asynchronously by setting val_rsp as NULL. This way the
method will not wait for response and will return immediately after sending the com-
mand.

To process the response arguments of an async method, register the od_status callback
in `bt_mesh_od_priv_proxy_cli` struct.

Parameters
  • net_idx – Network index to encrypt with.
  • addr – Target node address.
  • val – On-Demand Private GATT Proxy state to be set
  • val_rsp – Response buffer for On-Demand Private GATT Proxy value.

Returns
  0 on success, or (negative) error code otherwise.

void bt_mesh_od_priv_proxy_cli_timeout_set(int32_t timeout)
Set the transmission timeout value.

Parameters
  • timeout – The new transmission timeout in milliseconds.

struct bt_mesh_od_priv_proxy_cli
#include <od_priv_proxy_cli.h> On-Demand Private Proxy Client Model Context.

Public Members

const struct bt_mesh_model *model
  Solicitation PDU RPL model entry pointer.
void (*od_status)(struct bt_mesh_od_priv_proxy_cli *cli, uint16_t addr, uint8_t state)
Optional callback for On-Demand Private Proxy Status messages.
Handles received On-Demand Private Proxy Status messages from a On-Demand Private Proxy server. The state param represents state of On-Demand Private Proxy server.

**Param cli**
On-Demand Private Proxy client that received the status message.

**Param addr**
Address of the sender.

**Param state**
State value.

### On-Demand Private Proxy Server
The On-Demand Private Proxy Server model is a foundation model defined by the Bluetooth Mesh specification. It is enabled with the `CONFIG_BT_MESH_OD_PRIV_PROXY_SRV` option.

The On-Demand Private Proxy Server model was introduced in the Bluetooth Mesh Protocol Specification version 1.1, and supports the configuration of advertising with Private Network Identity type of a node that is a recipient of Solicitation PDUs by managing its On-Demand Private GATT Proxy state.

When enabled, the **Solicitation PDU RPL Configuration Server** is also enabled. The On-Demand Private Proxy Server is dependent on the **Private Beacon Server** to be present on the node.

The On-Demand Private Proxy Server does not have an API of its own, and relies on a **On-Demand Private Proxy Client** to control it. The On-Demand Private Proxy Server model only accepts messages encrypted with the node's device key.

If present, the On-Demand Private Proxy Server model must only be instantiated on the primary element.

**API reference**

```
group bt_mesh_od_priv_proxy_srv
```

**Defines**

```
BT_MESH_MODEL_OD_PRIV_PROXY_SRV
On-Demand Private Proxy Server model composition data entry.
```

### Opcodes Aggregator Client
The Opcodes Aggregator Client model is a foundation model defined by the Bluetooth Mesh specification. It is an optional model, enabled with the `CONFIG_BT_MESH_OP_AGG_CLI` option.

The Opcodes Aggregator Client model is introduced in the Bluetooth Mesh Protocol Specification version 1.1, and is used to support the functionality of dispatching a sequence of access layer messages to nodes supporting the **Opcodes Aggregator Server** model.

The Opcodes Aggregator Client model communicates with an Opcodes Aggregator Server model using the device key of the target node or the application keys configured by the Configuration Client.

If present, the Opcodes Aggregator Client model must only be instantiated on the primary element.
The Opcodes Aggregator Client model is implicitly bound to the device key on initialization. It should be bound to the same application keys as the client models that are used to produce the sequence of messages.

To be able to aggregate a message from a client model, it should support an asynchronous API, for example through callbacks.

**API reference**

*group bt_mesh_op_agg_cli*

**Defines**

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<td>Opcodes Aggregator Client model composition data entry.</td>
</tr>
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</table>

**Functions**

```c
int bt_mesh_op_agg_cli_seq_start(uint16_t net_idx, uint16_t app_idx, uint16_t dst, uint16_t elem_addr)
```

Configure Opcodes Aggregator context.

**Parameters**

- `net_idx` – NetKey index to encrypt with.
- `app_idx` – AppKey index to encrypt with.
- `dst` – Target Opcodes Aggregator Server address.
- `elem_addr` – Target node element address for the sequence message.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_op_agg_cli_seq_send(void)
```

Opcodes Aggregator message send.

Uses previously configured context and sends aggregated message to target node.

**Returns**

0 on success, or (negative) error code on failure.

```c
void bt_mesh_op_agg_cli_seq_abort(void)
```

Abort Opcodes Aggregator context.

```c
bool bt_mesh_op_agg_cli_seq_is_started(void)
```

Check if Opcodes Aggregator Sequence context is started.

**Returns**

true if it is started, otherwise false.

```c
size_t bt_mesh_op_agg_cli_seq_tailroom(void)
```

Get Opcodes Aggregator context tailroom.

**Returns**

Remaning tailroom of Opcodes Aggregator SDU.
int32_t bt_mesh_op_agg_cli_timeout_get(void)
Get the current transmission timeout value.

Returns
The configured transmission timeout in milliseconds.

void bt_mesh_op_agg_cli_timeout_set(int32_t timeout)
Set the transmission timeout value.

Parameters

- timeout – The new transmission timeout.

Opcodes Aggregator Server   The Opcodes Aggregator Server model is a foundation model defined by the Bluetooth mesh specification. It is an optional model, enabled with the CONFIG_BT_MESH_OP_AGG_SRV option.

The Opcodes Aggregator Server model is introduced in the Bluetooth Mesh Protocol Specification version 1.1, and is used to support the functionality of processing a sequence of access layer messages.

The Opcodes Aggregator Server model accepts messages encrypted with the node's device key or the application keys.

If present, the Opcodes Aggregator Server model must only be instantiated on the primary element.

The targeted server models should be bound to the same application key that is used to encrypt the sequence of access layer messages sent to the Opcodes Aggregator Server.

The Opcodes Aggregator Server handles aggregated messages and dispatches them to the respective models and their message handlers. Current implementation assumes that responses are sent from the same execution context as the received message and doesn't allow to send a postponed response, for example from a work queue.

API reference

*group bt_mesh_op_agg_srv*

Defines

BT_MESH_MODEL_OP_AGG_SRV
Opcodes Aggregator Server model composition data entry.

**Note:** The Opcodes Aggregator Server handles aggregated messages and dispatches them to the respective models and their message handlers. Current implementation assumes that responses are sent from the same execution context as the received message and doesn't allow to send a postponed response, e.g. from workqueue.

Private Beacon Client   The Private Beacon Client model is a foundation model defined by the Bluetooth mesh specification. It is enabled with the CONFIG_BT_MESH_PRIV_BEACON_CLI option.

The Private Beacon Client model is introduced in the Bluetooth Mesh Protocol Specification version 1.1, and provides functionality for configuring the Private Beacon Server models.
The Private Beacons feature adds privacy to the different Bluetooth Mesh beacons by periodically randomizing the beacon input data. This protects the mesh node from being tracked by devices outside the mesh network, and hides the network’s IV index, IV update and the Key Refresh state.

The Private Beacon Client model communicates with a Private Beacon Server model using the device key of the target node. The Private Beacon Client model may communicate with servers on other nodes or self-configure through the local Private Beacon Server model.

All configuration functions in the Private Beacon Client API have `net_idx` and `addr` as their first parameters. These should be set to the network index and the primary unicast address the target node was provisioned with.

If present, the Private Beacon Client model must only be instantiated on the primary element.

**API reference**

*group bt_mesh_priv_beacon_cli*

**Defines**

`BT_MESH_MODEL_PRIV_BEACON_CLI(cli_data)`

Private Beacon Client model composition data entry.

**Parameters**

- `cli_data` – Pointer to a Bluetooth Mesh Private Beacon Client instance.

**Functions**

```c
int bt_mesh_priv_beacon_cli_set(uint16_t net_idx, uint16_t addr, struct bt_mesh_priv_beacon *val, struct bt_mesh_priv_beacon *rsp)
```

Set the target's Private Beacon state.

This method can be used asynchronously by setting `rsp` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `val` – New Private Beacon value.
- `rsp` – If set, returns response status on success.

**Returns**

0 on success, or (negative) error code otherwise.

```c
int bt_mesh_priv_beacon_cli_get(uint16_t net_idx, uint16_t addr, struct bt_mesh_priv_beacon *val)
```

Get the target's Private Beacon state.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `val` – Response buffer for Private Beacon value.
Returns
  0 on success, or (negative) error code otherwise.

int bt_mesh_priv_beacon_cli_gatt_proxy_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *rsp)

Set the target's Private GATT Proxy state.
This method can be used asynchronously by setting \texttt{rsp} as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
  • \texttt{net_idx} – Network index to encrypt with.
  • \texttt{addr} – Target node address.
  • \texttt{val} – New Private GATT Proxy value.
  • \texttt{rsp} – If set, returns response status on success.

Returns
  0 on success, or (negative) error code otherwise.

int bt_mesh_priv_beacon_cli_gatt_proxy_get(uint16_t net_idx, uint16_t addr, uint8_t *val)

Get the target's Private GATT Proxy state.

Parameters
  • \texttt{net_idx} – Network index to encrypt with.
  • \texttt{addr} – Target node address.
  • \texttt{val} – Response buffer for Private GATT Proxy value.

Returns
  0 on success, or (negative) error code otherwise.

int bt_mesh_priv_beacon_cli_node_id_set(uint16_t net_idx, uint16_t addr, struct bt_mesh_priv_node_id *val, struct bt_mesh_priv_node_id *rsp)

Set the target's Private Node Identity state.
This method can be used asynchronously by setting \texttt{rsp} as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
  • \texttt{net_idx} – Network index to encrypt with.
  • \texttt{addr} – Target node address.
  • \texttt{val} – New Private Node Identity value.
  • \texttt{rsp} – If set, returns response status on success.

Returns
  0 on success, or (negative) error code otherwise.

int bt_mesh_priv_beacon_cli_node_id_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, struct bt_mesh_priv_node_id *val)

Get the target's Private Node Identity state.

Parameters
  • \texttt{net_idx} – Network index to encrypt with.
  • \texttt{addr} – Target node address.
• key_net_idx – Network index to get the Private Node Identity state of.
• val – Response buffer for Private Node Identity value.

**Returns**
0 on success, or (negative) error code otherwise.

```c
struct bt_mesh_priv_beacon
#include <priv_beacon_cli.h> Private Beacon.

**Public Members**

uint8_t enabled
Private beacon is enabled.

uint8_t rand_interval
Random refresh interval (in 10 second steps), or 0 to keep current value.
```

```c
struct bt_mesh_priv_node_id
#include <priv_beacon_cli.h> Private Node Identity.

**Public Members**

uint16_t net_idx
Index of the NetKey.

uint8_t state
Private Node Identity state.

uint8_t status
Response status code.
```

```c
struct bt_mesh_priv_beacon_cli_cb
#include <priv_beacon_cli.h> Private Beacon Client Status messages callbacks.

**Public Members**

void (*priv_beacon_status)(struct bt_mesh_priv_beacon_cli *cli, uint16_t addr, struct bt_mesh_priv_beacon *priv_beacon)
Optional callback for Private Beacon Status message.
Handles received Private Beacon Status messages from a Private Beacon server.

**Param cli**
Private Beacon client context.

**Param addr**
Address of the sender.

**Param priv_beacon**
Mesh Private Beacon state received from the server.
```
void (*priv_gatt_proxy_status)(struct bt_mesh_priv_beacon_cli *cli, uint16_t addr, uint8_t gatt_proxy)
Optional callback for Private GATT Proxy Status message.
Handles received Private GATT Proxy Status messages from a Private Beacon server.
  \textbf{Param cli}
  Private Beacon client context.
  \textbf{Param addr}
  Address of the sender.
  \textbf{Param gatt_proxy}
  Private GATT Proxy state received from the server.

void (*priv_node_id_status)(struct bt_mesh_priv_beacon_cli *cli, uint16_t addr, struct bt_mesh_priv_node_id *priv_node_id)
Optional callback for Private Node Identity Status message.
Handles received Private Node Identity Status messages from a Private Beacon server.
  \textbf{Param cli}
  Private Beacon client context.
  \textbf{Param addr}
  Address of the sender.
  \textbf{Param priv_node_id}
  Private Node Identity state received from the server.

\begin{verbatim}
struct bt_mesh_priv_beacon_cli
#define priv_beacon_cli.h
Mesh Private Beacon Client model.
\end{verbatim}

\textbf{Public Members}

const struct bt_mesh_priv_beacon_cli_cb *\textbf{cb}
Optional callback for Private Beacon Client Status messages.

\textbf{Private Beacon Server} \hspace{1em} The Private Beacon Server model is a foundation model defined by the Bluetooth mesh specification. It is enabled with \texttt{CONFIG_BT_MESH_PRIV_BEACON_SRV} option.
The Private Beacon Server model is introduced in the Bluetooth Mesh Protocol Specification version 1.1, and controls the mesh node's Private Beacon state, Private GATT Proxy state and Private Node Identity state.
The Private Beacons feature adds privacy to the different Bluetooth Mesh beacons by periodically randomizing the beacon input data. This protects the mesh node from being tracked by devices outside the mesh network, and hides the network's IV index, IV update and the Key Refresh state. The Private Beacon Server must be instantiated for the device to support sending of the private beacons, but the node will process received private beacons without it.
The Private Beacon Server does not have an API of its own, but relies on a \textit{Private Beacon Client} to control it. The Private Beacon Server model only accepts messages encrypted with the node's device key.
The application can configure the initial parameters of the Private Beacon Server model through the \texttt{bt_mesh_priv_beacon_srv} instance passed to \texttt{BT_MESH_MODEL_PRIV_BEACON_SRV}. Note that if the mesh node stored changes to this configuration in the settings subsystem, the initial values may be overwritten upon loading.
If present, the Private Beacon Server model must only be instantiated on the primary element.
API reference

*group* bt_mesh_priv_beacon_srv

**Defines**

```
BT_MESH_MODEL_PRIV_BEACON_SRV
    Private Beacon Server model composition data entry.
```

**Remote Provisioning Client**  
The Remote Provisioning Client model is a foundation model defined by the Bluetooth mesh specification. It is enabled with the `CONFIG_BT_MESH_RPR_CLI` option.

The Remote Provisioning Client model is introduced in the Bluetooth Mesh Protocol Specification version 1.1. This model provides functionality to remotely provision devices into a mesh network, and perform Node Provisioning Protocol Interface procedures by interacting with mesh nodes that support the Remote Provisioning Server model.

The Remote Provisioning Client model communicates with a Remote Provisioning Server model using the device key of the node containing the target Remote Provisioning Server model instance.

If present, the Remote Provisioning Client model must be instantiated on the primary element.

**Scanning**  
The scanning procedure is used to scan for unprovisioned devices located nearby the Remote Provisioning Server. The Remote Provisioning Client starts a scan procedure by using the `bt_mesh_rpr_scan_start()` call:

```c
static void rpr_scan_report(struct bt_mesh_rpr_cli *cli,
    const struct bt_mesh_rpr_node *srv,
    struct bt_mesh_rpr_unprov *unprov,
    struct net_buf_simple *adv_data)
{
}

struct bt_mesh_rpr_cli rpr_cli = {
    .scan_report = rpr_scan_report,
};

const struct bt_mesh_rpr_node srv = {
    .addr = 0x0004,
    .net_idx = 0,
    .ttl = BT_MESH_TTL_DEFAULT,
};

struct bt_mesh_rpr_scan_status status;
uint8_t *uuid = NULL;
uint8_t timeout = 10;
uint8_t max_devs = 3;

bt_mesh_rpr_scan_start(&rpr_cli, &srv, uuid, timeout, max_devs, &status);
```

The above example shows pseudo code for starting a scan procedure on the target Remote Provisioning Server node. This procedure will start a ten-second, multiple-device scanning where the generated scan report will contain a maximum of three unprovisioned devices. If the UUID argument was specified, the same procedure would only scan for the device with the corresponding UUID. After the procedure completes, the server sends the scan report that will be handled in the client's `bt_mesh_rpr_cli.scan_report` callback.
Additionally, the Remote Provisioning Client model also supports extended scanning with the `bt_mesh_rpr_scan_start_ext()` call. Extended scanning supplements regular scanning by allowing the Remote Provisioning Server to report additional data for a specific device. The Remote Provisioning Server will use active scanning to request a scan response from the unprovisioned device if it is supported by the unprovisioned device.

**Provisioning** The Remote Provisioning Client starts a provisioning procedure by using the `bt_mesh_provision_remote()` call:

```c
struct bt_mesh_rpr_cli rpr_cli;
const struct bt_mesh_rpr_node srv = {
    .addr = 0x0004,
    .net_idx = 0,
    .ttl = BT_MESH_TTL_DEFAULT,
};
uint8_t uuid[16] = { 0xaa };
uint16_t addr = 0x0006;
uint16_t net_idx = 0;
bt_mesh_provision_remote(&rpr_cli, &srv, uuid, net_idx, addr);
```

The above example shows pseudo code for remotely provisioning a device through a Remote Provisioning Server node. This procedure will attempt to provision the device with the corresponding UUID, and assign the address 0x0006 to its primary element using the network key located at index zero.

**Note:** During the remote provisioning, the same `bt_mesh_prov` callbacks are triggered as for ordinary provisioning. See section **Provisioning** for further details.

**Re-provisioning** In addition to scanning and provisioning functionality, the Remote Provisioning Client also provides means to reconfigure node addresses, device keys and Composition Data on devices that support the Remote Provisioning Server model. This is provided through the Node Provisioning Protocol Interface (NPPI) which supports the following three procedures:

- **Device Key Refresh procedure**: Used to change the device key of the Target node without a need to reconfigure the node.
- **Node Address Refresh procedure**: Used to change the node's device key and unicast address.
- **Node Composition Refresh procedure**: Used to change the device key of the node, and to add or delete models or features of the node.

The three NPPI procedures can be initiated with the `bt_mesh_reprovision_remote()` call:

```c
struct bt_mesh_rpr_cli rpr_cli;
struct bt_mesh_rpr_node srv = {
    .addr = 0x0006,
    .net_idx = 0,
    .ttl = BT_MESH_TTL_DEFAULT,
};
bool composition_changed = false;
uint16_t new_addr = 0x0009;
btc_mesh_reprovision_remote(&rpr_cli, &srv, new_addr, composition_changed);
```
The above example shows pseudo code for triggering a Node Address Refresh procedure on the Target node. The specific procedure is not chosen directly, but rather through the other parameters that are inputted. In the example we can see that the current unicast address of the Target is 0x0006, while the new address is set to 0x0009. If the two addresses were the same, and the composition_changed flag was set to true, this code would instead trigger a Node Composition Refresh procedure. If the two addresses were the same, and the composition_changed flag was set to false, this code would trigger a Device Key Refresh procedure.

**API reference**

*group bt_mesh_rpr_cli*

**Defines**

**BT_MESH_RPR_SCAN_MAX_DEVS_ANY**

Special value for the `max_devs` parameter of `bt_mesh_rpr_scan_start`. Tells the Remote Provisioning Server not to put restrictions on the max number of devices reported to the Client.

**BT_MESH_MODEL_RPR_CLI(_cli)**

Remote Provisioning Client model composition data entry.

**Parameters**

- `_cli` – Pointer to a *Remote Provisioning Client model* instance.

**Functions**

**int bt_mesh_rpr_scan_caps_get(struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv, struct bt_mesh_rpr_caps *caps)**

Get scanning capabilities of Remote Provisioning Server.

**Parameters**

- `cli` – Remote Provisioning Client.
- `caps` – Capabilities response buffer.

**Returns**

0 on success, or (negative) error code otherwise.

**int bt_mesh_rpr_scan_get(struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv, struct bt_mesh_rpr_scan_status *status)**

Get current scanning state of Remote Provisioning Server.

**Parameters**

- `cli` – Remote Provisioning Client.
- `status` – Scan status response buffer.

**Returns**

0 on success, or (negative) error code otherwise.

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int bt_mesh_rpr_scan_start(const struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv, const uint8_t uuid[16], uint8_t timeout, uint8_t max_devs, struct bt_mesh_rpr_scan_status *status)

Start scanning for unprovisioned devices.

Tells the Remote Provisioning Server to start scanning for unprovisioned devices. The Server will report back the results through the bt_mesh_rpr_cli::scan_report callback.

Use the uuid parameter to scan for a specific device, or leave it as NULL to report all unprovisioned devices.

The Server will ignore duplicates, and report up to max_devs number of devices. Requesting a max_devs number that’s higher than the Server’s capability will result in an error.

**Parameters**

- **cli** – Remote Provisioning Client.
- **srv** – Remote Provisioning Server.
- **uuid** – Device UUID to scan for, or NULL to report all devices.
- **timeout** – Scan timeout in seconds. Must be at least 1 second.
- **max_devs** – Max number of devices to report, or 0 to report as many as possible.
- **status** – Scan status response buffer.

**Returns**

0 on success, or (negative) error code otherwise.

int bt_mesh_rpr_scan_start_ext(const struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv, const uint8_t uuid[16], uint8_t timeout, const uint8_t *ad_types, size_t ad_count)

Start extended scanning for unprovisioned devices.

Extended scanning supplements regular unprovisioned scanning, by allowing the Server to report additional data for a specific device. The Remote Provisioning Server will use active scanning to request a scan response from the unprovisioned device, if supported. If no UUID is provided, the Server will report a scan on its own OOB information and advertising data.

Use the ad_types array to specify which AD types to include in the scan report. Some AD types invoke special behavior:

- **BT_DATA_NAME_COMPLETE** Will report both the complete and the shortened name.
- **BT_DATA_URI** If the unprovisioned beacon contains a URI hash, the Server will extend the scanning to include packets other than the scan response, to look for URIs matching the URI hash. Only matching URIs will be reported.

The following AD types should not be used:

- **BT_DATA_NAME_SHORTENED**
- **BT_DATA_UUID16_SOME**
- **BT_DATA_UUID32_SOME**
- **BT_DATA_UUID128_SOME**

Additionally, each AD type should only occur once.

**Parameters**

- **cli** – Remote Provisioning Client.
• **srv** – Remote Provisioning Server.
• **uuid** – Device UUID to start extended scanning for, or NULL to scan the remote server.
• **timeout** – Scan timeout in seconds. Valid values from \texttt{BT\_MESH\_RPR\_EXT\_SCAN\_TIME\_MIN} to \texttt{BT\_MESH\_RPR\_EXT\_SCAN\_TIME\_MAX}. Ignored if UUID is NULL.
• **ad_types** – List of AD types to include in the scan report. Must contain 1 to \texttt{CONFIG\_BT\_MESH\_RPR\_AD\_TYPES\_MAX} entries.
• **ad_count** – Number of AD types in \texttt{ad_types}.

Returns
0 on success, or (negative) error code otherwise.

```c
int bt_mesh_rpr_scan_stop(struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv, struct bt_mesh_rpr_scan_status *status)
```

Stop any ongoing scanning on the Remote Provisioning Server.

Parameters
• **cli** – Remote Provisioning Client.
• **srv** – Remote Provisioning Server.
• **status** – Scan status response buffer.

Returns
0 on success, or (negative) error code otherwise.

```c
int bt_mesh_rpr_link_get(struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv, struct bt_mesh_rpr_link *rsp)
```

Get the current link status of the Remote Provisioning Server.

Parameters
• **cli** – Remote Provisioning Client.
• **srv** – Remote Provisioning Server.
• **rsp** – Link status response buffer.

Returns
0 on success, or (negative) error code otherwise.

```c
int bt_mesh_rpr_link_close(struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv, struct bt_mesh_rpr_link *rsp)
```

Close any open link on the Remote Provisioning Server.

Parameters
• **cli** – Remote Provisioning Client.
• **srv** – Remote Provisioning Server.
• **rsp** – Link status response buffer.

Returns
0 on success, or (negative) error code otherwise.

```c
int32_t bt_mesh_rpr_cli_timeout_get(void)
```

Get the current transmission timeout value.

Returns
The configured transmission timeout in milliseconds.
void bt_mesh_rpr_cli_timeout_set(int32_t timeout)
    Set the transmission timeout value.
    The transmission timeout controls the amount of time the Remote Provisioning Client
    models will wait for a response from the Server.

    **Parameters**
    - timeout – The new transmission timeout.

struct bt_mesh_rpr_scan_status
    #include <rpr_cli.h> Scan status response.

    **Public Members**

    enum bt_mesh_rpr_status status
        Current scan status.
    
    enum bt_mesh_rpr_scan scan
        Current scan state.
    
    uint8_t max_devs
        Max number of devices to report in current scan.
    
    uint8_t timeout
        Seconds remaining of the scan.

struct bt_mesh_rpr_caps
    #include <rpr_cli.h> Remote Provisioning Server scanning capabilities.

    **Public Members**

    uint8_t max_devs
        Max number of scannable devices.
    
    bool active_scan
        Supports active scan.

struct bt_mesh_rpr_cli
    #include <rpr_cli.h> Remote Provisioning Client model instance.

    **Public Members**

    void (*scan_report)(struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv,
                        struct bt_mesh_rpr_unprov *unprov, struct net_buf_simple *adv_data)
        Scan report callback.
        **Param cli**
        Remote Provisioning Client.
        **Param srv**
        Remote Provisioning Server.
Remote Provisioning Server

The Remote Provisioning Server model is a foundation model defined by the Bluetooth mesh specification. It is enabled with the CONFIG_BT_MESH_RPR_SRV option.

The Remote Provisioning Server model is introduced in the Bluetooth Mesh Protocol Specification version 1.1, and is used to support the functionality of remotely provisioning devices into a mesh network.

The Remote Provisioning Server does not have an API of its own, but relies on a Remote Provisioning Client to control it. The Remote Provisioning Server model only accepts messages encrypted with the node’s device key.

If present, the Remote Provisioning Server model must be instantiated on the primary element. Note that after refreshing the device key, node address or Composition Data through a Node Provisioning Protocol Interface (NPPI) procedure, the bt_mesh_prov.reprovisioned callback is triggered. See section Remote Provisioning Client for further details.

Limitations

The following limitations apply to Remote Provisioning Server model:

- Provisioning of unprovisioned device using PB-GATT is not supported.
- All Node Provisioning Protocol Interface (NPPI) procedures are supported. However, if the composition data of a device gets changed after device firmware update (see firmware effect), it is not possible for the device to remain provisioned. The device should be unprovisioned if its composition data is expected to change.

API reference

group bt_mesh_rpr_srv

Defines

BT_MESH_MODEL_RPR_SRV

Remote Provisioning Server model composition data entry.

SAR Configuration Client

The SAR Configuration Client model is a foundation model defined by the Bluetooth Mesh specification. It is an optional model, enabled with the CONFIG_BT_MESH_SAR_CFG_CLI configuration option.

The SAR Configuration Client model is introduced in the Bluetooth Mesh Protocol Specification version 1.1, and it supports the configuration of the lower transport layer behavior of a node that supports the SAR Configuration Server model.

The model can send messages to query or change the states supported by the SAR Configuration Server (SAR Transmitter and SAR Receiver) using SAR Configuration messages.

The SAR Transmitter procedure is used to determine and configure the SAR Transmitter state of a SAR Configuration Server. Function calls bt_mesh_sar_cfg_cli_transmitter_get() and
bt_mesh_sar_cfg_cli_transmitter_set() are used to get and set the SAR Transmitter state of the Target node respectively.

The SAR Receiver procedure is used to determine and configure the SAR Receiver state of a SAR Configuration Server. Function calls bt_mesh_sar_cfg_cli_receiver_get() and bt_mesh_sar_cfg_cli_receiver_set() are used to get and set the SAR Receiver state of the Target node respectively.

For more information about the two states, see SAR states.

An element can send any SAR Configuration Client message at any time to query or change the states supported by the SAR Configuration Server model of a peer node. The SAR Configuration Client model only accepts messages encrypted with the device key of the node supporting the SAR Configuration Server model.

If present, the SAR Configuration Client model must only be instantiated on the primary element.

API reference

group bt_mesh_sar_cfg_cli

   Bluetooth Mesh.

Defines

BT_MESH_MODEL_SAR_CFG_CLI(_cli)
   SAR Configuration Client model composition data entry.

   Parameters

   • _cli – [in] Pointer to a Bluetooth Mesh SAR Configuration Client Model instance.

Functions

int bt_mesh_sar_cfg_cli_transmitter_get(uint16_t net_idx, uint16_t addr, struct bt_mesh_sar_tx *rsp)

Get the SAR Transmitter state of the target node.

   Parameters

   • net_idx – Network index to encrypt with.
   • addr – Target node address.
   • rsp – Status response parameter.

   Returns

   0 on success, or (negative) error code on failure.

int bt_mesh_sar_cfg_cli_transmitter_set(uint16_t net_idx, uint16_t addr, const struct bt_mesh_sar_tx *set, struct bt_mesh_sar_tx *rsp)

Set the SAR Transmitter state of the target node.

   Parameters

   • net_idx – Network index to encrypt with.
   • addr – Target node address.
   • set – New SAR Transmitter state to set on the target node.
   • rsp – Status response parameter.
Returns
0 on success, or (negative) error code on failure.

int bt_mesh_sar_cfg_cli_receiver_get(uint16_t net_idx, uint16_t addr, struct bt_mesh_sar_rx *rsp)

Get the SAR Receiver state of the target node.

Parameters
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **rsp** – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_sar_cfg_cli_receiver_set(uint16_t net_idx, uint16_t addr, const struct bt_mesh_sar_rx *set, struct bt_mesh_sar_rx *rsp)

Set the SAR Receiver state of the target node.

Parameters
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **set** – New SAR Receiver state to set on the target node.
- **rsp** – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int32_t bt_mesh_sar_cfg_cli_timeout_get(void)

Get the current transmission timeout value.

Returns
The configured transmission timeout in milliseconds.

void bt_mesh_sar_cfg_cli_timeout_set(int32_t timeout)

Set the transmission timeout value.

Parameters
- **timeout** – The new transmission timeout.

Include <sar_cfg_cli.h> Mesh SAR Configuration Client Model Context.

Public Members

- const struct bt_mesh_model *model
  Access model pointer.

SAR Configuration Server The SAR Configuration Server model is a foundation model defined by the Bluetooth Mesh specification. It is an optional model, enabled with the CONFIG_BT_MESH_SAR_CFG_SRV configuration option.

The SAR Configuration Server model is introduced in the Bluetooth Mesh Protocol Specification version 1.1, and it supports the configuration of the segmentation and reassembly (SAR) behavior.
of a Bluetooth Mesh node. The model defines a set of states and messages for the SAR configuration.

The SAR Configuration Server model defines two states, SAR Transmitter state and SAR Receiver state. For more information about the two states, see SAR states.

The model also supports the SAR Transmitter and SAR Receiver get and set messages.

The SAR Configuration Server model does not have an API of its own, but relies on a SAR Configuration Client to control it. The SAR Configuration Server model only accepts messages encrypted with the node’s device key.

If present, the SAR Configuration Server model must only be instantiated on the primary element.

**API reference**

```
group bt_mesh_sar_cfg_srv
    Bluetooth Mesh.
```

**Defines**

```
BT_MESH_MODEL_SAR_CFG_SRV
    Transport SAR Configuration Server model composition data entry.
```

**Solicitation PDU RPL Configuration Client** The Solicitation PDU RPL Configuration Client model is a foundation model defined by the Bluetooth mesh specification. The model is optional, and is enabled through the CONFIG_BT_MESH_SOL_PDU_RPL_CLI option.

The Solicitation PDU RPL Configuration Client model was introduced in the Bluetooth Mesh Protocol Specification version 1.1, and supports the functionality of removing addresses from the solicitation replay protection list (SRPL) of a node that supports the Solicitation PDU RPL Configuration Server model.

The Solicitation PDU RPL Configuration Client model communicates with a Solicitation PDU RPL Configuration Server model using the application keys configured by the Configuration Client.

If present, the Solicitation PDU RPL Configuration Client model must only be instantiated on the primary element.

**Configurations** The Solicitation PDU RPL Configuration Client model behavior can be configured with the transmission timeout option CONFIG_BT_MESH_SOL_PDU_RPL_CLI_TIMEOUT. The CONFIG_BT_MESH_SOL_PDU_RPL_CLI_TIMEOUT controls how long the Solicitation PDU RPL Configuration Client waits for a response message to arrive in milliseconds. This value can be changed at runtime using `bt_mesh_sol_pdu_rpl_cli_timeout_set()`.

**API reference**

```
group bt_mesh_sol_pdu_rpl_cli
```

**Defines**

```
BT_MESH_MODEL_SOL_PDU_RPL_CLI(cli_data)
    Solicitation PDU RPL Client model composition data entry.
```
## Functions

```c
int bt_mesh_sol_pdu_rpl_clear(struct bt_mesh_msg_ctx *ctx, uint16_t range_start, uint8_t range_len, uint16_t *start_rsp, uint8_t *len_rsp)
```

Remove entries from Solicitation PDU RPL of addresses in given range.

This method can be used asynchronously by setting `start_rsp` or `len_rsp` as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the `srpl_status` callback in `bt_mesh_sol_pdu_rpl_cli` struct.

**Parameters**

- `ctx` – Message context for the message.
- `range_start` – Start of Unicast address range.
- `range_len` – Length of Unicast address range. Valid values are 0x00 and 0x02 to 0xff.
- `start_rsp` – Range start response buffer.
- `len_rsp` – Range length response buffer.

**Returns**

0 on success, or (negative) error code otherwise.

```c
int bt_mesh_sol_pdu_rpl_clear_unack(struct bt_mesh_msg_ctx *ctx, uint16_t range_start, uint8_t range_len)
```

Remove entries from Solicitation PDU RPL of addresses in given range (unacked).

**Parameters**

- `ctx` – Message context for the message.
- `range_start` – Start of Unicast address range.
- `range_len` – Length of Unicast address range. Valid values are 0x00 and 0x02 to 0xff.

**Returns**

0 on success, or (negative) error code otherwise.

```c
void bt_mesh_sol_pdu_rpl_cli_timeout_set(int32_t timeout)
```

Set the transmission timeout value.

**Parameters**

- `timeout` – The new transmission timeout in milliseconds.

### Public Members

- `const struct bt_mesh_model *model`

  Solicitation PDU RPL model entry pointer.
void (*srpl_status)(struct bt_mesh_sol_pdu_rpl_cli *cli, uint16_t addr, uint16_t range_start, uint8_t range_length)

Optional callback for Solicitation PDU RPL Status messages.

Handles received Solicitation PDU RPL Status messages from a Solicitation PDU RPL server. The `range_start` param represents the start of range that server has cleared. The `range_length` param represents length of range cleared by server.

**Param cli**
Solicitation PDU RPL client that received the status message.

**Param addr**
Address of the sender.

**Param range_start**
Range start value.

**Param range_length**
Range length value.

### Solicitation PDU RPL Configuration Server

The Solicitation PDU RPL Configuration Server model is a foundation model defined by the Bluetooth mesh specification. The model is enabled if the node has the **On-Demand Private Proxy Server** enabled.

The Solicitation PDU RPL Configuration Server model was introduced in the Bluetooth Mesh Protocol Specification version 1.1, and manages the Solicitation Replay Protection List (SRPL) saved on the device. The SRPL is used to reject Solicitation PDUs that are already processed by a node. When a valid Solicitation PDU message is successfully processed by a node, the SSRC field and SSEQ field of the message are stored in the node's SRPL.

The Solicitation PDU RPL Configuration Server does not have an API of its own, and relies on a **Solicitation PDU RPL Configuration Client** to control it. The model only accepts messages encrypted with an application key as configured by the Configuration Client.

If present, the Solicitation PDU RPL Configuration Server model must only be instantiated on the primary element.

### Configurations

For the Solicitation PDU RPL Configuration Server model, the `CONFIG_BT_MESH_PROXY_SRPL_SIZE` option can be configured to set the size of the SRPL.

### API reference

*group bt_mesh_sol_pdu_rpl_srv*

**Defines**

*BT_MESH_MODEL_SOL_PDU_RPL_SRV*
Solicitation PDU RPL Server model composition data entry.

### Model specification models

In addition to the foundation models defined in the Bluetooth Mesh specification, the Bluetooth Mesh Model Specification defines several models, some of which are implemented in Zephyr:
The Binary Large Object (BLOB) Transfer models implement the Bluetooth Mesh Binary Large Object Transfer Model specification version 1.0 and provide functionality for sending large binary objects from a single source to many Target nodes over the Bluetooth Mesh network. It is the underlying transport method for the Device Firmware Update (DFU), but may be used for other object transfer purposes. The implementation is in experimental state.

The BLOB Transfer models support transfers of continuous binary objects of up to 4 GB ($2^{32}$ bytes). The BLOB transfer protocol has built-in recovery procedures for packet losses, and sets up checkpoints to ensure that all targets have received all the data before moving on. Data transfer order is not guaranteed.

BLOB transfers are constrained by the transfer speed and reliability of the underlying mesh network. Under ideal conditions, the BLOBs can be transferred at a rate of up to 1 kbps, allowing a 100 kB BLOB to be transferred in 10-15 minutes. However, network conditions, transfer capabilities and other limiting factors can easily degrade the data rate by several orders of magnitude. Tuning the parameters of the transfer according to the application and network configuration, as well as scheduling it to periods with low network traffic, will offer significant improvements on the speed and reliability of the protocol. However, achieving transfer rates close to the ideal rate is unlikely in actual deployments.

There are two BLOB Transfer models:

**BLOB Transfer Server** The Binary Large Object (BLOB) Transfer Server model implements reliable receiving of large binary objects. It serves as the backend of the Firmware Update Server, but can also be used for receiving other binary images.

**BLOBs** As described in BLOB Transfer models, the binary objects transferred by the BLOB Transfer models are divided into blocks, which are divided into chunks. As the transfer is controlled by the BLOB Transfer Client model, the BLOB Transfer Server must allow blocks to come in any order. The chunks within a block may also come in any order, but all chunks in a block must be received before the next block is started.

The BLOB Transfer Server keeps track of the received blocks and chunks, and will process each block and chunk only once. The BLOB Transfer Server also ensures that any missing chunks are resent by the BLOB Transfer Client.

**Usage** The BLOB Transfer Server is instantiated on an element with a set of event handler callbacks:

```c
static const struct bt_mesh_blob_srv_cb blob_cb = {
    /* Callbacks */
};
static struct bt_mesh_blob_srv blob_srv = {
    .cb = &blob_cb,
};
static const struct bt_mesh_model models[] = {
    BT_MESH_MODEL_BLOB_SRV(&blob_srv),
};
```

A BLOB Transfer Server is capable of receiving a single BLOB transfer at a time. Before the BLOB Transfer Server can receive a transfer, it must be prepared by the user. The transfer ID must be passed to the BLOB Transfer Server through the `bt_mesh_blob_srv_recv()` function before the transfer is started by the BLOB Transfer Client. The ID must be shared between the BLOB Transfer Client and the BLOB Transfer Server through some higher level procedure, like a vendor specific transfer management model.
Once the transfer has been set up on the BLOB Transfer Server, it’s ready for receiving the BLOB. The application is notified of the transfer progress through the event handler callbacks, and the BLOB data is sent to the BLOB stream.

The interaction between the BLOB Transfer Server, BLOB stream and application is shown below:

![BLOB Transfer Server model interaction](image)

**Fig. 8: BLOB Transfer Server model interaction**

**Transfer suspension** The BLOB Transfer Server keeps a running timer during the transfer, that is reset on every received message. If the BLOB Transfer Client does not send a message before the transfer timer expires, the transfer is suspended by the BLOB Transfer Server.

The BLOB Transfer Server notifies the user of the suspension by calling the `suspended` callback. If the BLOB Transfer Server is in the middle of receiving a block, this block is discarded.

The BLOB Transfer Client may resume a suspended transfer by starting a new block transfer. The BLOB Transfer Server notifies the user by calling the `resume` callback.

**Transfer recovery** The state of the BLOB transfer is stored persistently. If a reboot occurs, the BLOB Transfer Server will attempt to recover the transfer. When the Bluetooth Mesh subsystem is started (for instance by calling `bt_mesh_init()`), the BLOB Transfer Server will check for aborted transfers, and call the `recover` callback if there is any. In the recover callback, the user must provide a BLOB stream to use for the rest of the transfer. If the recover callback doesn’t
return successfully or does not provide a BLOB stream, the transfer is abandoned. If no recover callback is implemented, transfers are always abandoned after a reboot.

After a transfer is successfully recovered, the BLOB Transfer Server enters the suspended state. It will stay suspended until the BLOB Transfer Client resumes the transfer, or the user cancels it.

---

**Note:** The BLOB Transfer Client sending the transfer must support transfer recovery for the transfer to complete. If the BLOB Transfer Client has already given up the transfer, the BLOB Transfer Server will stay suspended until the application calls `bt_mesh_blob_srv_cancel()`.

---

**API reference**

**group bt_mesh_blob_srv**

**Defines**

- `BT_MESH_BLOB_BLOCKS_MAX`
  Max number of blocks in a single transfer.

- `BT_MESH_MODEL_BLOB_SRV(_srv)`
  BLOB Transfer Server model composition data entry.

**Parameters**

- `_srv` – Pointer to a Bluetooth Mesh BLOB Transfer Server model API instance.

**Functions**

- `int bt_mesh_blob_srv_recv(struct bt_mesh_blob_srv *srv, uint64_t id, const struct bt_mesh_blob_io *io, uint8_t ttl, uint16_t timeout_base)`
  Prepare BLOB Transfer Server for an incoming transfer.

  Before a BLOB Transfer Server can receive a transfer, the transfer must be prepared through some application level mechanism. The BLOB Transfer Server will only accept incoming transfers with a matching BLOB ID.

  **Parameters**

  - `srv` – BLOB Transfer Server instance.
  - `id` – BLOB ID to accept.
  - `io` – BLOB stream to write the incoming BLOB to.
  - `ttl` – Time to live value to use in responses to the BLOB Transfer Client.
  - `timeout_base` – Extra time for the Client to respond in addition to the base 10 seconds, in 10-second increments.

  **Returns**

  0 on success, or (negative) error code on failure.

- `int bt_mesh_blob_srv_cancel(struct bt_mesh_blob_srv *srv)`
  Cancel the current BLOB transfer.

  Tells the BLOB Transfer Client to drop this device from the list of Targets for the current transfer. Note that the client may continue sending the transfer to other Targets.
Parameters
• \( \texttt{srv} \) – BLOB Transfer Server instance.

Returns
0 on success, or (negative) error code on failure.

```c
bool \textbf{bt\_mesh\_blob\_srv\_is\_busy}(\texttt{const struct bt\_mesh\_blob\_srv *srv})
```
Get the current state of the BLOB Transfer Server.

Parameters
• \( \texttt{srv} \) – BLOB Transfer Server instance.

Returns
true if the BLOB Transfer Server is currently participating in a transfer, false otherwise.

```c
uint8_t \textbf{bt\_mesh\_blob\_srv\_progress}(\texttt{const struct bt\_mesh\_blob\_srv *srv})
```
Get the current progress of the active transfer in percent.

Parameters
• \( \texttt{srv} \) – BLOB Transfer Server instance.

Returns
The current transfer progress, or 0 if no transfer is active.

```c
\textbf{struct bt\_mesh\_blob\_srv\_cb}
```

#include <blob\_srv.h> BLOB Transfer Server model event handlers.
All callbacks are optional.

Public Members

```c
int (*\textbf{start})(\texttt{struct bt\_mesh\_blob\_srv *srv, struct bt\_mesh\_msg\_ctx *ctx, struct bt\_mesh\_blob\_xfer *xfer})
```
Transfer start callback.
Called when the transfer has started with the prepared BLOB ID.

- **Param srv**
  BLOB Transfer Server instance.

- **Param ctx**
  Message context for the incoming start message. The entire transfer will be sent from the same source address.

- **Param xfer**
  Transfer parameters.

Return
0 on success, or (negative) error code to reject the transfer.

```c
void (*\textbf{end})(\texttt{struct bt\_mesh\_blob\_srv *srv, uint64_t id, bool success})
```
Transfer end callback.
Called when the transfer ends, either because it was cancelled, or because it finished successfully. A new transfer may be prepared.

**Note**: The transfer may end before it's started if the start parameters are invalid.

- **Param srv**
  BLOB Transfer Server instance.
**Param id**
BLOB ID of the cancelled transfer.

**Param success**
Whether the transfer was successful.

```c
void (*suspended)(struct bt_mesh_blob_srv *srv)
Transfer suspended callback.
```

Called if the Server timed out while waiting for a transfer packet. A suspended transfer may resume later from the start of the current block. Any received chunks in the current block should be discarded, they will be received again if the transfer resumes.

The transfer will call `resume` again when resuming.

**Note:** The BLOB Transfer Server does not run a timer in the suspended state, and it's up to the application to determine whether the transfer should be permanently cancelled. Without interaction, the transfer will be suspended indefinitely, and the BLOB Transfer Server will not accept any new transfers.

```c
void (*resume)(struct bt_mesh_blob_srv *srv)
Transfer resume callback.
```

Called if the transfer is resumed after being suspended.

```c
int (*recover)(struct bt_mesh_blob_srv *srv, struct bt_mesh_blob_xfer *xfer, const struct bt_mesh_blob_io **io)
```

Transfer recovery callback.

Called when the Bluetooth Mesh subsystem is started if the device is rebooted in the middle of a transfer.

Transfers will not be resumed after a reboot if this callback is not defined.

```c
param srv
BLOB Transfer Server instance.
```

```c
param xfer
Transfer to resume.
```

```c
param io
BLOB stream return parameter. Must be set to a valid BLOB stream by the callback.
```

**Return**
0 on success, or (negative) error code to abandon the transfer.

```c
#include <blob_srv.h>
```

**Public Members**

```c
const struct bt_mesh_blob_srv_cb *cb
Event handler callbacks.
```
struct bt_mesh_blob_srv_state
#include <blob_srv.h>

**BLOB Transfer Client** The Binary Large Object (BLOB) Transfer Client is the sender of the BLOB transfer. It supports sending BLOBs of any size to any number of Target nodes, in both Push BLOB Transfer Mode and Pull BLOB Transfer Mode.

**Usage**

**Initialization** The BLOB Transfer Client is instantiated on an element with a set of event handler callbacks:

```c
static const struct bt_mesh_blob_cli_cb blob_cb = {
    /* Callbacks */
};
static struct bt_mesh_blob_cli blob_cli = {
    .cb = &blob_cb,
};
static const struct bt_mesh_model models[] = {
    BT_MESH_MODEL_BLOB_CLI(&blob_cli),
};
```

**Transfer context** Both the transfer capabilities retrieval procedure and the BLOB transfer uses an instance of a `bt_mesh_blob_cli_inputs` to determine how to perform the transfer. The BLOB Transfer Client Inputs structure must at least be initialized with a list of targets, an application key and a time to live (TTL) value before it is used in a procedure:

```c
static struct bt_mesh_blob_target targets[3] = {
    {.addr = 0x0001 },
    {.addr = 0x0002 },
    {.addr = 0x0003 },
};
static struct bt_mesh_blob_cli_inputs inputs = {
    .app_idx = MY_APP_IDX,
    .ttl = BT_MESH_TTL_DEFAULT,
};
sys_slist_init(&inputs.targets);
sys_slist_append(&inputs.targets, &targets[0].n);
sys_slist_append(&inputs.targets, &targets[1].n);
sys_slist_append(&inputs.targets, &targets[2].n);
```

Note that all BLOB Transfer Servers in the transfer must be bound to the chosen application key.

**Group address** The application may additionally specify a group address in the context structure. If the group is not `BT_MESH_ADDR_UNASSIGNED`, the messages in the transfer will be sent to the group address, instead of being sent individually to each Target node. Mesh Manager must ensure that all Target nodes having the BLOB Transfer Server model subscribe to this group address.

Using group addresses for transferring the BLOBs can generally increase the transfer speed, as the BLOB Transfer Client sends each message to all Target nodes at the same time. However,
sending large, segmented messages to group addresses in Bluetooth Mesh is generally less reliable than sending them to unicast addresses, as there is no transport layer acknowledgment mechanism for groups. This can lead to longer recovery periods at the end of each block, and increases the risk of losing Target nodes. Using group addresses for BLOB transfers will generally only pay off if the list of Target nodes is extensive, and the effectiveness of each addressing strategy will vary heavily between different deployments and the size of the chunks.

**Transfer timeout**  
If a Target node fails to respond to an acknowledged message within the BLOB Transfer Client's time limit, the Target node is dropped from the transfer. The application can reduce the chances of this by giving the BLOB Transfer Client extra time through the context structure. The extra time may be set in 10-second increments, up to 182 hours, in addition to the base time of 20 seconds. The wait time scales automatically with the transfer TTL.

Note that the BLOB Transfer Client only moves forward with the transfer in following cases:

- All Target nodes have responded.
- A node has been removed from the list of Target nodes.
- The BLOB Transfer Client times out.

Increasing the wait time will increase this delay.

**BLOB transfer capabilities retrieval**  
It is generally recommended to retrieve BLOB transfer capabilities before starting a transfer. The procedure populates the transfer capabilities from all Target nodes with the most liberal set of parameters that allows all Target nodes to participate in the transfer. Any Target nodes that fail to respond, or respond with incompatible transfer parameters, will be dropped.

Target nodes are prioritized according to their order in the list of Target nodes. If a Target node is found to be incompatible with any of the previous Target nodes, for instance by reporting a non-overlapping block size range, it will be dropped. Lost Target nodes will be reported through the `lost_target` callback.

The end of the procedure is signalled through the `caps` callback, and the resulting capabilities can be used to determine the block and chunk sizes required for the BLOB transfer.

**BLOB transfer**  
The BLOB transfer is started by calling `bt_mesh_blob_cli_send()` function, which (in addition to the aforementioned transfer inputs) requires a set of transfer parameters and a BLOB stream instance. The transfer parameters include the 64-bit BLOB ID, the BLOB size, the transfer mode, the block size in logarithmic representation and the chunk size. The BLOB ID is application defined, but must match the BLOB ID the BLOB Transfer Servers have been started with.

The transfer runs until it either completes successfully for at least one Target node, or it is cancelled. The end of the transfer is communicated to the application through the `end` callback. Lost Target nodes will be reported through the `lost_target` callback.

**API reference**

*group* `bt_mesh_blob_cli`

在职
BT_MESH_MODEL_BLOB_CLI(_cli)

BLOB Transfer Client model Composition Data entry.

**Parameters**

- `_cli` – Pointer to a *Bluetooth Mesh BLOB Transfer Client model API* instance.

### Enums

**enum bt_mesh_blob_cli_state**

BLOB Transfer Client state.

**Values:**

- `BT_MESH_BLOB_CLI_STATE_NONE` - No transfer is active.
- `BT_MESH_BLOB_CLI_STATE_CAPS_GET` - Retrieving transfer capabilities.
- `BT_MESH_BLOB_CLI_STATE_START` - Sending transfer start.
- `BT_MESH_BLOB_CLI_STATE_BLOCK_START` - Sending block start.
- `BT_MESH_BLOB_CLI_STATE_BLOCK_SEND` - Sending block chunks.
- `BT_MESH_BLOB_CLI_STATE_BLOCK_CHECK` - Checking block status.
- `BT_MESH_BLOB_CLI_STATE_XFER_CHECK` - Checking transfer status.
- `BT_MESH_BLOB_CLI_STATE_CANCEL` - Cancelling transfer.
- `BT_MESH_BLOB_CLI_STATE_SUSPENDED` - Transfer is suspended.
- `BT_MESH_BLOB_CLI_STATE_XFER_PROGRESS_GET` - Checking transfer progress.

### Functions
int bt_mesh_blob_cli_caps_get(struct bt_mesh_blob_cli *cli, const struct bt_mesh_blob_cli_inputs *inputs)

Retrieve transfer capabilities for a list of Target nodes.

Queries the availability and capabilities of all Target nodes, producing a cumulative set of transfer capabilities for the Target nodes, and returning it through the bt_mesh_blob_cli_cb::caps callback.

Retrieving the capabilities may take several seconds, depending on the number of Target nodes and mesh network performance. The end of the procedure is indicated through the bt_mesh_blob_cli_cb::caps callback.

This procedure is not required, but strongly recommended as a preparation for a transfer to maximize performance and the chances of success.

**Parameters**

- cli – BLOB Transfer Client instance.
- inputs – Statically allocated BLOB Transfer Client transfer inputs.

**Returns**

0 on success, or (negative) error code otherwise.

int bt_mesh_blob_cli_send(struct bt_mesh_blob_cli *cli, const struct bt_mesh_blob_cli_inputs *inputs, const struct bt_mesh_blob_xfer *xfer, const struct bt_mesh_blob_io *io)

Perform a BLOB transfer.

Starts sending the transfer to the Target nodes. Only Target nodes with a status of BT_MESH_BLOB_SUCCESS will be considered.

The transfer will keep going either until all Target nodes have been dropped, or the full BLOB has been sent.

The BLOB transfer may take several minutes, depending on the number of Target nodes, size of the BLOB and mesh network performance. The end of the transfer is indicated through the bt_mesh_blob_cli_cb::end callback.

A Client only supports one transfer at the time.

**Parameters**

- cli – BLOB Transfer Client instance.
- inputs – Statically allocated BLOB Transfer Client transfer inputs.
- xfer – Statically allocated transfer parameters.
- io – BLOB stream to read the transfer from.

**Returns**

0 on success, or (negative) error code otherwise.

int bt_mesh_blob_cli_suspend(struct bt_mesh_blob_cli *cli)

Suspend the active transfer.

**Parameters**

- cli – BLOB Transfer Client instance.

**Returns**

0 on success, or (negative) error code otherwise.

int bt_mesh_blob_cli_resume(struct bt_mesh_blob_cli *cli)

Resume the suspended transfer.

**Parameters**
• cli – BLOB Transfer Client instance.

**Returns**
0 on success, or (negative) error code otherwise.

```c
void bt_mesh_blob_cli_cancel(struct bt_mesh_blob_cli *cli)
```
Cancel an ongoing transfer.

**Parameters**
• cli – BLOB Transfer Client instance.

```c
int bt_mesh_blob_cli_xfer_progress_get(struct bt_mesh_blob_cli *cli,
const struct bt_mesh_blob_cli_inputs *inputs)
```
Get the progress of BLOB transfer.

This function can only be used if the BLOB Transfer Client is currently not per-
forming a BLOB transfer. To get progress of the active BLOB transfer, use the
`bt_mesh_blob_cli_xfer_progress_active_get` function.

**Parameters**
• cli – BLOB Transfer Client instance.
• inputs – Statically allocated BLOB Transfer Client transfer inputs.

**Returns**
0 on success, or (negative) error code otherwise.

```c
uint8_t bt_mesh_blob_cli_xfer_progress_active_get(struct bt_mesh_blob_cli *cli)
```
Get the current progress of the active transfer in percent.

**Parameters**
• cli – BLOB Transfer Client instance.

**Returns**
The current transfer progress, or 0 if no transfer is active.

```c
bool bt_mesh_blob_cli_is_busy(struct bt_mesh_blob_cli *cli)
```
Get the current state of the BLOB Transfer Client.

**Parameters**
• cli – BLOB Transfer Client instance.

**Returns**
true if the BLOB Transfer Client is currently participating in a transfer or
retrieving the capabilities and false otherwise.

```c
struct bt_mesh_blob_target_pull

#include <blob_cli.h> Target node's Pull mode (Pull BLOB Transfer Mode) context used
while sending chunks to the Target node.
```

**Public Members**

```c
int64_t block_report_timestamp

Timestamp when the Block Report Timeout Timer expires for this Target node.
```

```c
uint8_t missing[DIV_ROUND_UP(CONFIG_BT_MESH_BLOB_CHUNK_COUNT_MAX, 8)]

Missing chunks reported by this Target node.
```
struct bt_mesh_blob_target
    
    *include <blob_cli.h>* BLOB Transfer Client Target node.

Public Members

sys_snodo_t n
    
    Linked list node.

uint16_t addr
    
    Target node address.

struct bt_mesh_blob_target_pull *pull
    
    Target node's Pull mode context.
    
    Needs to be initialized when sending a BLOB in Pull mode.

uint8_t status
    
    BLOB transfer status, see *bt_mesh_blob_status*.

struct bt_mesh_blob_xfer_info
    
    *include <blob_cli.h>* BLOB transfer information.

    If phase is *BT_MESH_BLOB_XFER_PHASE_INACTIVE*, the fields below phase are not initialized. If phase is *BT_MESH_BLOB_XFER_PHASE_WAITING_FOR_START*, the fields below id are not initialized.

Public Members

enum bt_mesh_blob_status status
    
    BLOB transfer status.

enum bt_mesh_blob_xfer_mode mode
    
    BLOB transfer mode.

enum bt_mesh_blob_xfer_phase phase
    
    BLOB transfer phase.

uint64_t id
    
    BLOB ID.

uint32_t size
    
    BLOB size in octets.

uint8_t block_size_log
    
    Logarithmic representation of the block size.

uint16_t mtu_size
    
    MTU size in octets.
const uint8_t *missing_blocks
    Bit field indicating blocks that were not received.

```c
struct bt_mesh_blob_cli_inputs
    #include <blob_cli.h> BLOB Transfer Client transfer inputs.
```

**Public Members**

```c
sys_slist_t targets
    Linked list of Target nodes.
    Each node should point to bt_mesh_blob_target::n.
```

```c
uint16_t app_idx
    AppKey index to send with.
```

```c
uint16_t group
    Group address destination for the BLOB transfer, or
    BT_MESH_ADDR_UNASSIGNED to send every message to each Target node
    individually.
```

```c
uint8_t ttl
    Time to live value of BLOB transfer messages.
```

```c
uint16_t timeout_base
    Additional response time for the Target nodes, in 10-second increments.
    The extra time can be used to give the Target nodes more time to respond to
    messages from the Client. The actual timeout will be calculated according to the
    following formula:

    * timeout = 20 seconds + (10 seconds * timeout_base) + (100 ms * TTL)
    *

    If a Target node fails to respond to a message from the Client within the configured
    transfer timeout, the Target node is dropped.
```

```c
struct bt_mesh_blob_cli_caps
    #include <blob_cli.h> Transfer capabilities of a Target node.
```

**Public Members**

```c
size_t max_size
    Max BLOB size.
```

```c
uint8_t min_block_size_log
    Logarithmic representation of the minimum block size.
```

```c
uint8_t max_block_size_log
    Logarithmic representation of the maximum block size.
uint16_t max_chunks
Max number of chunks per block.

uint16_t max_chunk_size
Max chunk size.

uint16_t mtu_size
Max MTU size.

enum bt_mesh_blob_xfer_mode modes
Supported transfer modes.

struct bt_mesh_blob_cli_cb
#include <blob_cli.h> Event handler callbacks for the BLOB Transfer Client model.
All handlers are optional.

Public Members

void (*caps)(struct bt_mesh_blob_cli *cli, const struct bt_mesh_blob_cli_caps *caps)
Capabilities retrieval completion callback.
Called when the capabilities retrieval procedure completes, indicating that a common set of acceptable transfer parameters have been established for the given list of Target nodes. All compatible Target nodes have status code BT_MESH_BLOB_SUCCESS.
   Param cli
   BLOB Transfer Client instance.
   Param caps
   Safe transfer capabilities if the transfer capabilities of at least one Target node has satisfied the Client, or NULL otherwise.

void (*lost_target)(struct bt_mesh_blob_cli *cli, struct bt_mesh_blob_target *target, enum bt_mesh_blob_status reason)
Target node loss callback.
Called whenever a Target node has been lost due to some error in the transfer. Losing a Target node is not considered a fatal error for the Client until all Target nodes have been lost.
   Param cli
   BLOB Transfer Client instance.
   Param target
   Target node that was lost.
   Param reason
   Reason for the Target node loss.

void (*suspended)(struct bt_mesh_blob_cli *cli)
Transfer is suspended.
Called when the transfer is suspended due to response timeout from all Target nodes.
   Param cli
   BLOB Transfer Client instance.
void (*end)(struct bt_mesh_blob_cli *cli, const struct bt_mesh_blob_xfer *xfer, bool success)
Transfer end callback.
Called when the transfer ends.

  **Param cli**
  BLOB Transfer Client instance.

  **Param xfer**
  Completed transfer.

  **Param success**
  Status of the transfer. Is true if at least one Target node received the whole transfer.

void (*xfer_progress)(struct bt_mesh_blob_cli *cli, struct bt_mesh_blob_target *target, const struct bt_mesh_blob_xfer_info *info)
Transfer progress callback.
The content of info is invalidated upon exit from the callback. Therefore it needs
to be copied if it is planned to be used later.

  **Param cli**
  BLOB Transfer Client instance.

  **Param target**
  Target node that responded to the request.

  **Param info**
  BLOB transfer information.

void (*xfer_progress_complete)(struct bt_mesh_blob_cli *cli)
End of Get Transfer Progress procedure.
Called when all Target nodes have responded or the procedure timed-out.

  **Param cli**
  BLOB Transfer Client instance.

struct bt_mesh_blob_cli
#include <blob_cli.h> BLOB Transfer Client model instance.

**Public Members**

  **const struct bt_mesh_blob_cli_cb **cb**
  Event handler callbacks.

The BLOB Transfer Client is instantiated on the sender node, and the BLOB Transfer Server is
instantiated on the receiver nodes.

**Concepts** The BLOB transfer protocol introduces several new concepts to implement the BLOB transfer.

**BLOBs** BLOBs are binary objects up to 4 GB in size, that can contain any data the application
would like to transfer through the mesh network. The BLOBs are continuous data objects, di-
vided into blocks and chunks to make the transfers reliable and easy to process. No limitations
are put on the contents or structure of the BLOB, and applications are free to define any encoding
or compression they'd like on the data itself.

The BLOB transfer protocol does not provide any built-in integrity checks, encryption or authen-
tication of the BLOB data. However, the underlying encryption of the Bluetooth Mesh protocol
provides data integrity checks and protects the contents of the BLOB from third parties using network and application level encryption.

**Blocks**  The binary objects are divided into blocks, typically from a few hundred to several thousand bytes in size. Each block is transmitted separately, and the BLOB Transfer Client ensures that all BLOB Transfer Servers have received the full block before moving on to the next. The block size is determined by the transfer's `block_size_log` parameter, and is the same for all blocks in the transfer except the last, which may be smaller. For a BLOB stored in flash memory, the block size is typically a multiple of the flash page size of the Target devices.

**Chunks**  Each block is divided into chunks. A chunk is the smallest data unit in the BLOB transfer, and must fit inside a single Bluetooth Mesh access message excluding the opcode (379 bytes or less). The mechanism for transferring chunks depends on the transfer mode.

When operating in Push BLOB Transfer Mode, the chunks are sent as unacknowledged packets from the BLOB Transfer Client to all targeted BLOB Transfer Servers. Once all chunks in a block have been sent, the BLOB Transfer Client asks each BLOB Transfer Server if they're missing any chunks, and resends them. This is repeated until all BLOB Transfer Servers have received all chunks, or the BLOB Transfer Client gives up.

When operating in Pull BLOB Transfer Mode, the BLOB Transfer Server will request a small number of chunks from the BLOB Transfer Client at a time, and wait for the BLOB Transfer Client to send them before requesting more chunks. This repeats until all chunks have been transferred, or the BLOB Transfer Server gives up.

Read more about the transfer modes in [Transfer modes](#) section.

**BLOB streams**  In the BLOB Transfer models' APIs, the BLOB data handling is separated from the high-level transfer handling. This split allows reuse of different BLOB storage and transfer strategies for different applications. While the high level transfer is controlled directly by the application, the BLOB data itself is accessed through a BLOB stream.

The BLOB stream is comparable to a standard library file stream. Through opening, closing, reading and writing, the BLOB Transfer model gets full access to the BLOB data, whether it's kept in flash, RAM, or on a peripheral. The BLOB stream is opened with an access mode (read or write) before it's used, and the BLOB Transfer models will move around inside the BLOB's data in blocks and chunks, using the BLOB stream as an interface.

**Interaction**  Before the BLOB is read or written, the stream is opened by calling its `open` callback. When used with a BLOB Transfer Server, the BLOB stream is always opened in write mode, and when used with a BLOB Transfer Client, it's always opened in read mode.

For each block in the BLOB, the BLOB Transfer model starts by calling `block_start`. Then, depending on the access mode, the BLOB stream's `wr` or `rd` callback is called repeatedly to move data to or from the BLOB. When the model is done processing the block, it calls `block_end`. When the transfer is complete, the BLOB stream is closed by calling `close`.

**Implementations**  The application may implement their own BLOB stream, or use the implementations provided by Zephyr:

**BLOB Flash**  The BLOB Flash Readers and Writers implement BLOB reading to and writing from flash partitions defined in the `flash map`.

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6.1. Bluetooth
**BLOB Flash Reader**  The BLOB Flash Reader interacts with the BLOB Transfer Client to read BLOB data directly from flash. It must be initialized by calling `bt_mesh_blob_flash_rd_init()` before being passed to the BLOB Transfer Client. Each BLOB Flash Reader only supports one transfer at the time.

**BLOB Flash Writer**  The BLOB Flash Writer interacts with the BLOB Transfer Server to write BLOB data directly to flash. It must be initialized by calling `bt_mesh_blob_flash_rd_init()` before being passed to the BLOB Transfer Server. Each BLOB Flash Writer only supports one transfer at the time, and requires a block size that is a multiple of the flash page size. If a transfer is started with a block size lower than the flash page size, the transfer will be rejected.

The BLOB Flash Writer copies chunk data into a buffer to accommodate chunks that are unaligned with the flash write block size. The buffer data is padded with \(0xff\) if either the start or length of the chunk is unaligned.

**API Reference**

*group* bt_mesh_blob_io_flash

**Functions**

```c
int bt_mesh_blob_io_flash_init(struct bt_mesh_blob_io_flash *flash, uint8_t area_id, off_t offset)
```

Initialize a flash stream.

**Parameters**

- `flash` – Flash stream.
- `area_id` – Flash partition identifier. See `flash_area_open`.
- `offset` – Offset into the flash area, in bytes.

**Returns**

0 on success or (negative) error code otherwise.

```c
struct bt_mesh_blob_io_flash
```

Include `<blob_io_flash.h>` BLOB flash stream.

**Public Members**

```c
uint8_t area_id
```

Flash area ID to write the BLOB to.

```c
enum bt_mesh_blob_io_mode mode
```

Active stream mode.

```c
off_t offset
```

Offset into the flash area to place the BLOB at (in bytes).
**Transfer capabilities**  Each BLOB Transfer Server may have different transfer capabilities. The transfer capabilities of each device are controlled through the following configuration options:

- `CONFIG_BT_MESH_BLOB_SIZE_MAX`
- `CONFIG_BT_MESH_BLOB_BLOCK_SIZE_MIN`
- `CONFIG_BT_MESH_BLOB_BLOCK_SIZE_MAX`
- `CONFIG_BT_MESH_BLOB_CHUNK_COUNT_MAX`

The `CONFIG_BT_MESH_BLOB_CHUNK_COUNT_MAX` option is also used by the BLOB Transfer Client and affects memory consumption by the BLOB Transfer Client model structure.

To ensure that the transfer can be received by as many servers as possible, the BLOB Transfer Client can retrieve the capabilities of each BLOB Transfer Server before starting the transfer. The client will transfer the BLOB with the highest possible block and chunk size.

**Transfer modes**  BLOBs can be transferred using two transfer modes, Push BLOB Transfer Mode and Pull BLOB Transfer Mode. In most cases, the transfer should be conducted in Push BLOB Transfer Mode.

In Push BLOB Transfer Mode, the send rate is controlled by the BLOB Transfer Client, which will push all the chunks of each block without any high level flow control. Push BLOB Transfer Mode supports any number of Target nodes, and should be the default transfer mode.

In Pull BLOB Transfer Mode, the BLOB Transfer Server will “pull” the chunks from the BLOB Transfer Client at its own rate. Pull BLOB Transfer Mode can be conducted with multiple Target nodes, and is intended for transferring BLOBs to Target nodes acting as **Low Power Node**. When operating in Pull BLOB Transfer Mode, the BLOB Transfer Server will request chunks from the BLOB Transfer Client in small batches, and wait for them all to arrive before requesting more chunks. This process is repeated until the BLOB Transfer Server has received all chunks in a block. Then, the BLOB Transfer Client starts the next block, and the BLOB Transfer Server requests all chunks of that block.

**Transfer timeout**  The timeout of the BLOB transfer is based on a Timeout Base value. Both client and server use the same Timeout Base value, but they calculate timeout differently.

The BLOB Transfer Server uses the following formula to calculate the BLOB transfer timeout:

\[ 10 \times (\text{Timeout Base} + 1) \text{ seconds} \]

For the BLOB Transfer Client, the following formula is used:

\[ ((10000 \times (\text{Timeout Base} + 2)) + (100 \times \text{TTL})) \text{ milliseconds} \]

where TTL is time to live value set in the transfer.

**API reference**  This section contains types and defines common to the BLOB Transfer models.

```
group bt_mesh_blob

Defines

CONFIG_BT_MESH_BLOB_CHUNK_COUNT_MAX
```
Enums

enum bt_mesh_blob_xfer_mode
    BLOB transfer mode.
    Values:

    enumerator BT_MESH_BLOB_XFER_MODE_NONE
        No valid transfer mode.

    enumerator BT_MESH_BLOB_XFER_MODE_PUSH
        Push mode (Push BLOB Transfer Mode).

    enumerator BT_MESH_BLOB_XFER_MODE_PULL
        Pull mode (Pull BLOB Transfer Mode).

    enumerator BT_MESH_BLOB_XFER_MODE_ALL
        Both modes are valid.

enum bt_mesh_blob_xfer_phase
    Transfer phase.
    Values:

    enumerator BT_MESH_BLOB_XFER_PHASE_INACTIVE
        The BLOB Transfer Server is awaiting configuration.

    enumerator BT_MESH_BLOB_XFER_PHASE_WAITING_FOR_START
        The BLOB Transfer Server is ready to receive a BLOB transfer.

    enumerator BT_MESH_BLOB_XFER_PHASE_WAITING_FOR_BLOCK
        The BLOB Transfer Server is waiting for the next block of data.

    enumerator BT_MESH_BLOB_XFER_PHASE_WAITING_FOR CHUNK
        The BLOB Transfer Server is waiting for the next chunk of data.

    enumerator BT_MESH_BLOB_XFER_PHASE_COMPLETE
        The BLOB was transferred successfully.

   enumerator BT_MESH_BLOB_XFER_PHASE_SUSPENDED
        The BLOB transfer is paused.

enum bt_mesh_blob_status
    BLOB model status codes.
    Values:

    enumerator BT_MESH_BLOB_SUCCESS
        The message was processed successfully.
enumerator BT_MESH_BLOB_ERR_INVALID_BLOCK_NUM
      The Block Number field value is not within the range of blocks being transferred.

enumerator BT_MESH_BLOB_ERR_INVALID_BLOCK_SIZE
      The block size is smaller than the size indicated by the Min Block Size Log state or
      is larger than the size indicated by the Max Block Size Log state.

enumerator BT_MESH_BLOB_ERR_INVALID_CHUNK_SIZE
      The chunk size exceeds the size indicated by the Max Chunk Size state, or the num-
      ber of chunks exceeds the number specified by the Max Total Chunks state.

enumerator BT_MESH_BLOB_ERR_WRONG_PHASE
      The operation cannot be performed while the server is in the current phase.

enumerator BT_MESH_BLOB_ERR_INVALID_PARAM
      A parameter value in the message cannot be accepted.

enumerator BT_MESH_BLOB_ERR_WRONG_BLOB_ID
      The message contains a BLOB ID value that is not expected.

enumerator BT_MESH_BLOB_ERR_BLOB_TOO_LARGE
      There is not enough space available in memory to receive the BLOB.

enumerator BT_MESH_BLOB_ERR_UNSUPPORTED_MODE
      The transfer mode is not supported by the BLOB Transfer Server model.

enumerator BT_MESH_BLOB_ERR_INTERNAL
      An internal error occurred on the node.

enumerator BT_MESH_BLOB_ERR_INFO_UNAVAILABLE
      The requested information cannot be provided while the server is in the current
      phase.

enum bt_mesh_blob_io_mode
      BLOB stream interaction mode.
      Values:

      enumerator BT_MESH_BLOB_READ
          Read data from the stream.

      enumerator BT_MESH_BLOB_WRITE
          Write data to the stream.

struct bt_mesh_blob_block
      #include <blob.h> BLOB transfer data block.

Public Members
size_t size
    Block size in bytes.

off_t offset
    Offset in bytes from the start of the BLOB.

uint16_t number
    Block number.

uint16_t chunk_count
    Number of chunks in block.

uint8_t missing[DIV_ROUND_UP(0, 8)]
    Bitmap of missing chunks.

struct bt_mesh_blob_chunk
    #include <blob.h> BLOB data chunk.

Public Members

do_t offset
    Offset of the chunk data from the start of the block.

size_t size
    Chunk data size.

uint8_t *data
    Chunk data.

struct bt_mesh_blob_xfer
    #include <blob.h> BLOB transfer.

Public Members

uint64_t id
    BLOB ID.

size_t size
    Total BLOB size in bytes.

eenum bt_mesh_blob_xfer_mode mode
    BLOB transfer mode.

uint16_t chunk_size
    Base chunk size.
    May be smaller for the last chunk.
struct bt_mesh_blob_io

#include <blob.h> BLOB stream.

Public Members

int (*open)(const struct bt_mesh_blob_io *io, const struct bt_mesh_blob_xfer *xfer,
enum bt_mesh_blob_io_mode mode)
    Open callback.
    Called when the reader is opened for reading.
    Param io
        BLOB stream.
    Param xfer
        BLOB transfer.
    Param mode
        Direction of the stream (read/write).
    Return
        0 on success, or (negative) error code otherwise.

void (*close)(const struct bt_mesh_blob_io *io, const struct bt_mesh_blob_xfer *xfer)
    Close callback.
    Called when the reader is closed.
    Param io
        BLOB stream.
    Param xfer
        BLOB transfer.

int (*block_start)(const struct bt_mesh_blob_io *io, const struct bt_mesh_blob_xfer *
xfer, const struct bt_mesh_blob_block *block)
    Block start callback.
    Called when a new block is opened for sending. Each block is only sent once, and
    are always sent in increasing order. The data chunks inside a single block may
    be requested out of order and multiple times.
    Param io
        BLOB stream.
    Param xfer
        BLOB transfer.
    Param block
        Block that was started.

void (*block_end)(const struct bt_mesh_blob_io *io, const struct bt_mesh_blob_xfer *
xfer, const struct bt_mesh_blob_block *block)
    Block end callback.
    Called when the current block has been transmitted in full. No data from this block
    will be requested again, and the application data associated with this block may
    be discarded.
    Param io
        BLOB stream.
    Param xfer
        BLOB transfer.
    Param block
        Block that finished sending.
int (*wr)(const struct bt_mesh_blob_io *io, const struct bt_mesh_blob_xfer *xfer, const struct bt_mesh_blob_block *block, const struct bt_mesh_blob_chunk *chunk)

  Chunk data write callback.
  Used by the BLOB Transfer Server on incoming data.
  Each block is divided into chunks of data. This callback is called when a new chunk of data is received. Chunks may be received in any order within their block.
  If the callback returns successfully, this chunk will be marked as received, and will not be received again unless the block is restarted due to a transfer suspension.
  If the callback returns a non-zero value, the chunk remains unreceived, and the BLOB Transfer Client will attempt to resend it later.
  Note that the Client will only perform a limited number of attempts at delivering a chunk before dropping a Target node from the transfer. The number of retries performed by the Client is implementation specific.

Param io
  BLOB stream.
Param xfer
  BLOB transfer.
Param block
  Block the chunk is part of.
Param chunk
  Received chunk.
Return
  0 on success, or (negative) error code otherwise.

int (*rd)(const struct bt_mesh_blob_io *io, const struct bt_mesh_blob_xfer *xfer, const struct bt_mesh_blob_block *block, const struct bt_mesh_blob_chunk *chunk)

  Chunk data read callback.
  Used by the BLOB Transfer Client to fetch outgoing data.
  The Client calls the chunk data request callback to populate a chunk message going out to the Target nodes. The data request callback may be called out of order and multiple times for each offset, and cannot be used as an indication of progress.
  Returning a non-zero status code on the chunk data request callback results in termination of the transfer.

Param io
  BLOB stream.
Param xfer
  BLOB transfer.
Param block
  Block the chunk is part of.
Param chunk
  Chunk to get the data of. The buffer pointer to by the data member should be filled by the callback.
Return
  0 on success, or (negative) error code otherwise.

Device Firmware Update (DFU)  Bluetooth Mesh supports the distribution of firmware images across a mesh network. The Bluetooth mesh DFU subsystem implements the Bluetooth Mesh Device Firmware Update Model specification version 1.0. The implementation is in experimental state.

Bluetooth Mesh DFU implements a distribution mechanism for firmware images, and does not put any restrictions on the size, format or usage of the images. The primary design goal of the
subsystem is to provide the qualifiable parts of the Bluetooth Mesh DFU specification, and leave
the usage, firmware validation and deployment to the application.

The DFU specification is implemented in the Zephyr Bluetooth Mesh DFU subsystem as three
separate models:

**Firmware Update Server**  The Firmware Update Server model implements the Target node
functionality of the Device Firmware Update (DFU) subsystem. It extends the BLOB Transfer
Server, which it uses to receive the firmware image binary from the Distributor node.

Together with the extended BLOB Transfer Server model, the Firmware Update Server model im-
plements all the required functionality for receiving firmware updates over the mesh network,
but does not provide any functionality for storing, applying or verifying the images.

**Firmware images**  The Firmware Update Server holds a list of all the updatable firmware images
on the device. The full list shall be passed to the server through the \_imgs parameter in
`BT_MESH_DFU_SRV_INIT`, and must be populated before the Bluetooth Mesh subsystem is started.
Each firmware image in the image list must be independently updatable, and should have its
own firmware ID.

For instance, a device with an upgradable bootloader, an application and a peripheral chip with
firmware update capabilities could have three entries in the firmware image list, each with their
own separate firmware ID.

**Receiving transfers**  The Firmware Update Server model uses a BLOB Transfer Server model
on the same element to transfer the binary image. The interaction between the Firmware Update
Server, BLOB Transfer Server and application is described below:

**Transfer check**  The transfer check is an optional pre-transfer check the application can per-
form on incoming firmware image metadata. The Firmware Update Server performs the trans-
fer check by calling the `check` callback.

The result of the transfer check is a pass/fail status return and the expected `bt_mesh_dfu_effect`.
The DFU effect return parameter will be communicated back to the Distributor, and should in-
dicate what effect the firmware update will have on the mesh state of the device.

**Composition Data and Models Metadata**  If the transfer will cause the device to change its
Composition Data or become unprovisioned, this should be communicated through the effect
parameter of the metadata check.

When the transfer will cause the Composition Data to change, and the Remote Provisioning Server
is supported, the Composition Data of the new firmware image will be represented by Compo-
sition Data Pages 128, 129, and 130. The Models Metadata of the new firmware image will be
represented by Models Metadata Page 128. Composition Data Pages 0, 1 and 2, and Models Meta-
data Page 0, will represent the Composition Data and the Models Metadata of the old firmware
image until the device is reprovisioned with Node Provisioning Protocol Interface (NPPI) proce-
dures using the Remote Provisioning Client.

The application must call functions `bt_mesh_comp_change_prepare()` and
`bt_mesh_models_metadata_change_prepare()` to store the existing Composition Data and
Models Metadata pages before booting into the firmware with the updated Composition Data
and Models Metadata. The old Composition Data will then be loaded into Composition Data
Pages 0, 1 and 2, while the Composition Data in the new firmware will be loaded into Compo-
sition Data Pages 128, 129 and 130. The Models Metadata for the old image will be loaded into
Models Metadata Page 0, and the Models Metadata for the new image will be loaded into Models
Metadata Page 128.

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Fig. 9: Bluetooth Mesh Firmware Update Server transfer
Limitation:

- It is not possible to change the Composition Data of the device and keep the device provisioned and working with the old firmware after the new firmware image is applied.

**Start**  The Start procedure prepares the application for the incoming transfer. It will contain information about which image is being updated, as well as the update metadata.

The Firmware Update Server *start* callback must return a pointer to the BLOB Writer the BLOB Transfer Server will send the BLOB to.

**BLOB transfer**  After the setup stage, the Firmware Update Server prepares the BLOB Transfer Server for the incoming transfer. The entire firmware image is transferred to the BLOB Transfer Server, which passes the image to its assigned BLOB Writer.

At the end of the BLOB transfer, the Firmware Update Server calls its *end* callback.

**Image verification**  After the BLOB transfer has finished, the application should verify the image in any way it can to ensure that it is ready for being applied. Once the image has been verified, the application calls `bt_mesh_dfu_srv_verified()`.

If the image can't be verified, the application calls `bt_mesh_dfu_srv_rejected()`.

**Applying the image**  Finally, if the image was verified, the Distributor may instruct the Firmware Update Server to apply the transfer. This is communicated to the application through the *apply* callback. The application should swap the image and start running with the new firmware. The firmware image table should be updated to reflect the new firmware ID of the updated image.

When the transfer applies to the mesh application itself, the device might have to reboot as part of the swap. This restart can be performed from inside the apply callback, or done asynchronously. After booting up with the new firmware, the firmware image table should be updated before the Bluetooth Mesh subsystem is started.

The Distributor will read out the firmware image table to confirm that the transfer was successfully applied. If the metadata check indicated that the device would become unprovisioned, the Target node is not required to respond to this check.

**API reference**

`group bt_mesh_dfu_srv`

API for the Bluetooth Mesh Firmware Update Server model.

**Defines**

`BT_MESH_DFU_SRV_INIT(_handlers, _imgs, _img_count)`

Initialization parameters for *Firmware Update Server model*.

**Parameters**

- `_handlers` – DFU handler function structure.
- `_imgs` – List of `bt_mesh_dfu_img` managed by this Server.
- `_img_count` – Number of DFU images managed by this Server.
Firmware Update Server model entry.

**Parameters**

- `_srv` – Pointer to a Firmware Update Server model instance.

**Functions**

```c
void bt_mesh_dfu_srv_verified(struct bt_mesh_dfu_srv *srv)
```

Accept the received DFU transfer.

Should be called at the end of a successful DFU transfer.

If the DFU transfer completes successfully, the application should verify the image validity (including any image authentication or integrity checks), and call this function if the image is ready to be applied.

**Parameters**

- `srv` – Firmware Update Server instance.

```c
void bt_mesh_dfu_srv_rejected(struct bt_mesh_dfu_srv *srv)
```

Reject the received DFU transfer.

Should be called at the end of a successful DFU transfer.

If the DFU transfer completes successfully, the application should verify the image validity (including any image authentication or integrity checks), and call this function if one of the checks fail.

**Parameters**

- `srv` – Firmware Update Server instance.

```c
void bt_mesh_dfu_srv_cancel(struct bt_mesh_dfu_srv *srv)
```

Cancel the ongoing DFU transfer.

**Parameters**

- `srv` – Firmware Update Server instance.

```c
void bt_mesh_dfu_srv_applied(struct bt_mesh_dfu_srv *srv)
```

Confirm that the received DFU transfer was applied.

Should be called as a result of the `bt_mesh_dfu_srv_cb::apply` callback.

**Parameters**

- `srv` – Firmware Update Server instance.

```c
bool bt_mesh_dfu_srv_is_busy(const struct bt_mesh_dfu_srv *srv)
```

Check if the Firmware Update Server is busy processing a transfer.

**Parameters**

- `srv` – Firmware Update Server instance.

**Returns**

- `true` if a DFU procedure is in progress, false otherwise.

```c
uint8_t bt_mesh_dfu_srv_progress(const struct bt_mesh_dfu_srv *srv)
```

Get the progress of the current DFU procedure, in percent.

**Parameters**

- `srv` – Firmware Update Server instance.
Returns
The current transfer progress in percent.

struct bt_mesh_dfu_srv_cb
#include <dfu_srv.h> Firmware Update Server event callbacks.

Public Members

int (*check)(struct bt_mesh_dfu_srv *srv, const struct bt_mesh_dfu_img *img, struct net_buf_simple *metadata, enum bt_mesh_dfu_effect *effect)
Transfer check callback.
The transfer check can be used to validate the incoming transfer before it starts. The contents of the metadata is implementation specific, and should contain all the information the application needs to determine whether this image should be accepted, and what the effect of the transfer would be.
If applying the image will have an effect on the provisioning state of the mesh stack, this can be communicated through the effect return parameter.
The metadata check can be performed both as part of starting a new transfer and as a separate procedure.
This handler is optional.

Param srv
Firmware Update Server instance.

Param img
DFU image the metadata check is performed on.

Param metadata
Image metadata.

Param effect
Return parameter for the image effect on the provisioning state of the mesh stack.

Return
0 on success, or (negative) error code otherwise.

int (*start)(struct bt_mesh_dfu_srv *srv, const struct bt_mesh_dfu_img *img, struct net_buf_simple *metadata, const struct bt_mesh_blob_io **io)
Transfer start callback.
Called when the Firmware Update Server is ready to start a new DFU transfer. The application must provide an initialized BLOB stream to be used during the DFU transfer.
The following error codes are treated specially, and should be used to communicate these issues:
• -ENOMEM: The device cannot fit this image.
• -EBUSY: The application is temporarily unable to accept the transfer.
• -EALREADY: The device has already received and verified this image, and there's no need to transfer it again. The Firmware Update model will skip the transfer phase, and mark the image as verified.
This handler is mandatory.

Param srv
Firmware Update Server instance.

Param img
DFU image being updated.

Param metadata
Image metadata.
**Param io**
BLOB stream return parameter. Must be set to a valid BLOB stream by the callback.

**Return**
0 on success, or (negative) error code otherwise. Return codes -ENOMEM, -EBUSY -EALREADY will be passed to the updater, other error codes are reported as internal errors.

```c
void (*end)(struct bt_mesh_dfu_srv *srv, const struct bt_mesh_dfu_img *img, bool success)
```
Transfer end callback.

This handler is optional.

If the transfer is successful, the application should verify the firmware image, and call either `bt_mesh_dfu_srv_verified` or `bt_mesh_dfu_srv_rejected` depending on the outcome.

If the transfer fails, the Firmware Update Server will be available for new transfers immediately after this function returns.

**Param srv**
Firmware Update Server instance.

**Param img**
DFU image that failed the update.

**Param success**
Whether the DFU transfer was successful.

```c
int (*recover)(struct bt_mesh_dfu_srv *srv, const struct bt_mesh_dfu_img *img, const struct bt_mesh_blob_io **io)
```
Transfer recovery callback.

If the device reboots in the middle of a transfer, the Firmware Update Server calls this function when the Bluetooth Mesh subsystem is started.

This callback is optional, but transfers will not be recovered after a reboot without it.

**Param srv**
Firmware Update Server instance.

**Param img**
DFU image being updated.

**Param io**
BLOB stream return parameter. Must be set to a valid BLOB stream by the callback.

**Return**
0 on success, or (negative) error code to abandon the transfer.

```c
int (*apply)(struct bt_mesh_dfu_srv *srv, const struct bt_mesh_dfu_img *img)
```
Transfer apply callback.

Called after a transfer has been validated, and the updater sends an apply message to the Target nodes.

This handler is optional.

**Param srv**
Firmware Update Server instance.

**Param img**
DFU image that should be applied.

**Return**
0 on success, or (negative) error code otherwise.
struct bt_mesh_dfu_srv
    #include <dfu_srv.h> Firmware Update Server instance.
    Should be initialized with BT_MESH_DFU_SRV_INIT.

Public Members

struct bt_mesh_blob_srv blob
    Underlying BLOB Transfer Server.

const struct bt_mesh_dfu_srv_cb *cb
    Callback structure.

const struct bt_mesh_dfu_img *imgs
    List of updatable images.

size_t img_count
    Number of updatable images.

**Firmware Update Client** The Firmware Update Client is responsible for distributing firmware updates through the mesh network. The Firmware Update Client uses the *BLOB Transfer Client* as a transport for its transfers.

**API reference**

*group* bt_mesh_dfu_cli
    API for the Bluetooth Mesh Firmware Update Client model.

**Defines**

**BT_MESH_DFU_CLI_INIT(_handlers)**
    Initialization parameters for the Firmware Update Client model.

**See also:**

*bt_mesh_dfu_cli_cb*.

**Parameters**

• _handlers – Handler callback structure.

**BT_MESH_MODEL_DFU_CLI(_cli)**
    Firmware Update Client model Composition Data entry.

**Parameters**

• _cli – Pointer to a Firmware Update Client model instance.
### Typedefs

typedef enum bt_mesh_dfu_iter (*bt_mesh_dfu_img_cb_t)(struct bt_mesh_dfu_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t idx, uint8_t total, const struct bt_mesh_dfu_img *img, void *cb_data)

DFU image callback.
The image callback is called for every DFU image on the Target node when calling `bt_mesh_dfu_cli_imgs_get`.

**Param cli**
Firmware Update Client model instance.

**Param ctx**
Message context of the received message.

**Param idx**
Image index.

**Param total**
Total number of images on the Target node.

**Param img**
Image information for the given image index.

**Param cb_data**
Callback data.

**Retval BT_MESH_DFU_ITER_STOP**
Stop iterating through the image list and return from `bt_mesh_dfu_cli_imgs_get`.

**Retval BT_MESH_DFU_ITER_CONTINUE**
Continue iterating through the image list if any images remain.

### Functions

```c
int bt_mesh_dfu_cli_send(struct bt_mesh_dfu_cli *cli, const struct bt_mesh_blob_cli_inputs *inputs, const struct bt_mesh_blob_io *io, const struct bt_mesh_dfu_cli_xfer *xfer)
```

Start distributing a DFU.

Starts distribution of the firmware in the given slot to the list of DFU Target nodes in `ctx`. The transfer runs in the background, and its end is signalled through the `bt_mesh_dfu_cli_cb::ended` callback.

**Note:** The BLOB Transfer Client transfer inputs target's list must point to a list of `bt_mesh_dfu_target` nodes.

### Parameters

- **cli** – Firmware Update Client model instance.
- **inputs** – BLOB Transfer Client transfer inputs.
- **io** – BLOB stream to read BLOB from.
- **xfer** – Firmware Update Client transfer parameters.

### Returns

0 on success, or (negative) error code otherwise.
int bt_mesh_dfu_cli_suspend(struct bt_mesh_dfu_cli *cli)
Suspend a DFU transfer.

Parameters
• cli – Firmware Update Client instance.

Returns
0 on success, or (negative) error code otherwise.

int bt_mesh_dfu_cli_resume(struct bt_mesh_dfu_cli *cli)
Resume the suspended transfer.

Parameters
• cli – Firmware Update Client instance.

Returns
0 on success, or (negative) error code otherwise.

int bt_mesh_dfu_cli_cancel(struct bt_mesh_dfu_cli *cli, struct bt_mesh_msg_ctx *ctx)
Cancel a DFU transfer.

Will cancel the ongoing DFU transfer, or the transfer on a specific Target node if ctx is valid.

Parameters
• cli – Firmware Update Client model instance.
• ctx – Message context, or NULL to cancel the ongoing DFU transfer.

Returns
0 on success, or (negative) error code otherwise.

int bt_mesh_dfu_cli_apply(struct bt_mesh_dfu_cli *cli)
Apply the completed DFU transfer.

A transfer can only be applied after it has ended successfully. The Firmware Update Client's applied callback is called at the end of the apply procedure.

Parameters
• cli – Firmware Update Client model instance.

Returns
0 on success, or (negative) error code otherwise.

int bt_mesh_dfu_cli_confirm(struct bt_mesh_dfu_cli *cli)
Confirm that the active transfer has been applied on the Target nodes.

A transfer can only be confirmed after it has been applied. The Firmware Update Client's confirmed callback is called at the end of the confirm procedure.

Target nodes that have reported the effect as BT_MESH_DFU_EFFECT_UNPROV are expected to not respond to the query, and will fail if they do.

Parameters
• cli – Firmware Update Client model instance.

Returns
0 on success, or (negative) error code otherwise.

uint8_t bt_mesh_dfu_cli_progress(struct bt_mesh_dfu_cli *cli)
Get progress as a percentage of completion.

Parameters
• cli – Firmware Update Client model instance.
Returns
The progress of the current transfer in percent, or 0 if no transfer is active.

bool bt_mesh_dfu_cli_is_busy(struct bt_mesh_dfu_cli *cli)
Check whether a DFU transfer is in progress.

Parameters
• cli – Firmware Update Client model instance.

Returns
ture if the BLOB Transfer Client is currently participating in a transfer, false otherwise.

int bt_mesh_dfu_cli_imgs_get(struct bt_mesh_dfu_cli *cli, struct bt_mesh_msg_ctx *ctx,
bt_mesh_dfu_img_cb_t cb, void *cb_data, uint8_t max_count)
Perform a DFU image list request.
Requests the full list of DFU images on a Target node, and iterates through them, calling
the cb for every image.
The DFU image list request can be used to determine which image index the Target
node holds its different firmwares in.
Waits for a response until the procedure timeout expires.

Parameters
• cli – Firmware Update Client model instance.
• ctx – Message context.
• cb – Callback to call for each image index.
• cb_data – Callback data to pass to cb.
• max_count – Max number of images to return.

Returns
0 on success, or (negative) error code otherwise.

int bt_mesh_dfu_cli_metadata_check(struct bt_mesh_dfu_cli *cli, struct bt_mesh_msg_ctx
*ctx, uint8_t img_idx, const struct bt_mesh_dfu_slot *slot, struct bt_mesh_dfu_metadata_status *rsp)
Perform a metadata check for the given DFU image slot.
The metadata check procedure allows the Firmware Update Client to check if a Target
node will accept a transfer of this DFU image slot, and what the effect would be.
Waits for a response until the procedure timeout expires.

Parameters
• cli – Firmware Update Client model instance.
• ctx – Message context.
• img_idx – Target node's image index to check.
• slot – DFU image slot to check for.
• rsp – Metadata status response buffer.

Returns
0 on success, or (negative) error code otherwise.
int bt_mesh_dfu_cli_status_get(struct bt_mesh_dfu_cli *cli, struct bt_mesh_msg_ctx *ctx, struct bt_mesh_dfu_target_status *rsp)

Get the status of a Target node.

**Parameters**

- `cli` – Firmware Update Client model instance.
- `ctx` – Message context.
- `rsp` – Response data buffer.

**Returns**

0 on success, or (negative) error code otherwise.

int32_t bt_mesh_dfu_cli_timeout_get(void)

Get the current procedure timeout value.

**Returns**

The configured procedure timeout.

void bt_mesh_dfu_cli_timeout_set(int32_t timeout)

Set the procedure timeout value.

**Parameters**

- `timeout` – The new procedure timeout.

struct bt_mesh_dfu_target

```
#include <dfu_cli.h> // DFU Target node.
```

**Public Members**

- `bt_mesh_blob_target blob`

  BLOB Target node.

- `uint8_t img_idx`

  Image index on the Target node.

- `uint8_t effect`

  Expected DFU effect, see `bt_mesh_dfu_effect`.

- `uint8_t status`

  Current DFU status, see `bt_mesh_dfu_status`.

- `uint8_t phase`

  Current DFU phase, see `bt_mesh_dfu_phase`.

struct bt_mesh_dfu_metadata_status

```
#include <dfu_cli.h> // Metadata status response.
```

**Public Members**

- `uint8_t idx`

  Image index.
enum \texttt{bt\_mesh\_dfu\_status} \texttt{status}  
\hspace{1em} Status code.

enum \texttt{bt\_mesh\_dfu\_effect} \texttt{effect}  
\hspace{1em} Effect of transfer.

\textbf{struct} \texttt{bt\_mesh\_dfu\_target\_status}  
\hspace{1em} \texttt{#include <dfu\_cli.h>} DFU Target node status parameters.

\textbf{Public Members}

enum \texttt{bt\_mesh\_dfu\_status} \texttt{status}  
\hspace{1em} Status of the previous operation.

enum \texttt{bt\_mesh\_dfu\_phase} \texttt{phase}  
\hspace{1em} Phase of the current DFU transfer.

enum \texttt{bt\_mesh\_dfu\_effect} \texttt{effect}  
\hspace{1em} The effect the update will have on the Target device's state.

\texttt{uint64\_t} \texttt{blob\_id}  
\hspace{1em} BLOB ID used in the transfer.

\texttt{uint8\_t} \texttt{img\_idx}  
\hspace{1em} Image index to transfer.

\texttt{uint8\_t} \texttt{ttl}  
\hspace{1em} TTL used in the transfer.

\texttt{uint16\_t} \texttt{timeout\_base}  
\hspace{1em} Additional response time for the Target nodes, in 10-second increments.  
\hspace{1em} The extra time can be used to give the Target nodes more time to respond to messages from the Client. The actual timeout will be calculated according to the following formula:

\begin{verbatim}
* timeout = 20 \text{ seconds} + (10 \text{ seconds} \times \text{timeout\_base}) + (100 \text{ ms} \times \text{TTL})
* 
\end{verbatim}

If a Target node fails to respond to a message from the Client within the configured transfer timeout, the Target node is dropped.

\textbf{struct} \texttt{bt\_mesh\_dfu\_cli\_cb}  
\hspace{1em} \texttt{#include <dfu\_cli.h>} Firmware Update Client event callbacks.

\textbf{Public Members}
void (*suspended)(struct bt_mesh_dfu_cli *cli)
BLOB transfer is suspended.
Called when the BLOB transfer is suspended due to response timeout from all Target nodes.
  **Param cli**
  Firmware Update Client model instance.

void (*ended)(struct bt_mesh_dfu_cli *cli, enum bt_mesh_dfu_status reason)
DFU ended.
Called when the DFU transfer ends, either because all Target nodes were lost or because the transfer was completed successfully.
  **Param cli**
  Firmware Update Client model instance.
  **Param reason**
  Reason for ending.

void (*applied)(struct bt_mesh_dfu_cli *cli)
DFU transfer applied on all active Target nodes.
Called at the end of the apply procedure started by `bt_mesh_dfu_cli_apply`.
  **Param cli**
  Firmware Update Client model instance.

void (*confirmed)(struct bt_mesh_dfu_cli *cli)
DFU transfer confirmed on all active Target nodes.
Called at the end of the apply procedure started by `bt_mesh_dfu_cli_confirm`.
  **Param cli**
  Firmware Update Client model instance.

void (*lost_target)(struct bt_mesh_dfu_cli *cli, struct bt_mesh_dfu_target *target)
DFU Target node was lost.
A DFU Target node was dropped from the receivers list. The Target node’s status is set to reflect the reason for the failure.
  **Param cli**
  Firmware Update Client model instance.
  **Param target**
  DFU Target node that was lost.

struct bt_mesh_dfu_cli
#include <dfu_cli.h> Firmware Update Client model instance.
Should be initialized with `BT_MESH_DFU_CLI_INIT`.

**Public Members**

const struct bt_mesh_dfu_cli_cb *cb
Callback structure.

struct bt_mesh_blob_cli blob
Underlying BLOB Transfer Client.
struct bt_mesh_dfu_cli_xfer_blob_params
    #include <dfu_cli.h> BLOB parameters for Firmware Update Client transfer:

Public Members

uint16_t chunk_size
    Base chunk size.
    May be smaller for the last chunk.

struct bt_mesh_dfu_cli_xfer
    #include <dfu_cli.h> Firmware Update Client transfer parameters:

Public Members

uint64_t blob_id
    BLOB ID to use for this transfer, or 0 to set it randomly.

const struct bt_mesh_dfu_slot *slot
    DFU image slot to transfer.

enum bt_mesh_blob_xfer_mode mode
    Transfer mode (Push (Push BLOB Transfer Mode) or Pull (Pull BLOB Transfer Mode))

const struct bt_mesh_dfu_cli_xfer_blob_params *blob_params
    BLOB parameters to be used for the transfer, or NULL to retrieve Target nodes’ capabilities before sending a firmware.

Firmware Distribution Server  The Firmware Distribution Server model implements the Distributor role for the Device Firmware Update (DFU) subsystem. It extends the BLOB Transfer Server, which it uses to receive the firmware image binary from the Initiator node. It also instantiates a Firmware Update Client, which it uses to distribute firmware updates throughout the mesh network.

Note:  Currently, the Firmware Distribution Server supports out-of-band (OOB) retrieval of firmware images over SMP service only.

The Firmware Distribution Server does not have an API of its own, but relies on a Firmware Distribution Client model on a different device to give it information and trigger image distribution and upload.

Firmware slots  The Firmware Distribution Server is capable of storing multiple firmware images for distribution. Each slot contains a separate firmware image with metadata, and can be distributed to other mesh nodes in the network in any order. The contents, format and size of the firmware images are vendor specific, and may contain data from other vendors. The application should never attempt to execute or modify them.
The slots are managed remotely by a Firmware Distribution Client, which can both upload new slots and delete old ones. The application is notified of changes to the slots through the Firmware Distribution Server’s callbacks (bt_mesh_fd_srv_cb). While the metadata for each firmware slot is stored internally, the application must provide a BLOB streams for reading and writing the firmware image.

API reference

group bt_mesh_dfd_srv
  API for the Firmware Distribution Server model.

Defines

CONFIG_BT_MESH_DFD_SRV_TARGETS_MAX
CONFIG_BT_MESH_DFD_SRV_SLOT_MAX_SIZE
CONFIG_BT_MESH_DFD_SRV_SLOT_SPACE

BT_MESH_DFD_SRV_INIT(_cb)
  Initialization parameters for the Firmware Distribution Server model.

  Parameters
  • _cb – [in] Pointer to a bt_mesh_dfd_srv_cb instance.

BT_MESH_MODEL_DFD_SRV(_srv)
  Firmware Distribution Server model Composition Data entry.

  Parameters
  • _srv – Pointer to a Firmware Distribution Server model instance.

#include <dfd_srv.h>

Firmware Distribution Server callbacks:

Public Members

int (*recv)(struct bt_mesh_dfd_srv *srv, const struct bt_mesh_dfu_slot *slot, const struct bt_mesh_blob_io **io)
  Slot receive callback.

  Called at the start of an upload procedure. The callback must fill io with a pointer to a writable BLOB stream for the Firmware Distribution Server to write the firmware image to.

  **Param srv**
  Firmware Distribution Server model instance.

  **Param slot**
  DFU image slot being received.

  **Param io**
  BLOB stream response pointer.

  **Return**
  0 on success, or (negative) error code otherwise.
void (*del)(struct bt_mesh_dfd_srv *srv, const struct bt_mesh_dfu_slot *slot)
    Slot delete callback.
    Called when the Firmware Distribution Server is about to delete a DFU image slot.
    All allocated data associated with the firmware slot should be deleted.
    Param srv
        Firmware Update Server instance.
    Param slot
        DFU image slot being deleted.

int (*send)(struct bt_mesh_dfd_srv *srv, const struct bt_mesh_dfu_slot *slot, const
    struct bt_mesh_blob_io **io)
    Slot send callback.
    Called at the start of a distribution procedure. The callback must fill io with a
    pointer to a readable BLOB stream for the Firmware Distribution Server to read
    the firmware image from.
    Param srv
        Firmware Distribution Server model instance.
    Param slot
        DFU image slot being sent.
    Param io
        BLOB stream response pointer.
    Return
        0 on success, or (negative) error code otherwise.

void (*phase)(struct bt_mesh_dfd_srv *srv, enum bt_mesh_dfd_phase phase)
    Phase change callback (Optional).
    Called whenever the phase of the Firmware Distribution Server changes.
    Param srv
        Firmware Distribution Server model instance.
    Param phase
        New Firmware Distribution phase.

struct bt_mesh_dfd_srv
    #include <dfd_srv.h> Firmware Distribution Server instance.

Overview

**DFU roles** The Bluetooth Mesh DFU subsystem defines three different roles the mesh nodes
have to assume in the distribution of firmware images:

**Target node** Target node is the receiver and user of the transferred firmware images. All its functionality
is implemented by the Firmware Update Server model. A transfer may be targeting any
number of Target nodes, and they will all be updated concurrently.

**Distributor** The Distributor role serves two purposes in the DFU process. First, it's acting as the Target
node in the Upload Firmware procedure, then it distributes the uploaded image to other
Target nodes as the Distributor. The Distributor does not select the parameters of the trans-
fer, but relies on an Initiator to give it a list of Target nodes and transfer parameters. The
Distributor functionality is implemented in two models, Firmware Distribution Server and
Firmware Update Client. The Firmware Distribution Server is responsible for communicat-
ing with the Initiator, and the Firmware Update Client is responsible for distributing the
image to the Target nodes.
**Initiator**

The Initiator role is typically implemented by the same device that implements the Bluetooth Mesh *Provisioner* and *Configurator* roles. The Initiator needs a full overview of the potential Target nodes and their firmware, and will control (and initiate) all firmware updates. The Initiator role is not implemented in the Zephyr Bluetooth Mesh DFU subsystem.

![DFU roles and the associated Bluetooth Mesh models](image)

**Fig. 10: DFU roles and the associated Bluetooth Mesh models**

Bluetooth Mesh applications may combine the DFU roles in any way they'd like, and even take on multiple instances of the same role by instantiating the models on separate elements. For instance, the Distributor and Initiator role can be combined by instantiating the *Firmware Update Client* on the Initiator node and calling its API directly.

It's also possible to combine the Initiator and Distributor devices into a single device, and replace the Firmware Distribution Server model with a proprietary mechanism that will access the Firmware Update Client model directly, e.g. over a serial protocol.

---

**Note:** All DFU models instantiate one or more *BLOB Transfer models*, and may need to be spread over multiple elements for certain role combinations.

---

**Stages**

The Bluetooth Mesh DFU process is designed to act in three stages:

**Upload stage**

First, the image is uploaded to a Distributor in a mesh network by an external entity, such as a phone or gateway (the Initiator). During the Upload stage, the Initiator transfers the firmware image and all its metadata to the Distributor node inside the mesh network. The Distributor stores the firmware image and its metadata persistently, and awaits further instructions from the Initiator. The time required to complete the upload process depends on the size of the image. After the upload completes, the Initiator can disconnect from the network during the much more time-consuming Distribution stage. Once the firmware has been uploaded to the Distributor, the Initiator may trigger the Distribution stage at any time.
**Firmware Capability Check stage (optional)**
Before starting the Distribution stage, the Initiator may optionally check if Target nodes can accept the new firmware. Nodes that do not respond, or respond that they can’t receive the new firmware, are excluded from the firmware distribution process.

**Distribution stage**
Before the firmware image can be distributed, the Initiator transfers the list of Target nodes and their designated firmware image index to the Distributor. Next, it tells the Distributor to start the firmware distribution process, which runs in the background while the Initiator and the mesh network perform other duties. Once the firmware image has been transferred to the Target nodes, the Distributor may ask them to apply the firmware image immediately and report back with their status and new firmware IDs.

**Firmware images**
All updatable parts of a mesh node’s firmware should be represented as a firmware image. Each Target node holds a list of firmware images, each of which should be independently updatable and identifiable.

Firmware images are represented as a BLOB (the firmware itself) with the following additional information attached to it:

**Firmware ID**
The firmware ID is used to identify a firmware image. The Initiator node may ask the Target nodes for a list of its current firmware IDs to determine whether a newer version of the firmware is available. The format of the firmware ID is vendor specific, but generally, it should include enough information for an Initiator node with knowledge of the format to determine the type of image as well as its version. The firmware ID is optional, and its maximum length is determined by `CONFIG_BT_MESH_DFU_FWID_MAXLEN`.

**Firmware metadata**
The firmware metadata is used by the Target node to determine whether it should accept an incoming firmware update, and what the effect of the update would be. The metadata format is vendor specific, and should contain all information the Target node needs to verify the image, as well as any preparation the Target node has to make before the image is applied. Typical metadata information can be image signatures, changes to the node’s Composition Data and the format of the BLOB. The Target node may perform a metadata check before accepting incoming transfers to determine whether the transfer should be started. The firmware metadata can be discarded by the Target node after the metadata check, as other nodes will never request the metadata from the Target node. The firmware metadata is optional, and its maximum length is determined by `CONFIG_BT_MESH_DFU_METADATA_MAXLEN`.

The Bluetooth Mesh DFU subsystem in Zephyr provides its own metadata format (`bt_mesh_dfu_metadata`) together with a set of related functions that can be used by an end product. The support for it is enabled using the `CONFIG_BT_MESH_DFU_METADATA` option. The format of the metadata is presented in the table below.
Field | Size (Bytes) | Description |
--- | --- | --- |
New firmware version | 8 B | 1 B: Major version 1 B: Minor version 2 B: Revision 4 B: Build number |
New firmware size | 3 B | Size in bytes for a new firmware |
New firmware core type | 1 B | Bit field: Bit 0: Application core Bit 1: Network core Bit 2: Applications specific BLOB. Other bits: RFU |
Hash of incoming composition data | 4 B (Optional) | Lower 4 octets of AES-CMAC (app-specific-key, composition data). This field is present, if Bit 0 is set in the New firmware core type field. |
New number of elements | 2 B (Optional) | Number of elements on the node after firmware is applied. This field is present, if Bit 0 is set in the New firmware core type field. |
Application-specific data for new firmware | <variable> (Optional) | Application-specific data to allow application to execute some vendor-specific behaviors using this data before it can respond with a status message. |

**Firmware URI**

The firmware URI gives the Initiator information about where firmware updates for the image can be found. The URI points to an online resource the Initiator can interact with to get new versions of the firmware. This allows Initiators to perform updates for any node in the mesh network by interacting with the web server pointed to in the URI. The URI must point to a resource using the http or https schemes, and the targeted web server must behave according to the Firmware Check Over HTTPS procedure defined by the specification. The firmware URI is optional, and its max length is determined by CONFIG_BT_MESH_DFU_URI_MAXLEN.

**Note:** The out-of-band distribution mechanism is not supported.

**Firmware effect** A new image may have the Composition Data Page 0 different from the one allocated on a Target node. This may have an effect on the provisioning data of the node and how the Distributor finalizes the DFU. Depending on the availability of the Remote Provisioning Server model on the old and new image, the device may either boot up unprovisioned after applying the new firmware or require to be re-provisioned. The complete list of available options is defined in bt_mesh_dfu_effect:

- **BT_MESH_DFU_EFFECT_NONE** The device stays provisioned after the new firmware is programmed. This effect is chosen if the composition data of the new firmware doesn’t change.
- **BT_MESH_DFU_EFFECT_COMP_CHANGE_NO_RPR** This effect is chosen when the composition data changes and the device doesn’t support the remote provisioning. The new composition data takes place only after re-provisioning.
- **BT_MESH_DFU_EFFECT_COMP_CHANGE** This effect is chosen when the composition data changes and the device supports the remote provisioning. In this case, the device stays provisioned and the new composition data takes place after re-provisioning using the Remote Provisioning models.
- **BT_MESH_DFU_EFFECT_UNPROV** This effect is chosen if the composition data in the new firmware changes, the device doesn’t support the remote provisioning, and the new composition data takes effect after applying the firmware.
When the Target node receives the Firmware Update Firmware Metadata Check message, the Firmware Update Server model calls the `bt_mesh_dfu_srv_cb.check` callback, the application can then process the metadata and provide the effect value. If the effect is `BT_MESH_DFU_EFFECT_COMP_CHANGE`, the application must call functions `bt_mesh_comp_change_prepare()` and `bt_mesh_models_metadata_change_prepare()` to prepare the Composition Data Page and Models Metadata Page contents before applying the new firmware image. See Composition Data and Models Metadata for more information.

**DFU procedures** The DFU protocol is implemented as a set of procedures that must be performed in a certain order:

The Initiator controls the Upload stage of the DFU protocol, and all Distributor side handling of the upload subprocedures is implemented in the Firmware Distribution Server.

The Distribution stage is controlled by the Distributor, as implemented by the Firmware Update Client. The Target node implements all handling of these procedures in the Firmware Update Server, and notifies the application through a set of callbacks.

**Uploading the firmware** The Upload Firmware procedure uses the BLOB Transfer models to transfer the firmware image from the Initiator to the Distributor. The Upload Firmware procedure works in two steps:

1. The Initiator generates a BLOB ID, and sends it to the Distributor's Firmware Distribution Server along with the firmware information and other input parameters of the BLOB transfer. The Firmware Distribution Server stores the information, and prepares its BLOB Transfer Server for the incoming transfer before it responds with a status message to the Initiator.

2. The Initiator's BLOB Transfer Client model transfers the firmware image to the Distributor’s BLOB Transfer Server, which stores the image in a predetermined flash partition.

When the BLOB transfer finishes, the firmware image is ready for distribution. The Initiator may upload several firmware images to the Distributor, and ask it to distribute them in any order or at any time. Additional procedures are available for querying and deleting firmware images from the Distributor.

The following Distributor's capabilities related to firmware images can be configured using the configuration options:

- `CONFIG_BT_MESH_DFU_SLOT_CNT`: Amount of image slots available on the device.
- `CONFIG_BT_MESH_DFD_SRV_SLOT_MAX_SIZE`: Maximum allowed size for each image.
- `CONFIG_BT_MESH_DFD_SRV_SLOT_SPACE`: Available space for all images.

**Populating the Distributor’s receivers list** Before the Distributor can start distributing the firmware image, it needs a list of Target nodes to send the image to. The Initiator gets the full list of Target nodes either by querying the potential targets directly, or through some external authority. The Initiator uses this information to populate the Distributor’s receivers list with the address and relevant firmware image index of each Target node. The Initiator may send one or more Firmware Distribution Receivers Add messages to build the Distributor's receivers list, and a Firmware Distribution Receivers Delete All message to clear it.

The maximum number of receivers that can be added to the Distributor is configured through the `CONFIG_BT_MESH_DFD_SRV_TARGETS_MAX` configuration option.

**Initiating the distribution** Once the Distributor has stored a firmware image and received a list of Target nodes, the Initiator may initiate the distribution procedure. The BLOB transfer parameters for the distribution are passed to the Distributor along with an update policy. The update policy decides whether the Distributor should request that the firmware is applied on
Fig. 11: DFU stages and procedures as seen from the Distributor
the Target nodes or not. The Distributor stores the transfer parameters and starts distributing
the firmware image to its list of Target nodes.

**Firmware distribution**  The Distributor's Firmware Update Client model uses its BLOB Trans-
fer Client model's broadcast subsystem to communicate with all Target nodes. The firmware
distribution is performed with the following steps:

1. The Distributor's Firmware Update Client model generates a BLOB ID and sends it to each
   Target node's Firmware Update Server model, along with the other BLOB transfer param-
   eters, the Target node firmware image index and the firmware image metadata. Each Target
   node performs a metadata check and prepares their BLOB Transfer Server model for the
   transfer, before sending a status response to the Firmware Update Client, indicating if the
   firmware update will have any effect on the Bluetooth Mesh state of the node.

2. The Distributor's BLOB Transfer Client model transfers the firmware image to all Target
   nodes.

3. Once the BLOB transfer has been received, the Target nodes' applications verify that the
   firmware is valid by performing checks such as signature verification or image checksums
   against the image metadata.

4. The Distributor's Firmware Update Client model queries all Target nodes to ensure that
   they've all verified the firmware image.

If the distribution procedure completed with at least one Target node reporting that the image
has been received and verified, the distribution procedure is considered successful.

---

**Note:** The firmware distribution procedure only fails if all Target nodes are lost. It is up to
the Initiator to request a list of failed Target nodes from the Distributor and initiate additional
attempts to update the lost Target nodes after the current attempt is finished.

---

**Suspending the distribution**  The Initiator can also request the Distributor to suspend the
firmware distribution. In this case, the Distributor will stop sending any messages to Target
nodes. When the firmware distribution is resumed, the Distributor will continue sending the
firmware from the last successfully transferred block.

**Applying the firmware image**  If the Initiator requested it, the Distributor can initiate the Ap-
ply Firmware on Target Node procedure on all Target nodes that successfully received and ver-
ified the firmware image. The Apply Firmware on Target Node procedure takes no parameters,
and to avoid ambiguity, it should be performed before a new transfer is initiated. The Apply
Firmware on Target Node procedure consists of the following steps:

1. The Distributor's Firmware Update Client model instructs all Target nodes that have ver-
   ified the firmware image to apply it. The Target nodes' Firmware Update Server models
   respond with a status message before calling their application's apply callback.

2. The Target node's application performs any preparations needed before applying the trans-
   fer, such as storing a snapshot of the Composition Data or clearing its configuration.

3. The Target node's application swaps the current firmware with the new image and updates
   its firmware image list with the new firmware ID.

4. The Distributor's Firmware Update Client model requests the full list of firmware images
   from each Target node, and scans through the list to make sure that the new firmware ID
   has replaced the old.

---

**Note:** During the metadata check in the distribution procedure, the Target node may have
reported that it will become unprovisioned after the firmware image is applied. In this case, the
Distributor’s Firmware Update Client model will send a request for the full firmware image list, and expect no response.

Cancelling the distribution The firmware distribution can be cancelled at any time by the Initiator. In this case, the Distributor starts the cancelling procedure by sending a cancelling message to all Target nodes. The Distributor waits for the response from all Target nodes. Once all Target nodes have replied, or the request has timed out, the distribution procedure is cancelled. After this the distribution procedure can be started again from the Firmware distribution section.

API reference This section lists the types common to the Device Firmware Update mesh models.

group bt_mesh_dfd

Enums

enum bt_mesh_dfd_status
   Firmware distribution status.
   Values:

   enumerator BT_MESH_DFD_SUCCESS
      The message was processed successfully.

   enumerator BT_MESH_DFD_ERR_INSUFFICIENT_RESOURCES
      Insufficient resources on the node.

   enumerator BT_MESH_DFD_ERR_WRONG_PHASE
      The operation cannot be performed while the Server is in the current phase.

   enumerator BT_MESH_DFD_ERR_INTERNAL
      An internal error occurred on the node.

   enumerator BT_MESH_DFD_ERR_FW_NOT_FOUND
      The requested firmware image is not stored on the Distributor.

   enumerator BT_MESH_DFD_ERR_INVALID_APPKEY_INDEX
      The AppKey identified by the AppKey Index is not known to the node.

   enumerator BT_MESH_DFD_ERR_RECEIVERS_LIST_EMPTY
      There are no Target nodes in the Distribution Receivers List state.

   enumerator BT_MESH_DFD_ERR_BUSY_WITH_DISTRIBUTION
      Another firmware image distribution is in progress.

   enumerator BT_MESH_DFD_ERR_BUSY_WITH_UPLOAD
      Another upload is in progress.
enumerator BT_MESH_DFD_ERR_URI_NOT_SUPPORTED
   The URI scheme name indicated by the Update URI is not supported.

enumerator BT_MESH_DFD_ERR_URI_MALFORMED
   The format of the Update URI is invalid.

enumerator BT_MESH_DFD_ERR_URI_UNREACHABLE
   The URI is currently unreachable.

enumerator BT_MESH_DFD_ERR_NEW_FW_NOT_AVAILABLE
   The Check Firmware OOB procedure did not find any new firmware.

enumerator BT_MESH_DFD_ERR_SUSPEND_FAILED
   The suspension of the Distribute Firmware procedure failed.

enum bt_mesh_dfd_phase
   Firmware distribution phases.
   Values:

   enumerator BT_MESH_DFD_PHASE_IDLE
      No firmware distribution is in progress.

   enumerator BT_MESH_DFD_PHASE_TRANSFER_ACTIVE
      Firmware distribution is in progress.

   enumerator BT_MESH_DFD_PHASE_TRANSFER_SUCCESS
      The Transfer BLOB procedure has completed successfully.

   enumerator BT_MESH_DFD_PHASE_APPLYING_UPDATE
      The Apply Firmware on Target Nodes procedure is being executed.

   enumerator BT_MESH_DFD_PHASE_COMPLETED
      The Distribute Firmware procedure has completed successfully.

   enumerator BT_MESH_DFD_PHASE_FAILED
      The Distribute Firmware procedure has failed.

   enumerator BT_MESH_DFD_PHASECANCELING_UPDATE
      The Cancel Firmware Update procedure is being executed.

   enumerator BT_MESH_DFD_PHASE_TRANSFER_SUSPENDED
      The Transfer BLOB procedure is suspended.

enum bt_mesh_dfd_upload_phase
   Firmware upload phases.
   Values:
enumerator BT_MESH_DFD_UPLOAD_PHASE_IDLE
   No firmware upload is in progress.

enumerator BT_MESH_DFD_UPLOAD_PHASE_TRANSFER_ACTIVE
   The Store Firmware procedure is being executed.

enumerator BT_MESH_DFD_UPLOAD_PHASE_TRANSFER_ERROR
   The Store Firmware procedure or Store Firmware OOB procedure failed.

enumerator BT_MESH_DFD_UPLOAD_PHASE_TRANSFER_SUCCESS
   The Store Firmware procedure or the Store Firmware OOB procedure completed successfully.

group bt_mesh_dfu

Defines

CONFIG_BT_MESH_DFU_FWID_MAXLEN

CONFIG_BT_MESH_DFU_METADATA_MAXLEN

CONFIG_BT_MESH_DFU_URI_MAXLEN

CONFIG_BT_MESH_DFU_SLOT_CNT

Enums

enum bt_mesh_dfu_phase
   DFU transfer phase.
   Values:

   enumerator BT_MESH_DFU_PHASE_IDLE
      Ready to start a Receive Firmware procedure.

   enumerator BT_MESH_DFU_PHASE_TRANSFER_ERR
      The Transfer BLOB procedure failed.

   enumerator BT_MESH_DFU_PHASE_TRANSFER_ACTIVE
      The Receive Firmware procedure is being executed.

   enumerator BT_MESH_DFU_PHASE_VERIFY
      The Verify Firmware procedure is being executed.

   enumerator BT_MESH_DFU_PHASE_VERIFY_OK
      The Verify Firmware procedure completed successfully.
enumerator BT_MESH_DFU_PHASE_VERIFY_FAIL
   The Verify Firmware procedure failed.

enumerator BT_MESH_DFU_PHASE_APPLYING
   The Apply New Firmware procedure is being executed.

enumerator BT_MESH_DFU_PHASE_TRANSFER_CANCELED
   Firmware transfer has been canceled.

enumerator BT_MESH_DFU_PHASE_APPLY_SUCCESS
   Firmware applying succeeded.

enumerator BT_MESH_DFU_PHASE_APPLY_FAIL
   Firmware applying failed.

enumerator BT_MESH_DFU_PHASE_UNKNOWN
   Phase of a node was not yet retrieved.

enum bt_mesh_dfu_status
   DFU status.
   Values:

   enumerator BT_MESH_DFU_SUCCESS
      The message was processed successfully.

   enumerator BT_MESH_DFU_ERR_RESOURCES
      Insufficient resources on the node.

   enumerator BT_MESH_DFU_ERR_WRONG_PHASE
      The operation cannot be performed while the Server is in the current phase.

   enumerator BT_MESH_DFU_ERR_INTERNAL
      An internal error occurred on the node.

   enumerator BT_MESH_DFU_ERR_FW_IDX
      The message contains a firmware index value that is not expected.

   enumerator BT_MESH_DFU_ERR_METADATA
      The metadata check failed.

   enumerator BT_MESH_DFU_ERR_TEMPORARILY_UNAVAILABLE
      The Server cannot start a firmware update.

   enumerator BT_MESH_DFU_ERR_BLOB_XFER_BUSY
      Another BLOB transfer is in progress.

enum bt_mesh_dfu_effect
   Expected effect of a DFU transfer.
   Values:
enumerator **BT_MESH_DFU_EFFECT_NONE**
No changes to node Composition Data.

enumerator **BT_MESH_DFU_EFFECT_COMP_CHANGE_NO_RPR**
Node Composition Data changed and the node does not support remote provisioning.

enumerator **BT_MESH_DFU_EFFECT_COMP_CHANGE**
Node Composition Data changed, and remote provisioning is supported.
The node supports remote provisioning and Composition Data Page 0x80. Page 0x80 contains different Composition Data than Page 0x0.

enumerator **BT_MESH_DFU_EFFECT_UNPROV**
Node will be unprovisioned after the update.

**enum bt_mesh_dfu_iter**
Action for DFU iteration callbacks.

*Values:*

enumerator **BT_MESH_DFU_ITER_STOP**
Stop iterating.

enumerator **BT_MESH_DFU_ITER_CONTINUE**
Continue iterating.

**struct bt_mesh_dfu_img**

#include <dfu.h>  DFU image instance.
Each DFU image represents a single updatable firmware image.

**Public Members**

const void *fwid
Firmware ID.

size_t fwid_len
Length of the firmware ID.

const char *uri
Update URI, or NULL.

**struct bt_mesh_dfu_slot**

#include <dfu.h>  DFU image slot for DFU distribution.

**Public Members**
size_t size
Size of the firmware in bytes.

size_t fwid_len
Length of the firmware ID.

size_t metadata_len
Length of the metadata.

uint8_t fwid[0]
Firmware ID.

uint8_t metadata[0]
Metadata.

group bt_mesh_dfu_metadata
Common types and functions for the Bluetooth Mesh DFU metadata.

Enums

gen bt_mesh_dfu_metadata_fw_core_type
Firmware core type.
Values:

enumerator BT_MESH_FW_CORE_TYPE_APP = BIT(0)
Application core.

enumerator BT_MESH_FW_CORE_TYPE_NETWORK = BIT(1)
Network core.

enumerator BT_MESH_FW_CORE_TYPE_APP_SPECIFIC_BLOB = BIT(2)
Application-specific BLOB.

Functions

int bt_mesh_dfu_metadata_decode(struct net_buf_simple *buf, struct bt_mesh_dfu_metadata *metadata)
Decode a firmware metadata from a network buffer.

Parameters

• buf – Buffer containing a raw metadata to be decoded.
• metadata – Pointer to a metadata structure to be filled.

Returns

0 on success, or (negative) error code otherwise.
int bt_mesh_dfu_metadata_encode(const struct bt_mesh_dfu_metadata *metadata, struct net_buf_simple *buf)

Encode a firmware metadata into a network buffer.

Parameters
- metadata – Firmware metadata to be encoded.
- buf – Buffer to store the encoded metadata.

Returns
0 on success, or (negative) error code otherwise.

int bt_mesh_dfu_metadata_comp_hash_get(struct net_buf_simple *buf, uint8_t *key, uint32_t *hash)

Compute hash of the Composition Data state.
The format of the Composition Data is defined in MshPRTv1.1: 4.2.2.1.

Parameters
- buf – Pointer to buffer holding Composition Data.
- key – 128-bit key to be used in the hash computation.
- hash – Pointer to a memory location to which the hash will be stored.

Returns
0 on success, or (negative) error code otherwise.

int bt_mesh_dfu_metadata_comp_hash_local_get(uint8_t *key, uint32_t *hash)

Compute hash of the Composition Data Page 0 of this device.

Parameters
- key – 128-bit key to be used in the hash computation.
- hash – Pointer to a memory location to which the hash will be stored.

Returns
0 on success, or (negative) error code otherwise.

struct bt_mesh_dfu_metadata_fw_ver
#include <dfu_metadata.h> Firmware version.

Public Members

uint8_t_t major
Firmware major version.

uint8_t_t minor
Firmware minor version.

uint16_t revision
Firmware revision.

uint32_t build_num
Firmware build number.

struct bt_mesh_dfu_metadata
#include <dfu_metadata.h> Firmware metadata.

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```c
struct bt_mesh_dfu_metadata_fw_ver
{
    uint32_t fw_ver;
    New firmware version.
}
```

```c
uint32_t fw_size
    New firmware size.
```

```c
enum bt_mesh_dfu_metadata_fw_core_type
{
    fw_core_type;
    New firmware core type.
}
```

```c
uint32_t comp_hash
    Hash of incoming Composition Data.
```

```c
uint16_t elems
    New number of node elements.
```

```c
uint8_t *user_data
    Application-specific data for new firmware.
    This field is optional.
```

```c
uint32_t user_data_len
    Length of the application-specific field.
```

Message  The Bluetooth Mesh message provides set of structures, macros and functions used
for preparing message buffers, managing message and acknowledged message contexts.

API reference

```c
group bt_mesh_msg
    Message.
```

Defines

```c
BT_MESH_MIC_SHORT
    Length of a short Mesh MIC.
```

```c
BT_MESH_MIC_LONG
    Length of a long Mesh MIC.
```

```c
BT_MESH_MODEL_OP_LEN(_op)
    Helper to determine the length of an opcode.
```

Parameters

- `_op` – Opcode.
Zephyr Project Documentation, Release 3.6.0-rc3

**BT_MESH_MODEL_BUF_LEN**(_op, _payload_len)
Helper for model message buffer length.

Returns the length of a Mesh model message buffer, including the opcode length and a short MIC.

**Parameters**
- _op – Opcode of the message.
- _payload_len – Length of the model payload.

**BT_MESH_MODEL_BUF_LEN_LONG_MIC**(_op, _payload_len)
Helper for model message buffer length.

Returns the length of a Mesh model message buffer, including the opcode length and a long MIC.

**Parameters**
- _op – Opcode of the message.
- _payload_len – Length of the model payload.

**BT_MESH_MODEL_BUF_DEFINE**(_buf, _op, _payload_len)
Define a Mesh model message buffer using NET_BUF_SIMPLE_DEFINE.

**Parameters**
- _buf – Buffer name.
- _op – Opcode of the message.
- _payload_len – Length of the model message payload.

**BT_MESH_MSG_CTX_INIT**(net_key_idx, app_key_idx, dst, ttl)
Helper for bt_mesh_msg_ctx structure initialization.

**Note:** If dst is a Virtual Address, Label UUID shall be initialized separately.

**Parameters**
- net_key_idx – NetKey Index of the subnet to send the message on. Only used if app_key_idx points to devkey.
- app_key_idx – AppKey Index to encrypt the message with.
- dst – Remote addr.
- ttl – Time To Live.

**BT_MESH_MSG_CTX_INIT_APP**(app_key_idx, dst)
Helper for bt_mesh_msg_ctx structure initialization secured with Application Key.

**Parameters**
- app_key_idx – AppKey Index to encrypt the message with.
- dst – Remote addr.

**BT_MESH_MSG_CTX_INIT_DEV**(net_key_idx, dst)
Helper for bt_mesh_msg_ctx structure initialization secured with Device Key of a remote device.

**Parameters**
- net_key_idx – NetKey Index of the subnet to send the message on.
• dst – Remote addr.

**BT_MESH_MSG_CTX_INIT_PUB***(pub)***

Helper for *bt_mesh_msg_ctx* structure initialization using Model Publication context.

**Parameters**

* • pub – Pointer to a model publication context.

**Functions**

void *bt_mesh_model_msg_init*(struct *net_buf_simple* *msg, uint32_t opcode)

Initialize a model message.

Clears the message buffer contents, and encodes the given opcode. The message buffer will be ready for filling in payload data.

**Parameters**

* • msg – Message buffer.
* • opcode – Opcode to encode.

static inline void *bt_mesh_msg_ack_ctx_init*(struct *bt_mesh_msg_ack_ctx* *ack)*

Initialize an acknowledged message context.

Initializes semaphore used for synchronization between *bt_mesh_msg_ack_ctx_wait* and *bt_mesh_msg_ack_ctx_rx* calls. Call this function before using *bt_mesh_msg_ack_ctx*.

**Parameters**

* • ack – Acknowledged message context to initialize.

static inline void *bt_mesh_msg_ack_ctx_reset*(struct *bt_mesh_msg_ack_ctx* *ack)*

Reset the synchronization semaphore in an acknowledged message context.

This function aborts call to *bt_mesh_msg_ack_ctx_wait*.

**Parameters**

* • ack – Acknowledged message context to be reset.

void *bt_mesh_msg_ack_ctx_clear*(struct *bt_mesh_msg_ack_ctx* *ack)*

Clear parameters of an acknowledged message context.

This function clears the opcode, remote address and user data set by *bt_mesh_msg_ack_ctx_prepare*.

**Parameters**

* • ack – Acknowledged message context to be cleared.

int *bt_mesh_msg_ack_ctx_prepare*(struct *bt_mesh_msg_ack_ctx* *ack, uint32_t op, uint16_t dst, void *user_data)*

Prepare an acknowledged message context for the incoming message to wait.

This function sets the opcode, remote address of the incoming message and stores the user data. Use this function before calling *bt_mesh_msg_ack_ctx_wait*.

**Parameters**

* • ack – Acknowledged message context to prepare.
* • op – The message OpCode.
* • dst – Destination address of the message.
• **user_data** – User data for the acknowledged message context.

**Returns**
0 on success, or (negative) error code on failure.

static inline bool bt_mesh_msg_ack_ctx_busy(struct bt_mesh_msg_ack_ctx *ack)
Check if the acknowledged message context is initialized with an opcode.

**Parameters**
• **ack** – Acknowledged message context.

**Returns**
true if the acknowledged message context is initialized with an opcode, false otherwise.

int bt_mesh_msg_ack_ctx_wait(struct bt_mesh_msg_ack_ctx *ack, k_timeout_t timeout)
Wait for a message acknowledge.
This function blocks execution until bt_mesh_msg_ack_ctx_rx is called or by timeout.

**Parameters**
• **ack** – Acknowledged message context of the message to wait for.
• **timeout** – Wait timeout.

**Returns**
0 on success, or (negative) error code on failure.

static inline void bt_mesh_msg_ack_ctx_rx(struct bt_mesh_msg_ack_ctx *ack)
Mark a message as acknowledged.
This function unblocks call to bt_mesh_msg_ack_ctx_wait.

**Parameters**
• **ack** – Context of a message to be acknowledged.

bool bt_mesh_msg_ack_ctx_match(const struct bt_mesh_msg_ack_ctx *ack, uint32_t op, uint16_t addr, void **user_data)
Check if an opcode and address of a message matches the expected one.

**Parameters**
• **ack** – Acknowledged message context to be checked.
• **op** – OpCode of the incoming message.
• **addr** – Source address of the incoming message.
• **user_data** – If not NULL, returns a user data stored in the acknowledged message context by bt_mesh_msg_ack_ctx_prepare.

**Returns**
true if the incoming message matches the expected one, false otherwise.

struct bt_mesh_msg_ctx
#include <msg.h> Message sending context.

**Public Members**

uint16_t net_idx
NetKey Index of the subnet to send the message on.

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uint16_t app_idx
    AppKey Index to encrypt the message with.

uint16_t addr
    Remote address.

uint16_t recv_dst
    Destination address of a received message.
    Not used for sending.

const uint8_t *uuid
    Label UUID if Remote address is Virtual address, or NULL otherwise.

int8_t recv_rssi
    RSSI of received packet.
    Not used for sending.

uint8_t recv_ttl
    Received TTL value.
    Not used for sending.

bool send_rel
    Force sending reliably by using segment acknowledgment.

bool rnd_delay
    Send message with a random delay according to the Access layer transmitting rules.

uint8_t send_ttl
    TTL, or BT_MESH_TTL_DEFAULT for default TTL.

struct bt_mesh_msg_ack_ctx
    #include <msg.h> Acknowledged message context for tracking the status of model messages pending a response.

Public Members

struct k_sem sem
    Sync semaphore.

uint32_t op
    Opcode we're waiting for.

uint16_t dst
    Address of the node that should respond.

void *user_data
    User specific parameter.
Segmentation and reassembly (SAR)  
Segmentation and reassembly (SAR) provides a way of handling larger upper transport layer messages in a mesh network, with a purpose of enhancing the Bluetooth Mesh throughput. The segmentation and reassembly mechanism is used by the lower transport layer.

The lower transport layer defines how the upper transport layer PDUs are segmented and reassembled into multiple Lower Transport PDUs, and sends them to the lower transport layer on a peer device. If the Upper Transport PDU fits, it is sent in a single Lower Transport PDU. For longer packets, which do not fit into a single Lower Transport PDU, the lower transport layer performs segmentation, splitting the Upper Transport PDU into multiple segments.

The lower transport layer on the receiving device reassembles the segments into a single Upper Transport PDU before passing it up the stack. Delivery of a segmented message is acknowledged by the lower transport layer of the receiving node, while an unsegmented message delivery is not acknowledged. However, an Upper Transport PDU that fits into one Lower Transport PDU can also be sent as a single-segment segmented message when acknowledgment by the lower transport layer is required. Set the send rel flag (see `bt_mesh_msg_ctx`) to use the reliable message transmission and acknowledge single-segment segmented messages.

The transport layer is able to transport up to 32 segments with its SAR mechanism, with a maximum message (PDU) size of 384 octets. To configure message size for the Bluetooth Mesh stack, use the following Kconfig options:

- `CONFIG_BT_MESH_RX_SEG_MAX` to set the maximum number of segments in an incoming message.
- `CONFIG_BT_MESH_TX_SEG_MAX` to set the maximum number of segments in an outgoing message.

The Kconfig options `CONFIG_BT_MESH_TX_SEG_MSG_COUNT` and `CONFIG_BT_MESH_RX_SEG_MSG_COUNT` define how many outgoing and incoming segmented messages can be processed simultaneously. When more than one segmented message is sent to the same destination, the messages are queued and sent one at a time.

Incoming and outgoing segmented messages share the same pool for allocation of their segments. This pool size is configured through the `CONFIG_BT_MESH_SEG_BUFS` Kconfig option. Both incoming and outgoing messages allocate segments at the start of the transaction. The outgoing segmented message releases its segments one by one as soon as they are acknowledged by the receiver, while the incoming message releases the segments first after the message is fully received. Keep this in mind when defining the size of the buffers.

SAR does not impose extra overhead on the access layer payload per segment.

Segmentation and reassembly (SAR) Configuration models  
With Bluetooth Mesh Protocol Specification version 1.1, it became possible to configure SAR behavior, such as intervals, timers and retransmission counters, over a mesh network using SAR Configuration models:

- `SAR Configuration Client`
- `SAR Configuration Server`

The following SAR behavior applies regardless of the presence of a SAR Configuration Server on a node.

Transmission of segments is separated by a segment transmission interval (see the `SAR Segment Interval Step` state). Other configurable time intervals and delays available for the segmentation and reassembly are:

- Interval between unicast retransmissions (see the states `SAR Unicast Retransmissions Interval Step` and `SAR Unicast Retransmissions Interval Increment`).
- Interval between multicast retransmissions (see the `SAR Multicast Retransmissions Interval Step` state).
- Segment reception interval (see the `SAR Receiver Segment Interval Step` state). 

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- Acknowledgment delay increment (see the SAR Acknowledgment Delay Increment state).

When the last segment marked as unacknowledged is transmitted, the lower transport layer starts a retransmissions timer. The initial value of the SAR Unicast Retransmissions timer depends on the value of the TTL field of the message. If the TTL field value is greater than 0, the initial value for the timer is set according to the following formula:

$$\text{unicast retransmissions interval step} + \text{unicast retransmissions interval increment} \times (TTL - 1)$$

If the TTL field value is 0, the initial value of the timer is set to the unicast retransmissions interval step.

The initial value of the SAR Multicast Retransmissions timer is set to the multicast retransmissions interval.

When the lower transport layer receives a message segment, it starts a SAR Discard timer. The discard timer tells how long the lower transport layer waits before discarding the segmented message the segment belongs to. The initial value of the SAR Discard timer is the discard timeout value indicated by the SAR Discard Timeout state.

SAR Acknowledgment timer holds the time before a Segment Acknowledgment message is sent for a received segment. The initial value of the SAR Acknowledgment timer is calculated using the following formula:

$$\min(\text{SegN} + 0.5, \text{acknowledgment delay increment}) \times \text{segment reception interval}$$

The SegN field value identifies the total number of segments the Upper Transport PDU is segmented into.

Four counters are related to SAR behavior:

- Two unicast retransmissions counts (see SAR Unicast Retransmissions Count state and SAR Unicast Retransmissions Without Progress Count state)
- Multicast retransmissions count (see SAR Multicast Retransmissions Count state)
- Acknowledgment retransmissions count (see SAR Acknowledgment Retransmissions Count state)

If the number of segments in the transmission is higher than the value of the SAR Segments Threshold state, Segment Acknowledgment messages are retransmitted using the value of the SAR Acknowledgment Retransmissions Count state.

**SAR states**

There are two states defined related to segmentation and reassembly:

- SAR Transmitter state
- SAR Receiver state

The SAR Transmitter state is a composite state that controls the number and timing of transmissions of segmented messages. It includes the following states:

- SAR Segment Interval Step
- SAR Unicast Retransmissions Count
- SAR Unicast Retransmissions Without Progress Count
- SAR Unicast Retransmissions Interval Step
- SAR Unicast Retransmissions Interval Increment
- SAR Multicast Retransmissions Count
- SAR Multicast Retransmissions Interval Step
The SAR Receiver state is a composite state that controls the number and timing of Segment Acknowledgment transmissions and the discarding of reassembly of a segmented message. It includes the following states:

- SAR Segments Threshold
- SAR Discard Timeout
- SAR Acknowledgment Delay Increment
- SAR Acknowledgment Retransmissions Count
- SAR Receiver Segment Interval Step

**SAR Segment Interval Step**  
SAR Segment Interval Step state holds a value that controls the interval between transmissions of segments of a segmented message. The interval is measured in milliseconds.

Use the `CONFIG_BT_MESH_SAR_TX_SEG_INT_STEP` Kconfig option to set the default value. Segment transmission interval is then calculated using the following formula:

\[(\text{CONFIG_BT_MESH_SAR_TX_SEG_INT_STEP} + 1) \times 10 \text{ ms}\]

**SAR Unicast Retransmissions Count**  
SAR Unicast Retransmissions Count holds a value that defines the maximum number of retransmissions of a segmented message to a unicast destination. Use the `CONFIG_BT_MESH_SAR_TX_UNICAST_RETRANS_COUNT` Kconfig option to set the default value for this state.

**SAR Unicast Retransmissions Without Progress Count**  
This state holds a value that defines the maximum number of retransmissions of a segmented message to a unicast address that will be sent if no acknowledgment was received during the timeout, or if an acknowledgment with already confirmed segments was received. Use the Kconfig option `CONFIG_BT_MESH_SAR_TX_UNICAST_RETRANSWITHOUT_PROG_COUNT` to set the maximum number of retransmissions.

**SAR Unicast Retransmissions Interval Step**  
The value of this state controls the interval step used for delaying the retransmissions of unacknowledged segments of a segmented message to a unicast address. The interval step is measured in milliseconds.

Use the `CONFIG_BT_MESH_SAR_TX_UNICAST_RETRANS_INT_STEP` Kconfig option to set the default value. This value is then used to calculate the interval step using the following formula:

\[(\text{CONFIG_BT_MESH_SAR_TX_UNICAST_RETRANS_INT_STEP} + 1) \times 25 \text{ ms}\]

**SAR Unicast Retransmissions Interval Increment**  
SAR Unicast Retransmissions Interval Increment holds a value that controls the interval increment used for delaying the retransmissions of unacknowledged segments of a segmented message to a unicast address. The increment is measured in milliseconds.

Use the Kconfig option `CONFIG_BT_MESH_SAR_TX_UNICAST_RETRANS_INT_INC` to set the default value. The Kconfig option value is used to calculate the increment using the following formula:

\[(\text{CONFIG_BT_MESH_SAR_TX_UNICAST_RETRANS_INT_INC} + 1) \times 25 \text{ ms}\]

**SAR Multicast Retransmissions Count**  
The state holds a value that controls the total number of retransmissions of a segmented message to a multicast address. Use the Kconfig option `CONFIG_BT_MESH_SAR_TX_MULTICAST_RETRANS_COUNT` to set the total number of retransmissions.
SAR Multicast Retransmissions Interval Step  This state holds a value that controls the interval between retransmissions of all segments in a segmented message to a multicast address. The interval is measured in milliseconds.

Use the Kconfig option CONFIG_BT_MESH_SAR_TX_MULTICAST_RETRANS_INT to set the default value that is used to calculate the interval using the following formula:

$$(\text{CONFIG_BT_MESH_SAR_TX_MULTICAST_RETRANS_INT} + 1) \times 25 \text{ ms}$$

SAR Discard Timeout  The value of this state defines the time in seconds that the lower transport layer waits after receiving segments of a segmented message before discarding that segmented message. Use the Kconfig option CONFIG_BT_MESH_SAR_RX_DISCARD_TIMEOUT to set the default value. The discard timeout will be calculated using the following formula:

$$(\text{CONFIG_BT_MESH_SAR_RX_DISCARD_TIMEOUT} + 1) \times 5 \text{ seconds}$$

SAR Acknowledgment Delay Increment  This state holds a value that controls the delay increment of an interval used for delaying the transmission of an acknowledgment message after receiving a new segment. The increment is measured in segments.

Use the Kconfig option CONFIG_BT_MESH_SAR_RX_ACK_DELAY_INC to set the default value. The increment value is calculated to be CONFIG_BT_MESH_SAR_RX_ACK_DELAY_INC + 1.5.

SAR Segments Threshold  SAR Segments Threshold state holds a value that defines a threshold in number of segments of a segmented message for acknowledgment retransmissions. Use the Kconfig option CONFIG_BT_MESH_SAR_RX_SEG_THRESHOLD to set the threshold.

When the number of segments of a segmented message is above this threshold, the stack will additionally retransmit every acknowledgment message the number of times given by the value of CONFIG_BT_MESH_SAR_RX_ACK_RETRANS_COUNT.

SAR Acknowledgment Retransmissions Count  The SAR Acknowledgment Retransmissions Count state controls the number of retransmissions of Segment Acknowledgment messages sent by the lower transport layer. It gives the total number of retransmissions of an acknowledgment message that the stack will additionally send when the size of segments in a segmented message is above the CONFIG_BT_MESH_SAR_RX_SEG_THRESHOLD value.

Use the Kconfig option CONFIG_BT_MESH_SAR_RX_ACK_RETRANS_COUNT to set the default value for this state. The maximum number of transmissions of a Segment Acknowledgment message is CONFIG_BT_MESH_SAR_RX_ACK_RETRANS_COUNT + 1.

SAR Receiver Segment Interval Step  The SAR Receiver Segment Interval Step defines the segments reception interval step used for delaying the transmission of an acknowledgment message after receiving a new segment. The interval is measured in milliseconds.

Use the Kconfig option CONFIG_BT_MESH_SAR_RX_SEG_INT_STEP to set the default value and calculate the interval using the following formula:

$$(\text{CONFIG_BT_MESH_SAR_RX_SEG_INT_STEP} + 1) \times 10 \text{ ms}$$

Provisioning  Provisioning is the process of adding devices to a mesh network. It requires two devices operating in the following roles:

- The provisioner represents the network owner, and is responsible for adding new nodes to the mesh network.
• The provisionee is the device that gets added to the network through the Provisioning process. Before the provisioning process starts, the provisionee is an unprovisioned device.

The Provisioning module in the Zephyr Bluetooth Mesh stack supports both the Advertising and GATT Provisioning bearers for the provisionee role, as well as the Advertising Provisioning bearer for the provisioner role.

The Provisioning process  All Bluetooth Mesh nodes must be provisioned before they can participate in a Bluetooth Mesh network. The Provisioning API provides all the functionality necessary for a device to become a provisioned mesh node. Provisioning is a five-step process, involving the following steps:

• Beaconing
• Invitation
• Public key exchange
• Authentication
• Provisioning data transfer

Beaconing  To start the provisioning process, the unprovisioned device must first start broadcasting the Unprovisioned Beacon. This makes it visible to nearby provisioners, which can initiate the provisioning. To indicate that the device needs to be provisioned, call `bt_mesh_prov_enable()`. The device starts broadcasting the Unprovisioned Beacon with the device UUID and the OOB information field, as specified in the `prov` parameter passed to `bt_mesh_init()`. Additionally, a Uniform Resource Identifier (URI) may be specified, which can point the provisioner to the location of some Out Of Band information, such as the device's public key or an authentication value database. The URI is advertised in a separate beacon, with a URI hash included in the unprovisioned beacon, to tie the two together.

Uniform Resource Identifier  The Uniform Resource Identifier shall follow the format specified in the Bluetooth Core Specification Supplement. The URI must start with a URI scheme, encoded as a single utf-8 data point, or the special `none` scheme, encoded as 0x01. The available schemes are listed on the Bluetooth website.

Examples of encoded URIs:

<table>
<thead>
<tr>
<th>URI</th>
<th>Encoded</th>
</tr>
</thead>
<tbody>
<tr>
<td><a href="http://example.com">http://example.com</a></td>
<td>\x16//example.com</td>
</tr>
<tr>
<td><a href="https://www.zephyrproject.org/">https://www.zephyrproject.org/</a></td>
<td>\x17//www.zephyrproject.org/</td>
</tr>
<tr>
<td>just a string</td>
<td>\x01just a string</td>
</tr>
</tbody>
</table>

Provisioning invitation  The provisioner initiates the Provisioning process by sending a Provisioning invitation. The invitations prompts the provisionee to call attention to itself using the Health Server Attention state, if available.

The Unprovisioned device automatically responds to the invite by presenting a list of its capabilities, including the supported Out of Band Authentication methods and algorithms.

Public key exchange  Before the provisioning process can begin, the provisioner and the unprovisioned device exchange public keys, either in-band or Out of Band (OOB).

In-band public key exchange is a part of the provisioning process and always supported by the unprovisioned device and provisioner.
If the application wants to support public key exchange via OOB, it needs to provide public and private keys to the mesh stack. The unprovisioned device will reflect this in its capabilities. The provisioner obtains the public key via any available OOB mechanism (e.g., the device may advertise a packet containing the public key or it can be encoded in a QR code printed on the device packaging). Note that even if the unprovisioned device has specified the public key for the Out of Band exchange, the provisioner may choose to exchange the public key in-band if it can't retrieve the public key via OOB mechanism. In this case, a new key pair will be generated by the mesh stack for each Provisioning process.

To enable support of OOB public key on the unprovisioned device side, `CONFIG_BT_MESH_PROV_OOB_PUBLIC_KEY` needs to be enabled. The application must provide public and private keys before the Provisioning process is started by initializing pointers to `bt_mesh_prov.public_key_be` and `bt_mesh_prov.private_key_be`. The keys needs to be provided in big-endian bytes order.

To provide the device's public key obtained via OOB, call `bt_mesh_prov_remote_pub_key_set()` on the provisioner side.

**Authentication** After the initial exchange, the provisioner selects an Out of Band (OOB) Authentication method. This allows the user to confirm that the device the provisioner connected to is actually the device they intended, and not a malicious third party.

The Provisioning API supports the following authentication methods for the provisionee:

- **Static OOB**: An authentication value is assigned to the device in production, which the provisioner can query in some application specific way.
- **Input OOB**: The user inputs the authentication value. The available input actions are listed in `bt_mesh_input_action_t`.
- **Output OOB**: Show the user the authentication value. The available output actions are listed in `bt_mesh_output_action_t`.

The application must provide callbacks for the supported authentication methods in `bt_mesh_prov`, as well as enabling the supported actions in `bt_mesh_prov.output_actions` and `bt_mesh_prov.input_actions`.

When an Output OOB action is selected, the authentication value should be presented to the user when the output callback is called, and remain until the `bt_mesh_prov.input_complete` or `bt_mesh_prov.complete` callback is called. If the action is blink, beep or vibrate, the sequence should be repeated after a delay of three seconds or more.

When an Input OOB action is selected, the user should be prompted when the application receives the `bt_mesh_prov.input` callback. The user response should be fed back to the Provisioning API through `bt_mesh_input_string()` or `bt_mesh_input_number()`. If no user response is recorded within 60 seconds, the Provisioning process is aborted.

If Provisionee wants to mandate OOB authentication, it is mandatory to use the `BT_MESH_ECDH_P256_HMAC_SHA256_AES_CCM` algorithm.

**Data transfer** After the device has been successfully authenticated, the provisioner transfers the Provisioning data:

- Unicast address
- A network key
- IV index
- Network flags
  - Key refresh
  - IV update
Additionally, a device key is generated for the node. All this data is stored by the mesh stack, and the provisioning `bt_mesh_prov.complete` callback gets called.

**Provisioning security** Depending on the choice of public key exchange mechanism and authentication method, the provisioning process can be secure or insecure.

On May 24th 2021, ANSSI disclosed a set of vulnerabilities in the Bluetooth Mesh provisioning protocol that showcased how the low entropy provided by the Blink, Vibrate, Push, Twist and Input/Output numeric OOB methods could be exploited in impersonation and MITM attacks. In response, the Bluetooth SIG has reclassified these OOB methods as insecure in the Bluetooth Mesh Profile Specification v1.0.1 erratum 16350, as AuthValue may be brute forced in real time. To ensure secure provisioning, applications should use a static OOB value and OOB public key transfer.

**API reference**

`group bt_mesh_prov` Provisioning.

** Enums**

- Available authentication algorithms.  
  *Values:*

  enumerator `BT_MESH_PROV_AUTH_CMAC_AES128_AES_CCM`

  enumerator `BT_MESH_PROV_AUTH_HMAC_SHA256_AES_CCM`

- OOB Type field values.  
  *Values:*

  enumerator `BT_MESH_STATIC_OOB_AVAILABLE = BIT(0)`  
  Static OOB information available.

  enumerator `BT_MESH_OOB_AUTH_REQUIRED = BIT(1)`  
  OOB authentication required.

`enum bt_mesh_output_action_t` Available Provisioning output authentication actions.  
*Values:*

enumerator `BT_MESH_NO_OUTPUT = 0`

enumerator `BT_MESH_BLINK = BIT(0)`  
Blink.
enumerator BT_MESH_BEEP = \textit{BIT}(1)
Beep.

enumerator BT_MESH_VIBRATE = \textit{BIT}(2)
Vibrate.

enumerator BT_MESH_DISPLAY_NUMBER = \textit{BIT}(3)
Output numeric.

enumerator BT_MESH_DISPLAY_STRING = \textit{BIT}(4)
Output alphanumeric.

c\text{enum bt\_mesh\_input\_action\_t}
Available Provisioning input authentication actions.
\textit{Values}:

enumerator BT_MESH_NO_INPUT = 0

enumerator BT_MESH_PUSH = \textit{BIT}(0)
Push.

enumerator BT_MESH_TWIST = \textit{BIT}(1)
Twist.

enumerator BT_MESH_ENTER_NUMBER = \textit{BIT}(2)
Input number.

enumerator BT_MESH_ENTER_STRING = \textit{BIT}(3)
Input alphanumeric.

c\text{enum bt\_mesh\_prov\_bearer\_t}
Available Provisioning bearers.
\textit{Values}:

enumerator BT_MESH_PROV_ADV = \textit{BIT}(0)
PB-ADV bearer.

enumerator BT_MESH_PROV_GATT = \textit{BIT}(1)
PB-GATT bearer.

enumerator BT_MESH_PROV_REMOTE = \textit{BIT}(2)
PB-Remote bearer.

c\text{enum bt\_mesh\_prov\_oob\_info\_t}
Out of Band information location.
\textit{Values}:
enumerator BT_MESH_PROV_OOB_OTHER = \textit{BIT}(0)
Other.

enumerator BT_MESH_PROV_OOB_URI = \textit{BIT}(1)
Electronic / URI.

enumerator BT_MESH_PROV_OOB_2D_CODE = \textit{BIT}(2)
2D machine-readable code

enumerator BT_MESH_PROV_OOB_BAR_CODE = \textit{BIT}(3)
Bar Code.

enumerator BT_MESH_PROV_OOB_NFC = \textit{BIT}(4)
Near Field Communication (NFC)

enumerator BT_MESH_PROV_OOB_NUMBER = \textit{BIT}(5)
Number.

enumerator BT_MESH_PROV_OOB_STRING = \textit{BIT}(6)
String.

enumerator BT_MESH_PROV_OOB_CERTIFICATE = \textit{BIT}(7)
Support for certificate-based provisioning.

enumerator BT_MESH_PROV_OOB_RECORDS = \textit{BIT}(8)
Support for provisioning records.

enumerator BT_MESH_PROV_OOB_ON_BOX = \textit{BIT}(11)
On box.

enumerator BT_MESH_PROV_OOB_IN_BOX = \textit{BIT}(12)
Inside box.

enumerator BT_MESH_PROV_OOB_ON_PAPER = \textit{BIT}(13)
On piece of paper.

enumerator BT_MESH_PROV_OOB_IN_MANUAL = \textit{BIT}(14)
Inside manual.

enumerator BT_MESH_PROV_OOB_ON_DEV = \textit{BIT}(15)
On device.

\textbf{Functions}

\begin{verbatim}
int bt_mesh_input_string(const char *str)
Provide provisioning input OOB string.
This is intended to be called after the \textit{bt_mesh_prov} input callback has been called with BT_MESH_ENTER_STRING as the action.
\end{verbatim}
Parameters
  • str – String.

Returns
    Zero on success or (negative) error code otherwise.

int bt_mesh_input_number(uint32_t num)
  Provide provisioning input OOB number.
  This is intended to be called after the bt_mesh_prov input callback has been called with BT_MESH_ENTER_NUMBER as the action.

Parameters
  • num – Number.

Returns
    Zero on success or (negative) error code otherwise.

int bt_mesh_prov_remote_pub_key_set(const uint8_t public_key[64])
  Provide Device public key.

Parameters
  • public_key – Device public key in big-endian.

Returns
    Zero on success or (negative) error code otherwise.

int bt_mesh_auth_method_set_input(bt_mesh_input_action_t action, uint8_t size)
  Use Input OOB authentication.
  Provisioner only.

Instruct the unprovisioned device to use the specified Input OOB authentication action. When using BT_MESH_PUSH, BT_MESH_TWIST or BT_MESH_ENTER_NUMBER, the bt_mesh_prov::output_number callback is called with a random number that has to be entered on the unprovisioned device.

When using BT_MESH_ENTER_STRING, the bt_mesh_prov::output_string callback is called with a random string that has to be entered on the unprovisioned device.

Parameters
  • action – Authentication action used by the unprovisioned device.
  • size – Authentication size.

Returns
    Zero on success or (negative) error code otherwise.

int bt_mesh_auth_method_set_output(bt_mesh_output_action_t action, uint8_t size)
  Use Output OOB authentication.
  Provisioner only.

Instruct the unprovisioned device to use the specified Output OOB authentication action. The bt_mesh_prov::input callback will be called.

When using BT_MESH_BLINK, BT_MESH_BEEP, BT_MESH_VIBRATE or BT_MESH_DISPLAY_NUMBER, and the application has to call bt_mesh_input_number with the random number indicated by the unprovisioned device.

When using BT_MESH_DISPLAY_STRING, the application has to call bt_mesh_input_string with the random string displayed by the unprovisioned device.

Parameters
• action – Authentication action used by the unprovisioned device.
• size – Authentication size.

**Returns**
Zero on success or (negative) error code otherwise.

int bt_mesh_auth_method_set_static(const uint8_t *static_val, uint8_t size)
Use static OOB authentication.
Provisioner only.
Instruct the unprovisioned device to use static OOB authentication, and use the given static authentication value when provisioning.

**Parameters**
• static_val – Static OOB value.
• size – Static OOB value size.

**Returns**
Zero on success or (negative) error code otherwise.

int bt_mesh_auth_method_set_none(void)
Don't use OOB authentication.
Provisioner only.
Don't use any authentication when provisioning new devices. This is the default behavior.

**Warning:** Not using any authentication exposes the mesh network to impersonation attacks, where attackers can pretend to be the unprovisioned device to gain access to the network. Authentication is strongly encouraged.

**Returns**
Zero on success or (negative) error code otherwise.

int bt_mesh_prov_enable(bt_mesh_prov_bearer_t bearers)
Enable specific provisioning bearers.
Enable one or more provisioning bearers.

**Parameters**
• bearers – Bit-wise or of provisioning bearers.

**Returns**
Zero on success or (negative) error code otherwise.

int bt_mesh_prov_disable(bt_mesh_prov_bearer_t bearers)
Disable specific provisioning bearers.
Disable one or more provisioning bearers.

**Parameters**
• bearers – Bit-wise or of provisioning bearers.

**Returns**
Zero on success or (negative) error code otherwise.
int bt_mesh_provision(const uint8_t net_key[16], uint16_t net_idx, uint8_t flags, uint32_t iv_index, uint16_t addr, const uint8_t dev_key[16])

Provision the local Mesh Node.

This API should normally not be used directly by the application. The only exception is for testing purposes where manual provisioning is desired without an actual external provisioner.

Parameters
- net_key – Network Key
- net_idx – Network Key Index
- flags – Provisioning Flags
- iv_index – IV Index
- addr – Primary element address
- dev_key – Device Key

Returns
Zero on success or (negative) error code otherwise.

int bt_mesh_provision_adv(const uint8_t uuid[16], uint16_t net_idx, uint16_t addr, uint8_t attention_duration)

Provision a Mesh Node using PB-ADV.

Parameters
- uuid – UUID
- net_idx – Network Key Index
- addr – Address to assign to remote device. If addr is 0, the lowest available address will be chosen.
- attention_duration – The attention duration to be send to remote device

Returns
Zero on success or (negative) error code otherwise.

int bt_mesh_provision_gatt(const uint8_t uuid[16], uint16_t net_idx, uint16_t addr, uint8_t attention_duration)

Provision a Mesh Node using PB-GATT.

Parameters
- uuid – UUID
- net_idx – Network Key Index
- addr – Address to assign to remote device. If addr is 0, the lowest available address will be chosen.
- attention_duration – The attention duration to be send to remote device

Returns
Zero on success or (negative) error code otherwise.

int bt_mesh_provision_remote(struct bt_mesh_rpr_cli *cli, const struct bt_mesh_rpr_node *srv, const uint8_t uuid[16], uint16_t net_idx, uint16_t addr)

Provision a Mesh Node using PB-Remote.

Parameters
- cli – Remote Provisioning Client Model to provision with.
• **srv** – Remote Provisioning Server that should be used to tunnel the provisioning.
• **uuid** – UUID of the unprovisioned node
• **net_idx** – Network Key Index to give to the unprovisioned node.
• **addr** – Address to assign to remote device. If addr is 0, the lowest available address will be chosen.

**Returns**
Zero on success or (negative) error code otherwise.

```c
int bt_mesh_reprovision_remote(struct bt_mesh_rpr_cli *cli, struct bt_mesh_rpr_node *srv, uint16_t addr, bool comp_change)
```
Reprovision a Mesh Node using PB-Remote.

Reprovisioning can be used to change the device key, unicast address and composition data of another device. The reprovisioning procedure uses the same protocol as normal provisioning, with the same level of security.

There are three tiers of reprovisioning:

a. Refreshing the device key

b. Refreshing the device key and node address. Composition data may change, including the number of elements.

c. Refreshing the device key and composition data, in case the composition data of the target node changed due to a firmware update or a similar procedure.

The target node indicates that its composition data changed by instantiating its composition data page 128. If the number of elements have changed, it may be necessary to move the unicast address of the target node as well, to avoid overlapping addresses.

**Note:** Changing the unicast addresses of the target node requires changes to all nodes that publish directly to any of the target node’s models.

**Parameters**

- **cli** – Remote Provisioning Client Model to provision on
- **srv** – Remote Provisioning Server to reprovision
- **addr** – Address to assign to remote device. If addr is 0, the lowest available address will be chosen.
- **comp_change** – The target node has indicated that its composition data has changed. Note that the target node will reject the update if this isn’t true.

**Returns**
Zero on success or (negative) error code otherwise.

```c
bool bt_mesh_is_provisioned(void)
```
Check if the local node has been provisioned.

This API can be used to check if the local node has been provisioned or not. It can e.g. be helpful to determine if there was a stored network in flash, i.e. if the network was restored after calling `settings_load()`.

**Returns**
True if the node is provisioned. False otherwise.
struct bt_mesh_dev_capabilities
#include <main.h> Device Capabilities.

**Public Members**

uint8_t elem_count
Number of elements supported by the device.

uint16_t algorithms
Supported algorithms and other capabilities.

uint8_t pub_key_type
Supported public key types.

uint8_t oob_type
Supported OOB Types.

*bt_mesh_output_action_t* output_actions
Supported Output OOB Actions.

*bt_mesh_input_action_t* input_actions
Supported Input OOB Actions.

uint8_t output_size
Maximum size of Output OOB supported.

uint8_t input_size
Maximum size in octets of Input OOB supported.

struct bt_mesh_prov
#include <main.h> Provisioning properties & capabilities.

**Public Members**

const uint8_t *uuid
The UUID that’s used when advertising as unprovisioned.

const char *uri
Optional URI.
This will be advertised separately from the unprovisioned beacon, however the unprovisioned beacon will contain a hash of it so the two can be associated by the provisioner.

*bt_mesh_prov_oob_info_t* oob_info
Out of Band information field.
const uint8_t *public_key_be
   Pointer to Public Key in big-endian for OOB public key type support.
   Remember to enable CONFIG_BT_MESH_PROV_OOB_PUBLIC_KEY when initializing this parameter.
   Must be used together with bt_mesh_prov::private_key_be.

const uint8_t *private_key_be
   Pointer to Private Key in big-endian for OOB public key type support.
   Remember to enable CONFIG_BT_MESH_PROV_OOB_PUBLIC_KEY when initializing this parameter.
   Must be used together with bt_mesh_prov::public_key_be.

const uint8_t *static_val
   Static OOB value.

uint8_t static_val_len
   Static OOB value length.

uint8_t output_size
   Maximum size of Output OOB supported.

uint16_t output_actions
   Supported Output OOB Actions.

uint8_t input_size
   Maximum size of Input OOB supported.

uint16_t input_actions
   Supported Input OOB Actions.

void (*capabilities)(const struct bt_mesh_dev_capabilities *cap)
   Provisioning Capabilities.
   This callback notifies the application that the provisioning capabilities of the un-provisioned device has been received.
   The application can consequently call bt_mesh_auth_method_set_<*> to select suitable provisioning oob authentication method.
   When this callback returns, the provisioner will start authentication with the chosen method.
   Param cap
      capabilities supported by device.

int (*output_number)(bt_mesh_output_action_t act, uint32_t num)
   Output of a number is requested.
   This callback notifies the application that it should output the given number using the given action.
   Param act
      Action for outputting the number.
   Param num
      Number to be outputted.
Return
Zero on success or negative error code otherwise

int (*output_string)(const char *str)
Output of a string is requested.
This callback notifies the application that it should display the given string to the user.
  Param str
  String to be displayed.
  Return
  Zero on success or negative error code otherwise

int (*input)(bt_mesh_input_action_t act, uint8_t size)
Input is requested.
This callback notifies the application that it should request input from the user using the given action. The requested input will either be a string or a number, and the application needs to consequently call the `bt_mesh_input_string()` or `bt_mesh_input_number()` functions once the data has been acquired from the user.
  Param act
  Action for inputting data.
  Param num
  Maximum size of the inputted data.
  Return
  Zero on success or negative error code otherwise

void (*input_complete)(void)
The other device finished their OOB input.
This callback notifies the application that it should stop displaying its output OOB value, as the other party finished their OOB input.

void (*unprovisioned_beacon)(uint8_t uuid[16], bt_mesh_prov_oob_info_t oob_info, uint32_t *uri_hash)
Unprovisioned beacon has been received.
This callback notifies the application that an unprovisioned beacon has been received.
  Param uuid
    UUID
  Param oob_info
    OOB Information
  Param uri_hash
    Pointer to URI Hash value. NULL if no hash was present in the beacon.

void (*unprovisioned_beacon_gatt)(uint8_t uuid[16], bt_mesh_prov_oob_info_t oob_info)
PB-GATT Unprovisioned Advertising has been received.
This callback notifies the application that an PB-GATT unprovisioned Advertising has been received.
  Param uuid
    UUID
  Param oob_info
    OOB Information

void (*link_open)(bt_mesh_prov_bearer_t bearer)
Provisioning link has been opened.
This callback notifies the application that a provisioning link has been opened on the given provisioning bearer.

**Param bearer**
Provisioning bearer.

```c
void (*link_close)(bt_mesh_prov_bearer_t bearer)
```
Provisioning link has been closed.
This callback notifies the application that a provisioning link has been closed on the given provisioning bearer.

**Param bearer**
Provisioning bearer.

```c
void (*complete)(uint16_t net_idx, uint16_t addr)
```
Provisioning is complete.
This callback notifies the application that provisioning has been successfully completed, and that the local node has been assigned the specified NetKeyIndex and primary element address.

**Param net_idx**
NetKeyIndex given during provisioning.

**Param addr**
Primary element address.

```c
void (*reprovisioned)(uint16_t addr)
```
Local node has been reprovisioned.
This callback notifies the application that reprovisioning has been successfully completed.

**Param addr**
New primary element address.

```c
void (*node_added)(uint16_t net_idx, uint8_t uuid[16], uint16_t addr, uint8_t num_elem)
```
A new node has been added to the provisioning database.
This callback notifies the application that provisioning has been successfully completed, and that a node has been assigned the specified NetKeyIndex and primary element address.

**Param net_idx**
NetKeyIndex given during provisioning.

**Param uuid**
UUID of the added node

**Param addr**
Primary element address.

**Param num_elem**
Number of elements that this node has.

```c
void (*reset)(void)
```
Node has been reset.
This callback notifies the application that the local node has been reset and needs to be provisioned again. The node will not automatically advertise as unprovisioned, rather the `bt_mesh_prov_enable()` API needs to be called to enable unprovisioned advertising on one or more provisioning bearers.
The Proxy feature allows legacy devices like phones to access the Bluetooth Mesh network through GATT. The Proxy feature is only compiled in if the \texttt{CONFIG\_BT\_MESH\_GATT\_PROXY} option is set. The Proxy feature state is controlled by the \textit{Configuration Server}, and the initial value can be set with \texttt{bt\_mesh\_cfg\_srv.gatt.proxy}.

Nodes with the Proxy feature enabled can advertise with Network Identity and Node Identity, which is controlled by the \textit{Configuration Client}.

The GATT Proxy state indicates if the Proxy feature is supported.

A node supporting the Proxy feature and the \textit{Private Beacon Server} model can advertise with Private Network Identity and Private Node Identity types, which is controlled by the \textit{Private Beacon Client}. By advertising with this set of identification types, the node allows the legacy device to connect to the network over GATT while maintaining the privacy of the network.

The Private GATT Proxy state indicates whether the Private Proxy functionality is supported.

In the case where both GATT Proxy and Private GATT Proxy states are disabled on a node, a legacy device cannot connect to it. A node supporting the \textit{On-Demand Private Proxy Server} may however be solicited to advertise connectable advertising events without enabling the Private GATT Proxy state. To solicit the node, the legacy device can send a Solicitation PDU by calling the \texttt{bt\_mesh\_proxy\_solicit()} function. To enable this feature, the device must be compiled with the \texttt{CONFIG\_BT\_MESH\_PROXY\_SOLICITATION} option set.

Solicitation PDUs are non-mesh, non-connectable, undirected advertising messages containing Proxy Solicitation UUID, encrypted with the network key of the subnet that the legacy device wants to connect to. The PDU contains the source address of the legacy device and a sequence number. The sequence number is maintained by the legacy device and is incremented for every new Solicitation PDU sent.

Each node supporting the Solicitation PDU reception holds its own Solicitation Replay Protection List (SRPL). The SRPL protects the solicitation mechanism from replay attacks by storing solicitation sequence number (SSEQ) and solicitation source (SSRC) pairs of valid Solicitation PDUs processed by the node. The delay between updating the SRPL and storing the change to the persistent storage is defined by \texttt{CONFIG\_BT\_MESH\_RPL\_STORE\_TIMEOUT}.

The Solicitation PDU RPL Configuration models, \textit{Solicitation PDU RPL Configuration Client} and \textit{Solicitation PDU RPL Configuration Server}, provide the functionality of saving and clearing SRPL entries. A node that supports the Solicitation PDU RPL Configuration Client model can clear a section of the SRPL on the target by calling the \texttt{bt\_mesh\_sol\_pdu\_rpl\_clear()} function. Communication between the Solicitation PDU RPL Configuration Client and Server is encrypted using the application key, therefore, the Solicitation PDU RPL Configuration Client can be instantiated on any device in the network.

When the node receives the Solicitation PDU and successfully authenticates it, it will start advertising connectable advertisements with the Private Network Identity type. The duration of the advertisement can be configured by the On-Demand Private Proxy Client model.

**API reference**

\texttt{group bt\_mesh\_proxy}

\hspace{1em}\texttt{Proxy.}

\hspace{1em}\texttt{Defines}
BT_MESH_PROXY_CB_DEFINE(_name)

Register a callback structure for Proxy events.

Registers a structure with callback functions that gets called on various Proxy events.

**Parameters**

- `_name` – Name of callback structure.

**Functions**

**int bt_mesh_proxy_identity_enable(void)**

Enable advertising with Node Identity.

This API requires that GATT Proxy support has been enabled. Once called each subnet will start advertising using Node Identity for the next 60 seconds.

**Returns**

0 on success, or (negative) error code on failure.

**int bt_mesh_proxy_private_identity_enable(void)**

Enable advertising with Private Node Identity.

This API requires that GATT Proxy support has been enabled. Once called each subnet will start advertising using Private Node Identity for the next 60 seconds.

**Returns**

0 on success, or (negative) error code on failure.

**int bt_mesh_proxy_connect(uint16_t net_idx)**

Allow Proxy Client to auto connect to a network.

This API allows a proxy client to auto-connect a given network.

**Parameters**

- `net_idx` – Network Key Index

**Returns**

0 on success, or (negative) error code on failure.

**int bt_mesh_proxy_disconnect(uint16_t net_idx)**

Disallow Proxy Client to auto connect to a network.

This API disallows a proxy client to connect a given network.

**Parameters**

- `net_idx` – Network Key Index

**Returns**

0 on success, or (negative) error code on failure.

**int bt_mesh_proxy_solicit(uint16_t net_idx)**

Schedule advertising of Solicitation PDUs.

Once called, the device will schedule advertising Solicitation PDUs for the amount of time defined by `adv_int * (CONFIG_BT_MESH_SOL_ADV_XMIT + 1)`, where `adv_int` is 20ms for Bluetooth v5.0 or higher, or 100ms otherwise.

If the number of advertised Solicitation PDUs reached `0xFFFFFFFF`, the advertisements will no longer be started until the node is reprovisioned.

**Parameters**

- `net_idx` – Network Key Index

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Returns
0 on success, or (negative) error code on failure.

```c
struct bt_mesh_proxy_cb
#include <proxy.h> Callbacks for the Proxy feature.
Should be instantiated with `BT_MESH_PROXY_CB_DEFINE`.
```

Public Members

```c
void (*identity_enabled)(uint16_t net_idx)
Started sending Node Identity beacons on the given subnet.
**Param net_idx**
Network index the Node Identity beacons are running on.

void (*identity_disabled)(uint16_t net_idx)
Stopped sending Node Identity beacons on the given subnet.
**Param net_idx**
Network index the Node Identity beacons were running on.
```

Heartbeat The Heartbeat feature provides functionality for monitoring Bluetooth Mesh nodes and determining the distance between nodes.
The Heartbeat feature is configured through the `Configuration Server` model.

Heartbeat messages Heartbeat messages are sent as transport control packets through the network, and are only encrypted with a network key. Heartbeat messages contain the original Time To Live (TTL) value used to send the message and a bitfield of the active features on the node. Through this, a receiving node can determine how many relays the message had to go through to arrive at the receiver, and what features the node supports.
Available Heartbeat feature flags:
- `BT_MESH_FEAT_RELAY`
- `BT_MESH_FEAT_PROXY`
- `BT_MESH_FEAT_FRIEND`
- `BT_MESH_FEAT_LOW_POWER`

Heartbeat publication Heartbeat publication is controlled through the Configuration models, and can be triggered in two ways:

Periodic publication
The node publishes a new Heartbeat message at regular intervals. The publication can be configured to stop after a certain number of messages, or continue indefinitely.

Triggered publication
The node publishes a new Heartbeat message every time a feature changes. The set of features that can trigger the publication is configurable.
The two publication types can be combined.
Heartbeat subscription A node can be configured to subscribe to Heartbeat messages from one node at the time. To receive a Heartbeat message, both the source and destination must match the configured subscription parameters.

Heartbeat subscription is always time limited, and throughout the subscription period, the node keeps track of the number of received Heartbeats as well as the minimum and maximum received hop count.

All Heartbeats received with the configured subscription parameters are passed to the bt_mesh_hb_cb::recv event handler.

When the Heartbeat subscription period ends, the bt_mesh_hb_cb::sub_end callback gets called.

API reference

**group bt_mesh_heartbeat**

Heartbeat.

**Defines**

BT_MESH_HB_CB_DEFINE(_name)

Register a callback structure for Heartbeat events.

Registers a callback structure that will be called whenever Heartbeat events occur

**Parameters**

- _name – Name of callback structure.

**Functions**

void bt_mesh_hb_pub_get(struct bt_mesh_hb_pub *get)

Get the current Heartbeat publication parameters.

**Parameters**

- get – Heartbeat publication parameters return buffer.

void bt_mesh_hb_sub_get(struct bt_mesh_hb_sub *get)

Get the current Heartbeat subscription parameters.

**Parameters**

- get – Heartbeat subscription parameters return buffer.

struct bt_mesh_hb_pub

#include <heartbeat.h> Heartbeat Publication parameters.

**Public Members**

uint16_t dst

Destination address.

uint16_t count

Remaining publish count.


**uint8_t ttl**

    Time To Live value.

**uint16_t feat**

    Bitmap of features that trigger a Heartbeat publication if they change.

    Legal values are **BT_MESH_FEAT_RELAY**, **BT_MESH_FEAT_PROXY**, **BT_MESH_FEAT_FRIEND** and **BT_MESH_FEAT_LOW_POWER**.

**uint16_t net_idx**

    Network index used for publishing.

**uint32_t period**

    Publication period in seconds.

**struct bt_mesh_hb_sub**

    #include <heartbeat.h> Heartbeat Subscription parameters.

**Public Members**

**uint32_t period**

    Subscription period in seconds.

**uint32_t remaining**

    Remaining subscription time in seconds.

**uint16_t src**

    Source address to receive Heartbeats from.

**uint16_t dst**

    Destination address to received Heartbeats on.

**uint16_t count**

    The number of received Heartbeat messages so far.

**uint8_t min_hops**

    Minimum hops in received messages, ie the shortest registered path from the publishing node to the subscribing node.

    A Heartbeat received from an immediate neighbor has hop count = 1.

**uint8_t max_hops**

    Maximum hops in received messages, ie the longest registered path from the publishing node to the subscribing node.

    A Heartbeat received from an immediate neighbor has hop count = 1.

**struct bt_mesh_hb_cb**

    #include <heartbeat.h> Heartbeat callback structure.
Public Members

void (*recv)(const struct bt_mesh_hb_sub *sub, uint8_t hops, uint16_t feat)
    Receive callback for heartbeats.
    Gets called on every received Heartbeat that matches the current Heartbeat subscription parameters.
    **Param sub**
    Current Heartbeat subscription parameters.
    **Param hops**
    The number of hops the Heartbeat was received with.
    **Param feat**
    The feature set of the publishing node. The value is a bitmap of BT_MESH_FEAT_RELAY, BT_MESH_FEAT_PROXY,
    BT_MESH_FEAT_FRIEND and BT_MESH_FEAT_LOW_POWER.

void (*sub_end)(const struct bt_mesh_hb_sub *sub)
    Subscription end callback for heartbeats.
    Gets called when the subscription period ends, providing a summary of the received heartbeat messages.
    **Param sub**
    Current Heartbeat subscription parameters.

void (*pub_sent)(const struct bt_mesh_hb_pub *pub)
    Publication sent callback for heartbeats.
    Gets called when the heartbeat is successfully published.
    **Param pub**
    Current Heartbeat publication parameters.

**Runtime Configuration**  The runtime configuration API allows applications to change their runtime configuration directly, without going through the Configuration models.

Bluetooth Mesh nodes should generally be configured by a central network configurator device with a Configuration Client model. Each mesh node instantiates a Configuration Server model that the Configuration Client can communicate with to change the node configuration. In some cases, the mesh node can’t rely on the Configuration Client to detect or determine local constraints, such as low battery power or changes in topology. For these scenarios, this API can be used to change the configuration locally.

**Note:** Runtime configuration changes before the node is provisioned will not be stored in the persistent storage.

**API reference**

*group bt_mesh_cfg*
    Runtime Configuration.

**Defines**

BT_MESH_KR_NORMAL

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BT_MESH_KR_PHASE_1
BT_MESH_KR_PHASE_2
BT_MESH_KR_PHASE_3
BT_MESH_RELAY_DISABLED
BT_MESH_RELAY_ENABLED
BT_MESH_RELAY_NOT_SUPPORTED
BT_MESH_BEACON_DISABLED
BT_MESH_BEACON_ENABLED
BT_MESH_PRIV_BEACON_DISABLED
BT_MESH_PRIV_BEACON_ENABLED
BT_MESH_GATT_PROXY_DISABLED
BT_MESH_GATT_PROXY_ENABLED
BT_MESH_GATT_PROXY_NOT_SUPPORTED
BT_MESH_PRIV_GATT_PROXY_DISABLED
BT_MESH_PRIV_GATT_PROXY_ENABLED
BT_MESH_PRIV_GATT_PROXY_NOT_SUPPORTED
BT_MESH_FRIEND_DISABLED
BT_MESH_FRIEND_ENABLED
BT_MESH_FRIEND_NOT_SUPPORTED
BT_MESH_NODE_IDENTITY_STOPPED
BT_MESH_NODE_IDENTITY_RUNNING
BT_MESH_NODE_IDENTITY_NOT_SUPPORTED
Enums

enum bt_mesh_feat_state
    Bluetooth Mesh feature states.
    Values:

    enumerator BT_MESH_FEATURE_DISABLED
        Feature is supported, but disabled.

    enumerator BT_MESH_FEATURE_ENABLED
        Feature is supported and enabled.

    enumerator BT_MESH_FEATURE_NOT_SUPPORTED
        Feature is not supported, and cannot be enabled.

Functions

void bt_mesh_beacon_set(bool beacon)
    Enable or disable sending of the Secure Network Beacon.
    Parameters
    • beacon – New Secure Network Beacon state.

bool bt_mesh_beacon_enabled(void)
    Get the current Secure Network Beacon state.
    Returns
    Whether the Secure Network Beacon feature is enabled.

int bt_mesh_priv_beacon_set(enum bt_mesh_feat_state priv_beacon)
    Enable or disable sending of the Mesh Private beacon.
    Support for the Private beacon state must be enabled with CONFIG_BT_MESH_PRIV_BEACONS.
    Parameters
    • priv_beacon – New Mesh Private beacon state. Must be one of BT_MESH_FEATURE_ENABLED and BT_MESH_FEATURE_DISABLED.
    Return values
    • 0 – Successfully changed the Mesh Private beacon feature state.
    • -ENOTSUP – The Mesh Private beacon feature is not supported.
    • -EINVAL – Invalid parameter.
    • -EALREADY – Already in the given state.

enum bt_mesh_feat_state bt_mesh_priv_beacon_get(void)
    Get the current Mesh Private beacon state.
    Returns
    The Mesh Private beacon feature state.
void bt_mesh_priv_beacon_update_interval_set(uint8_t interval)
    Set the current Mesh Private beacon update interval.
    The Mesh Private beacon's randomization value is updated regularly to maintain the
    node's privacy. The update interval controls how often the beacon is updated, in 10
    second increments.

    Parameters
    • interval – Private beacon update interval in 10 second steps, or 0 to up-
      date on every beacon transmission.

uint8_t bt_mesh_priv_beacon_update_interval_get(void)
    Get the current Mesh Private beacon update interval.
    The Mesh Private beacon's randomization value is updated regularly to maintain the
    node's privacy. The update interval controls how often the beacon is updated, in 10
    second increments.

    Returns
    The Private beacon update interval in 10 second steps, or 0 if the beacon is
    updated every time it's transmitted.

int bt_mesh_default_ttl_set(uint8_t default_ttl)
    Set the default TTL value.
    The default TTL value is used when no explicit TTL value is set. Models will use the
    default TTL value when bt_mesh_msg_ctx::send_ttl is BT_MESH_TTL_DEFAULT.

    Parameters
    • default_ttl – The new default TTL value. Valid values are 0x00 and 0x02
      to BT_MESH_TTL_MAX.

    Return values
    • 0 – Successfully set the default TTL value.
    • -EINVAL – Invalid TTL value.

uint8_t bt_mesh_default_ttl_get(void)
    Get the current default TTL value.

    Returns
    The current default TTL value.

int bt_mesh_od_priv_proxy_get(void)
    Get the current Mesh On-Demand Private Proxy state.

    Return values
    • 0 – or positive value represents On-Demand Private Proxy feature state
    • -ENOTSUP – The On-Demand Private Proxy feature is not supported.

int bt_mesh_od_priv_proxy_set(uint8_t on_demand_proxy)
    Set state of Mesh On-Demand Private Proxy.
    Support for the On-Demand Private Proxy state must be enabled with
    BT_MESH_OD_PRIV_PROXY_SRV.

    Parameters
    • on_demand_proxy – New Mesh On-Demand Private Proxy state. Value of
      0x00 means that advertising with Private Network Identity cannot be en-
      abled on demand. Values in range 0x01 - 0xFF set interval of this adver-
      tising after valid Solicitation PDU is received or client disconnects.

    Return values
• 0 – Successfully changed the Mesh On-Demand Private Proxy feature state.
• -ENOTSUP – The On-Demand Private Proxy feature is not supported.
• -EINVAL – Invalid parameter.
• -EALREADY – Already in the given state.

void bt_mesh_net_transmit_set(uint8_t xmit)
Set the Network Transmit parameters.
The Network Transmit parameters determine the parameters local messages are transmitted with.

See also:

BT_MESH_TRANSMIT

Parameters
• xmit – New Network Transmit parameters. Use BT_MESH_TRANSMIT for encoding.

uint8_t bt_mesh_net_transmit_get(void)
Get the current Network Transmit parameters.
The BT_MESH_TRANSMIT_COUNT and BT_MESH_TRANSMIT_INT macros can be used to decode the Network Transmit parameters.

Returns
The current Network Transmit parameters.

int bt_mesh_relay_set(enum bt_mesh_feat_state relay, uint8_t xmit)
Configure the Relay feature.
Enable or disable the Relay feature, and configure the parameters to transmit relayed messages with.
Support for the Relay feature must be enabled through the CONFIG_BT_MESH_RELAY configuration option.

See also:

BT_MESH_TRANSMIT

Parameters
• relay – New Relay feature state. Must be one of BT_MESH_FEATURE_ENABLED and BT_MESH_FEATURE_DISABLED.
• xmit – New Relay retransmit parameters. Use BT_MESH_TRANSMIT for encoding.

Return values
• 0 – Successfully changed the Relay configuration.
• -ENOTSUP – The Relay feature is not supported.
• -EINVAL – Invalid parameter.
• -EALREADY – Already using the given parameters.

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enum bt_mesh_feat_state bt_mesh_relay_get(void)
Get the current Relay feature state.

Returns
The Relay feature state.

uint8_t bt_mesh_relay_retransmit_get(void)
Get the current Relay Retransmit parameters.

The BT_MESH_TRANSMIT_COUNT and BT_MESH_TRANSMIT_INT macros can be used
to decode the Relay Retransmit parameters.

Returns
The current Relay Retransmit parameters, or 0 if relay is not supported.

int bt_mesh_gatt_proxy_set(enum bt_mesh_feat_state gatt_proxy)
Enable or disable the GATT Proxy feature.

Support for the GATT Proxy feature must be enabled through the CONFIG_BT_MESH_GATT_PROXY configuration option.

Note: The GATT Proxy feature only controls a Proxy node's ability to relay messages
to the mesh network. A node that supports GATT Proxy will still advertise Connectable
Proxy beacons, even if the feature is disabled. The Proxy feature can only be fully
disabled through compile time configuration.

Parameters
• gatt_proxy – New GATT Proxy state. Must be one of
  BT_MESH_FEATURE_ENABLED and BT_MESH_FEATURE_DISABLED.

Return values
• 0 – Successfully changed the GATT Proxy feature state.
• -ENOTSUP – The GATT Proxy feature is not supported.
• -EINVAL – Invalid parameter.
• -EALREADY – Already in the given state.

enum bt_mesh_feat_state bt_mesh_gatt_proxy_get(void)
Get the current GATT Proxy state.

Returns
The GATT Proxy feature state.

int bt_mesh_priv_gatt_proxy_set(enum bt_mesh_feat_state priv_gatt_proxy)
Enable or disable the Private GATT Proxy feature.

Support for the Private GATT Proxy feature must be enabled through the CONFIG_BT_MESH_PRIV_BEACONS and CONFIG_BT_MESH_GATT_PROXY configuration options.

Parameters
• priv_gatt_proxy – New Private GATT Proxy state. Must be one of
  BT_MESH_FEATURE_ENABLED and BT_MESH_FEATURE_DISABLED.

Return values
• 0 – Successfully changed the Private GATT Proxy feature state.
• -ENOTSUP – The Private GATT Proxy feature is not supported.
• -EINVAL – Invalid parameter.
enum bt_mesh_feat_state bt_mesh_priv_gatt_proxy_get(void)
Get the current Private GATT Proxy state.

Returns
The Private GATT Proxy feature state.

int bt_mesh_friend_set(enum bt_mesh_feat_state friendship)
Enable or disable the Friend feature.
Any active friendships will be terminated immediately if the Friend feature is disabled.
Support for the Friend feature must be enabled through the CONFIG_BT_MESH_FRIEND configuration option.

Parameters
• friendship – New Friend feature state. Must be one of BT_MESH_FEATURE_ENABLED and BT_MESH_FEATURE_DISABLED.

Return values
• 0 – Successfully changed the Friend feature state.
• -ENOTSUP – The Friend feature is not supported.
• -EINVAL – Invalid parameter.
• -EALREADY – Already in the given state.

enum bt_mesh_feat_state bt_mesh_friend_get(void)
Get the current Friend state.

Returns
The Friend feature state.

Frame statistic  The frame statistic API allows monitoring the number of received frames over different interfaces, and the number of planned and succeeded transmission and relaying attempts.
The API helps the user to estimate the efficiency of the advertiser configuration parameters and the scanning ability of the device. The number of the monitored parameters can be easily extended by customer values.
An application can read out and clean up statistics at any time.

API reference

group bt_mesh_stat
Statistic.

Functions

void bt_mesh_stat_get(struct bt_mesh_statistic *st)
Get mesh frame handling statistic.

Parameters
• st – BLE mesh statistic.

void bt_mesh_stat_reset(void)
Reset mesh frame handling statistic.
struct bt_mesh_statistic
   
#include <statistic.h> The structure that keeps statistics of mesh frames handling.

Public Members

uint32_t rx_adv
   All received frames passed basic validation and decryption.
   Received frames over advertiser.

uint32_t rx_loopback
   Received frames over loopback.

uint32_t rx_proxy
   Received frames over proxy.

uint32_t rx_unknown
   Received over unknown interface.

uint32_t tx_adv_relay_planned
   Counter of frames that were initiated to relay over advertiser bearer.

uint32_t tx_adv_relay_succeeded
   Counter of frames that succeeded relaying over advertiser bearer.

uint32_t tx_local_planned
   Counter of frames that were initiated to send over advertiser bearer locally.

uint32_t tx_local_succeeded
   Counter of frames that succeeded to send over advertiser bearer locally.

uint32_t tx_friend_planned
   Counter of frames that were initiated to send over friend bearer.

uint32_t tx_friend_succeeded
   Counter of frames that succeeded to send over friend bearer.

Bluetooth Mesh Shell The Bluetooth Mesh shell subsystem provides a set of Bluetooth Mesh shell commands for the Shell module. It allows for testing and exploring the Bluetooth Mesh API through an interactive interface, without having to write an application.

The Bluetooth Mesh shell interface provides access to most Bluetooth Mesh features, including provisioning, configuration, and message sending.

Prerequisites The Bluetooth Mesh shell subsystem depends on the application to create the composition data and do the mesh initialization.
**Application**  The Bluetooth Mesh shell subsystem is most easily used through the Bluetooth Mesh shell application under `tests/bluetooth/mesh_shell`. See *Shell* for information on how to connect and interact with the Bluetooth Mesh shell application.

**Basic usage**  The Bluetooth Mesh shell subsystem adds a single `mesh` command, which holds a set of sub-commands. Every time the device boots up, make sure to call `mesh init` before any of the other Bluetooth Mesh shell commands can be called:

```
uart:~$ mesh init
```

This is done to ensure that all available log will be printed to the shell output.

**Provisioning**  The mesh node must be provisioned to become part of the network. This is only necessary the first time the device boots up, as the device will remember its provisioning data between reboots.

The simplest way to provision the device is through self-provisioning. To do this the user must provision the device with the default network key and address `0x0001`, execute:

```
uart:~$ mesh prov local 0 0x0001
```

Since all mesh nodes use the same values for the default network key, this can be done on multiple devices, as long as they're assigned non-overlapping unicast addresses. Alternatively, to provision the device into an existing network, the unprovisioned beacon can be enabled with `mesh prov pb-adv on` or `mesh prov pb-gatt on`. The beacons can be picked up by an external provisioner, which can provision the node into its network.

Once the mesh node is part of a network, its transmission parameters can be controlled by the general configuration commands:

- To set the destination address, call `mesh target dst <Addr>`.
- To set the network key index, call `mesh target net <NetKeyIdx>`.
- To set the application key index, call `mesh target app <AppKeyIdx>`.

By default, the transmission parameters are set to send messages to the provisioned address and network key.

**Configuration**  By setting the destination address to the local unicast address (`0x0001` in the `mesh prov local` command above), we can perform self-configuration through any of the `Models` commands.

A good first step is to read out the node's own composition data:

```
uart:~$ mesh models cfg get-comp
```

This prints a list of the composition data of the node, including a list of its model IDs.

Next, since the device has no application keys by default, it's a good idea to add one:

```
uart:~$ mesh models cfg appkey add 0 0
```

**Message sending**  With an application key added (see above), the mesh node's transition parameters are all valid, and the Bluetooth Mesh shell can send raw mesh messages through the network.

For example, to send a Generic OnOff Set message, call:
uart:~$ mesh test net-send 82020100

Note: All multibyte fields model messages are in little endian, except the opcode.

The message will be sent to the current destination address, using the current network and application key indexes. As the destination address points to the local unicast address by default, the device will only send packets to itself. To change the destination address to the All Nodes broadcast address, call:

uart:~$ mesh target dst 0xffff

With the destination address set to 0xffff, any other mesh nodes in the network with the configured network and application keys will receive and process the messages we send.

Note: To change the configuration of the device, the destination address must be set back to the local unicast address before issuing any configuration commands.

Sending raw mesh packets is a good way to test model message handler implementations during development, as it can be done without having to implement the sending model. By default, only the reception of the model messages can be tested this way, as the Bluetooth Mesh shell only includes the foundation models. To receive a packet in the mesh node, you have to add a model with a valid opcode handler list to the composition data in subsys/bluetooth/mesh/shell.c, and print the incoming message to the shell in the handler callback.

Parameter formats  The Bluetooth Mesh shell commands are parsed with a variety of formats:

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>Integers</td>
<td>The default format unless something else is specified. Can be either decimal or hexadecimal.</td>
<td>1234, 0xabcd01234</td>
</tr>
<tr>
<td>Hexstrings</td>
<td>For raw byte arrays, like UUIDs, key values and message payloads, the parameters should be formatted as an unbroken string of hexadecimal values without any prefix.</td>
<td>deadbeef01234</td>
</tr>
<tr>
<td>Booleans</td>
<td>Boolean values are denoted in the API documentation as &lt;val(off, on&gt;).</td>
<td>on, off, enabled, disabled, 1, 0</td>
</tr>
</tbody>
</table>

Commands  The Bluetooth Mesh shell implements a large set of commands. Some of the commands accept parameters, which are mentioned in brackets after the command name. For example, mesh lpn set <value: off, on>. Mandatory parameters are marked with angle brackets (e.g. <NetKeyId>), and optional parameters are marked with square brackets (e.g. [DstAddr]).

The Bluetooth Mesh shell commands are divided into the following groups:
Note: Some commands depend on specific features being enabled in the compile time configuration of the application. Not all features are enabled by default. The list of available Bluetooth mesh shell commands can be shown in the shell by calling `mesh` without any arguments.

### General configuration

**mesh init**

Initialize the mesh shell. This command must be run before any other mesh command.

**mesh reset-local**

Reset the local mesh node to its initial unprovisioned state. This command will also clear the Configuration Database (CDB) if present.

### Target

The target commands enables the user to monitor and set the target destination address, network index and application index for the shell. These parameters are used by several commands, like provisioning, Configuration Client, etc.

**mesh target dst [DstAddr]**

Get or set the message destination address. The destination address determines where mesh packets are sent with the shell, but has no effect on modules outside the shell's control.

- **DstAddr**: If present, sets the new 16-bit mesh destination address. If omitted, the current destination address is printed.

**mesh target net [NetKeyId]**

Get or set the message network index. The network index determines which network key is used to encrypt mesh packets that are sent with the shell, but has no effect on modules outside the shell's control. The network key must already be added to the device, either through provisioning or by a Configuration Client.

- **NetKeyId**: If present, sets the new network index. If omitted, the current network index is printed.

**mesh target app [AppKeyId]**

Get or set the message application index. The application index determines which application key is used to encrypt mesh packets that are sent with the shell, but has no effect on modules outside the shell's control. The application key must already be added to the device by a Configuration Client, and must be bound to the current network index.
• **AppKeyIdx**: If present, sets the new application index. If omitted, the current application index is printed.

### Low Power Node

**mesh lpn set** `<Val(off, on)>

Enable or disable Low Power operation. Once enabled, the device will turn off its radio and start polling for friend nodes.

• **Val**: Sets whether Low Power operation is enabled.

**mesh lpn poll**

Perform a poll to the friend node, to receive any pending messages. Only available when LPN is enabled.

### Testing

**mesh test net-send** `<HexString`

Send a raw mesh message with the current destination address, network and application index. The message opcode must be encoded manually.

• **HexString**: Raw hexadecimal representation of the message to send.

**mesh test iv-update**

Force an IV update.

**mesh test iv-update-test** `<Val(off, on)>

Set the IV update test mode. In test mode, the IV update timing requirements are bypassed.

• **Val**: Enable or disable the IV update test mode.

**mesh test rpl-clear**

Clear the replay protection list, forcing the node to forget all received messages.

**Warning**: Clearing the replay protection list breaks the security mechanisms of the mesh node, making it susceptible to message replay attacks. This should never be performed in a real deployment.

### Health Server Test

**mesh test health-srv add-fault** `<FaultID`

Register a new Health Server Fault for the Linux Foundation Company ID.

• **FaultID**: ID of the fault to register (0x0001 to 0xFFFF)
mesh test health-srv del-fault [FaultID]

Remove registered Health Server faults for the Linux Foundation Company ID.

- FaultID: If present, the given fault ID will be deleted. If omitted, all registered faults will be cleared.

**Provisioning** To allow a device to broadcast connectable unprovisioned beacons, the CONFIG_BT_MESH_PROVISIONER configuration option must be enabled, along with the CONFIG_BT_MESH_PB_GATT option.

**mesh prov pb-gatt <Val(off, on)>**

Start or stop advertising a connectable unprovisioned beacon. The connectable unprovisioned beacon allows the mesh node to be discovered by nearby GATT based provisioners, and provisioned through the GATT bearer.

- Val: Enable or disable provisioning with GATT

To allow a device to broadcast unprovisioned beacons, the CONFIG_BT_MESH_PROVISIONER configuration option must be enabled, along with the CONFIG_BT_MESH_PB_ADV option.

**mesh prov pb-adv <Val(off, on)>**

Start or stop advertising the unprovisioned beacon. The unprovisioned beacon allows the mesh node to be discovered by nearby advertising-based provisioners, and provisioned through the advertising bearer.

- Val: Enable or disable provisioning with advertiser

To allow a device to provision devices, the CONFIG_BT_MESH_PROVISIONER and CONFIG_BT_MESH_PB_ADV configuration options must be enabled.

**mesh prov remote-adv <UUID(1-16 hex)> <NetKeyIdx> <Addr> <AttDur(s)>**

Provision a nearby device into the mesh. The mesh node starts scanning for unprovisioned beacons with the given UUID. Once found, the unprovisioned device will be added to the mesh network with the given unicast address, and given the network key indicated by NetKeyIdx.

- UUID: UUID of the unprovisioned device. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
- NetKeyIdx: Index of the network key to pass to the device.
- Addr: First unicast address to assign to the unprovisioned device. The device will occupy as many addresses as it has elements, and all must be available.
- AttDur: The duration in seconds the unprovisioned device will identify itself for, if supported. See **Attention state** for details.

To allow a device to provision devices over GATT, the CONFIG_BT_MESH_PROVISIONER and CONFIG_BT_MESH_PB_GATT_CLIENT configuration options must be enabled.

**mesh prov remote-gatt <UUID(1-16 hex)> <NetKeyIdx> <Addr> <AttDur(s)>**

Provision a nearby device into the mesh. The mesh node starts scanning for connectable advertising for PB-GATT with the given UUID. Once found, the unprovisioned device will be added to the mesh network with the given unicast address, and given the network key indicated by NetKeyIdx.
- UUID: UUID of the unprovisioned device. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
- NetKeyIdx: Index of the network key to pass to the device.
- Addr: First unicast address to assign to the unprovisioned device. The device will occupy as many addresses as it has elements, and all must be available.
- AttDur: The duration in seconds the unprovisioned device will identify itself for, if supported. See Attention state for details.

```
mesh prov uuid [UUID(1-16 hex)]
```

Get or set the mesh node's UUID, used in the unprovisioned beacons.

- UUID: If present, new 128-bit UUID value. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. If omitted, the current UUID will be printed. To enable this command, the CONFIG_BT_MESH_SHELL_PROV_CTX_INSTANCE option must be enabled.

```
mesh prov input-num <Number>
```

Input a numeric OOB authentication value. Only valid when prompted by the shell during provisioning. The input number must match the number presented by the other participant in the provisioning.

- Number: Decimal authentication number.

```
mesh prov input-str <String>
```

Input an alphanumeric OOB authentication value. Only valid when prompted by the shell during provisioning. The input string must match the string presented by the other participant in the provisioning.

- String: Unquoted alphanumeric authentication string.

```
mesh prov static-oob [Val(1-32 hex)]
```

Set or clear the static OOB authentication value. The static OOB authentication value must be set before provisioning starts to have any effect. The static OOB value must be same on both participants in the provisioning. To enable this command, the CONFIG_BT_MESH_SHELL_PROV_CTX_INSTANCE option must be enabled.

- Val: If present, indicates the new hexadecimal value of the static OOB. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. If omitted, the static OOB value is cleared.

```
mesh prov local <NetKeyIdx> <Addr> [IVI]
```

Provision the mesh node itself. If the Configuration database is enabled, the network key must be created. Otherwise, the default key value is used.

- NetKeyIdx: Index of the network key to provision.
- Addr: First unicast address to assign to the device. The device will occupy as many addresses as it has elements, and all must be available.
- IVI: Indicates the current network IV index. Defaults to 0 if omitted.
mesh prov beacon-listen <Val(off, on)>
Enable or disable printing of incoming unprovisioned beacons. Allows a provisioner
device to detect nearby unprovisioned devices and provision them. To enable this
command, the CONFIG_BT_MESH_SHELL_PROV_CTX_INSTANCE option must be enabled.
  • Val: Whether to enable the unprovisioned beacon printing.

mesh prov remote-pub-key <PubKey>
Provide Device public key.
  • PubKey - Device public key in big-endian.

mesh prov auth-method input <Action> <Size>
From the provisioner device, instruct the unprovisioned device to use the specified
Input OOB authentication action.
  • Action - Input action. Allowed values:
    – 0 - No input action.
    – 1 - Push action set.
    – 2 - Twist action set.
    – 4 - Enter number action set.
    – 8 - Enter String action set.
  • Size - Authentication size.

mesh prov auth-method output <Action> <Size>
From the provisioner device, instruct the unprovisioned device to use the specified
Output OOB authentication action.
  • Action - Output action. Allowed values:
    – 0 - No output action.
    – 1 - Blink action set.
    – 2 - Vibrate action set.
    – 4 - Display number action set.
    – 8 - Display String action set.
  • Size - Authentication size.

mesh prov auth-method static <Val(1-16 hex)>
From the provisioner device, instruct the unprovisioned device to use static OOB au-
thentication, and use the given static authentication value when provisioning.
  • Val - Static OOB value. Providing a hex-string shorter than 32 bytes will populate
the N most significant bytes of the array and zero-pad the rest.

mesh prov auth-method none
From the provisioner device, don't use any authentication when provisioning new
devices. This is the default behavior.
**Proxy** The Proxy Server module is an optional mesh subsystem that can be enabled through the `CONFIG_BT_MESH_GATT_PROXY` configuration option.

```
mesh proxy identity-enable
```
Enable the Proxy Node Identity beacon, allowing Proxy devices to connect explicitly to this device. The beacon will run for 60 seconds before the node returns to normal Proxy beacons.

The Proxy Client module is an optional mesh subsystem that can be enabled through the `CONFIG_BT_MESH_PROXY_CLIENT` configuration option.

```
mesh proxy connect <NetKeyIdx>
```
Auto-Connect a nearby proxy server into the mesh.
- `NetKeyIdx`: Index of the network key to connect.

```
mesh proxy disconnect <NetKeyIdx>
```
Disconnect the existing proxy connection.
- `NetKeyIdx`: Index of the network key to disconnect.

```
mesh proxy solicit <NetKeyIdx>
```
Begin Proxy Solicitation of a subnet. Support of this feature can be enabled through the `CONFIG_BT_MESH_PROXY_SOLICITATION` configuration option.
- `NetKeyIdx`: Index of the network key to send Solicitation PDUs to.

**Models**

**Configuration Client** The Configuration Client model is an optional mesh subsystem that can be enabled through the `CONFIG_BT_MESH_CFG_CLI` configuration option. This is implemented as a separate module (`mesh models cfg`) inside the `mesh models` subcommand list. This module will work on any instance of the Configuration Client model if the mentioned shell configuration options is enabled, and as long as the Configuration Client model is present in the model composition of the application. This shell module can be used for configuring itself and other nodes in the mesh network.

The Configuration Client uses general message parameters set by `mesh target dst` and `mesh target net` to target specific nodes. When the Bluetooth Mesh shell node is provisioned, given that the `CONFIG_BT_MESH_SHELL_PROV_CTX_INSTANCE` option is enabled with the shell provisioning context initialized, the Configuration Client model targets itself by default. Similarly, when another node has been provisioned by the Bluetooth Mesh shell, the Configuration Client model targets the new node. In most common use-cases, the Configuration Client is depending on the provisioning features and the Configuration database to be fully functional. The Configuration Client always sends messages using the Device key bound to the destination address, so it will only be able to configure itself and the mesh nodes it provisioned. The following steps are an example of how you can set up a device to start using the Configuration Client commands:

- Initialize the client node (`mesh init`).
- Create the CDB (`mesh cdb create`).
- Provision the local device (`mesh prov local`).
- The shell module should now target itself.
- Monitor the composition data of the local node (`mesh models cfg get-comp`).
- Configure the local node as desired with the Configuration Client commands.
- Provision other devices (`mesh prov beacon-listen`) (`mesh prov remote-adv`) (`mesh prov remote-gatt`).
  - The shell module should now target the newly added node.
- Monitor the newly provisioned nodes and their addresses (`mesh cdb show`).
- Monitor the composition data of the target device (`mesh models cfg get-comp`).
- Configure the node as desired with the Configuration Client commands.

```
mesh models cfg target get
  Get the target Configuration server for the Configuration Client model.
```

```
mesh models cfg help
  Print information for the Configuration Client shell module.
```

```
mesh models cfg reset
  Reset the target device.
```

```
mesh models cfg timeout [Timeout(s)]
  Get and set the Config Client model timeout used during message sending.
  - Timeout: If present, set the Config Client model timeout in seconds. If omitted, the current timeout is printed.
```

```
mesh models cfg get-comp [Page]
  Read a composition data page. The full composition data page will be printed. If the target does not have the given page, it will return the last page before it.
  - Page: The composition data page to request. Defaults to 0 if omitted.
```

```
mesh models cfg beacon [Val(off, on)]
  Get or set the network beacon transmission.
  - Val: If present, enables or disables sending of the network beacon. If omitted, the current network beacon state is printed.
```

```
mesh models cfg ttl [TTL]
  Get or set the default TTL value.
  - TTL: If present, sets the new default TTL value. Legal TTL values are 0x00 and 0x02-0x7f. If omitted, the current default TTL value is printed.
```
mesh models cfg friend [Val(off, on)]
Get or set the Friend feature.
- Val: If present, enables or disables the Friend feature. If omitted, the current Friend feature state is printed:
  - 0x00: The feature is supported, but disabled.
  - 0x01: The feature is enabled.
  - 0x02: The feature is not supported.

mesh models cfg gatt-proxy [Val(off, on)]
Get or set the GATT Proxy feature.
- Val: If present, enables or disables the GATT Proxy feature. If omitted, the current GATT Proxy feature state is printed:
  - 0x00: The feature is supported, but disabled.
  - 0x01: The feature is enabled.
  - 0x02: The feature is not supported.

mesh models cfg relay [<Val(off, on)> [Count] [Int(ms)]]
Get or set the Relay feature and its parameters.
- Val: If present, enables or disables the Relay feature. If omitted, the current Relay feature state is printed:
  - 0x00: The feature is supported, but disabled.
  - 0x01: The feature is enabled.
  - 0x02: The feature is not supported.
- Count: Sets the new relay retransmit count if val is on. Ignored if val is off. Legal retransmit count is 0-7. Defaults to 2 if omitted.
- Int: Sets the new relay retransmit interval in milliseconds if val is on. Legal interval range is 10-320 milliseconds. Ignored if val is off. Defaults to 20 if omitted.

mesh models cfg node-id <NetKeyIdx> [Identity]
Get or Set of current Node Identity state of a subnet.
- NetKeyIdx: The network key index to Get/Set.
- Identity: If present, sets the identity of Node Identity state.

mesh models cfg polltimeout-get <LPNAddr>
Get current value of the PollTimeout timer of the LPN within a Friend node.
- LPNAddr Address of Low Power node.
mesh models cfg net-transmit-param [<Count> <Int(ms)>]

Get or set the network transmit parameters.

- Count: Sets the number of additional network transmits for every sent message. Legal retransmit count is 0-7.
- Int: Sets the new network retransmit interval in milliseconds. Legal interval range is 10-320 milliseconds.

mesh models cfg netkey add <NetKeyIdx> [Key(1-16 hex)]

Add a network key to the target node. Adds the key to the Configuration Database if enabled.

- NetKeyIdx: The network key index to add.
- Key: If present, sets the key value as a 128-bit hexadecimal value. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. Only valid if the key does not already exist in the Configuration Database. If omitted, the default key value is used.

mesh models cfg netkey upd <NetKeyIdx> [Key(1-16 hex)]

Update a network key to the target node.

- NetKeyIdx: The network key index to updated.
- Key: If present, sets the key value as a 128-bit hexadecimal value. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. If omitted, the default key value is used.

mesh models cfg netkey get

Get a list of known network key indexes.

mesh models cfg netkey del <NetKeyIdx>

Delete a network key from the target node.

- NetKeyIdx: The network key index to delete.

mesh models cfg appkey add <NetKeyIdx> <AppKeyIdx> [Key(1-16 hex)]

Add an application key to the target node. Adds the key to the Configuration Database if enabled.

- NetKeyIdx: The network key index the application key is bound to.
- AppKeyIdx: The application key index to add.
- Key: If present, sets the key value as a 128-bit hexadecimal value. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. Only valid if the key does not already exist in the Configuration Database. If omitted, the default key value is used.
mesh models cfg appkey upd <NetKeyIdx> <AppKeyIdx> [Key(1-16 hex)]

Update an application key to the target node.

- NetKeyIdx: The network key index the application key is bound to.
- AppKeyIdx: The application key index to update.
- Key: If present, sets the key value as a 128-bit hexadecimal value. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. If omitted, the default key value is used.

mesh models cfg appkey get <NetKeyIdx>

Get a list of known application key indexes bound to the given network key index.

- NetKeyIdx: Network key indexes to get a list of application key indexes from.

mesh models cfg appkey del <NetKeyIdx> <AppKeyIdx>

Delete an application key from the target node.

- NetKeyIdx: The network key index the application key is bound to.
- AppKeyIdx: The application key index to delete.

mesh models cfg model app-bind <Addr> <AppKeyIdx> <MID> [CID]

Bind an application key to a model. Models can only encrypt and decrypt messages sent with application keys they are bound to.

- Addr: Address of the element the model is on.
- AppKeyIdx: The application key to bind to the model.
- MID: The model ID of the model to bind the key to.
- CID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model app-unbind <Addr> <AppKeyIdx> <MID> [CID]

Unbind an application key from a model.

- Addr: Address of the element the model is on.
- AppKeyIdx: The application key to unbind from the model.
- MID: The model ID of the model to unbind the key from.
- CID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model app-get <ElemAddr> <MID> [CID]

Get a list of application keys bound to a model.

- ElemAddr: Address of the element the model is on.
- MID: The model ID of the model to get the bound keys of.
- CID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.
Get or set the publication parameters of a model. If all publication parameters are included, they become the new publication parameters of the model. If all publication parameters are omitted, print the current publication parameters of the model.

- **Addr**: Address of the element the model is on.
- **MID**: The model ID of the model to get the bound keys of.
- **CID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

Publication parameters:

- **PubAddr**: The destination address to publish to.
- **AppKeyId**: The application key index to publish with.
- **Cred**: Whether to publish with Friendship credentials when acting as a Low Power Node.
- **TTL**: TTL value to publish with (0x00 to 0x07f).
- **PerRes**: Resolution of the publication period steps:
  - 0x00: The Step Resolution is 100 milliseconds
  - 0x01: The Step Resolution is 1 second
  - 0x02: The Step Resolution is 10 seconds
  - 0x03: The Step Resolution is 10 minutes
- **PerSteps**: Number of publication period steps, or 0 to disable periodic publication.
- **Count**: Number of retransmission for each published message (0 to 7).
- **Int**: The interval between each retransmission, in milliseconds. Must be a multiple of 50.

Set the publication parameters of a model.

- **Addr**: Address of the element the model is on.
- **MID**: The model ID of the model to get the bound keys of.
- **CID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

Publication parameters:

- **UUID**: The destination virtual address to publish to. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
- **AppKeyId**: The application key index to publish with.
- **Cred**: Whether to publish with Friendship credentials when acting as a Low Power Node.
- **TTL**: TTL value to publish with (0x00 to 0x07f).
- **PerRes**: Resolution of the publication period steps:
  - 0x00: The Step Resolution is 100 milliseconds
– 0x01: The Step Resolution is 1 second
– 0x02: The Step Resolution is 10 seconds
– 0x03: The Step Resolution is 10 minutes

- PerSteps: Number of publication period steps, or 0 to disable periodic publication.
- Count: Number of retransmission for each published message (0 to 7).
- Int: The interval between each retransmission, in milliseconds. Must be a multiple of 50.

```
mesh models cfg model sub-add <ElemAddr> <SubAddr> <MID> [CID]
```

Subscriptions the model to a group address. Models only receive messages sent to their unicast address or a group or virtual address they subscribe to. Models may subscribe to multiple group and virtual addresses.

- ElemAddr: Address of the element the model is on.
- SubAddr: 16-bit group address the model should subscribe to (0xc000 to 0xFEFF).
- MID: The model ID of the model to add the subscription to.
- CID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

```
mesh models cfg model sub-del <ElemAddr> <SubAddr> <MID> [CID]
```

Unsubscribe a model from a group address.

- ElemAddr: Address of the element the model is on.
- SubAddr: 16-bit group address the model should remove from its subscription list (0xc000 to 0xFEFF).
- MID: The model ID of the model to add the subscription to.
- CID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

```
mesh models cfg model sub-add-va <ElemAddr> <LabelUUID(1-16 hex)> <MID> [CID]
```

Subscribe the model to a virtual address. Models only receive messages sent to their unicast address or a group or virtual address they subscribe to. Models may subscribe to multiple group and virtual addresses.

- ElemAddr: Address of the element the model is on.
- LabelUUID: 128-bit label UUID of the virtual address to subscribe to. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
- MID: The model ID of the model to add the subscription to.
- CID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.
Unsubscribe a model from a virtual address.

- **ElemAddr**: Address of the element the model is on.
- **LabelUUID**: 128-bit label UUID of the virtual address to remove the subscription of. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
- **MID**: The model ID of the model to add the subscription to.
- **CID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

**mesh models cfg model sub-ow <ElemAddr> <SubAddr> <MID> [CID]**

Overwrite all model subscriptions with a single new group address.

- **ElemAddr**: Address of the element the model is on.
- **SubAddr**: 16-bit group address the model should added to the subscription list (0xc000 to 0xFEFF).
- **MID**: The model ID of the model to add the subscription to.
- **CID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

**mesh models cfg model sub-ow-va <ElemAddr> <LabelUUID(1-16 hex)> <MID> [CID]**

Overwrite all model subscriptions with a single new virtual address. Models only receive messages sent to their unicast address or a group or virtual address they subscribe to. Models may subscribe to multiple group and virtual addresses.

- **ElemAddr**: Address of the element the model is on.
- **LabelUUID**: 128-bit label UUID of the virtual address as the new Address to be added to the subscription list. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
- **MID**: The model ID of the model to add the subscription to.
- **CID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

**mesh models cfg model sub-del-all <ElemAddr> <MID> [CID]**

Remove all group and virtual address subscriptions from a model.

- **ElemAddr**: Address of the element the model is on.
- **MID**: The model ID of the model to Unsubscribe all.
- **CID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

**mesh models cfg model sub-get <ElemAddr> <MID> [CID]**

Get a list of addresses the model subscribes to.

- **ElemAddr**: Address of the element the model is on.
- **MID**: The model ID of the model to get the subscription list of.
• CID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

`mesh models cfg krp <NetKeyIdx> [Phase]`
Get or set the key refresh phase of a subnet.
• NetKeyIdx: The identified network key used to Get/Set the current Key Refresh Phase state.
• Phase: New Key Refresh Phase. Valid phases are:
  – 0x00: Normal operation; Key Refresh procedure is not active
  – 0x01: First phase of Key Refresh procedure
  – 0x02: Second phase of Key Refresh procedure

`mesh models cfg hb-sub [<Src> <Dst> <Per>]`
Get or set the Heartbeat subscription parameters. A node only receives Heartbeat messages matching the Heartbeat subscription parameters. Sets the Heartbeat subscription parameters if present, or prints the current Heartbeat subscription parameters if called with no parameters.
• Src: Unicast source address to receive Heartbeat messages from.
• Dst: Destination address to receive Heartbeat messages on.
• Per: Logarithmic representation of the Heartbeat subscription period:
  – 0: Heartbeat subscription will be disabled.
  – 1 to 17: The node will subscribe to Heartbeat messages for \(2^{(period - 1)}\) seconds.

`mesh models cfg hb-pub [<Dst> <Count> <Per> <TTL> <Features> <NetKeyIdx>]`
Get or set the Heartbeat publication parameters. Sets the Heartbeat publication parameters if present, or prints the current Heartbeat publication parameters if called with no parameters.
• Dst: Destination address to publish Heartbeat messages to.
• Count: Logarithmic representation of the number of Heartbeat messages to publish periodically:
  – 0: Heartbeat messages are not published periodically.
  – 1 to 17: The node will periodically publish \(2^{(count - 1)}\) Heartbeat messages.
  – 255: Heartbeat messages will be published periodically indefinitely.
• Per: Logarithmic representation of the Heartbeat publication period:
  – 0: Heartbeat messages are not published periodically.
  – 1 to 17: The node will publish Heartbeat messages every \(2^{(period - 1)}\) seconds.
• TTL: The TTL value to publish Heartbeat messages with (0x00 to 0x7f).
• Features: Bitfield of features that should trigger a Heartbeat publication when changed:
  – Bit 0: Relay feature.
  – Bit 1: Proxy feature.
  – Bit 2: Friend feature.
– Bit 3: Low Power feature.
  • NetKeyIdx: Index of the network key to publish Heartbeat messages with.

**Health Client** The Health Client model is an optional mesh subsystem that can be enabled through the `CONFIG_BT_MESH_HEALTH_CLI` configuration option. This is implemented as a separate module (mesh models health) inside the mesh models subcommand list. This module will work on any instance of the Health Client model if the mentioned shell configuration options is enabled, and as long as one or more Health Client model(s) is present in the model composition of the application. This shell module can be used to trigger interaction between Health Clients and Servers on devices in a Mesh network.

By default, the module will choose the first Health Client instance in the model composition when using the Health Client commands. To choose a specific Health Client instance the user can utilize the commands `mesh models health instance set` and `mesh models health instance get-all`.

The Health Client may use the general messages parameters set by `mesh target dst`, `mesh target net` and `mesh target app` to target specific nodes. If the shell target destination address is set to zero, the targeted Health Client will attempt to publish messages using its configured publication parameters.

```plaintext
mesh models health instance set <ElemIdx>
    Set the Health Client model instance to use.
    • ElemIdx: Element index of Health Client model.

mesh models health instance get-all
    Prints all available Health Client model instances on the device.

mesh models health fault-get <CID>
    Get a list of registered faults for a Company ID.
    • CID: Company ID to get faults for.

mesh models health fault-clear <CID>
    Clear the list of faults for a Company ID.
    • CID: Company ID to clear the faults for.

mesh models health fault-clear-unack <CID>
    Clear the list of faults for a Company ID without requesting a response.
    • CID: Company ID to clear the faults for.

mesh models health fault-test <CID> <TestID>
    Invoke a self-test procedure, and show a list of triggered faults.
    • CID: Company ID to perform self-tests for.
    • TestID: Test to perform.
```
mesh models health fault-test-unack <CID> <TestID>
Invoke a self-test procedure without requesting a response.
• CID: Company ID to perform self-tests for.
• TestID: Test to perform.

mesh models health period-get
Get the current Health Server publish period divisor.

mesh models health period-set <Divisor>
Set the current Health Server publish period divisor. When a fault is detected, the Health Server will start publishing its fault status with a reduced interval. The reduced interval is determined by the Health Server publish period divisor: Fault publish period = Publish period / \(2^{\text{Divisor}}\).
• Divisor: The new Health Server publish period divisor.

mesh models health period-set-unack <Divisor>
Set the current Health Server publish period divisor. When a fault is detected, the Health Server will start publishing its fault status with a reduced interval. The reduced interval is determined by the Health Server publish period divisor: Fault publish period = Publish period / \(2^{\text{Divisor}}\).
• Divisor: The new Health Server publish period divisor.

mesh models health attention-get
Get the current Health Server attention state.

mesh models health attention-set <Time(s)>
Enable the Health Server attention state for some time.
• Time: Duration of the attention state, in seconds (0 to 255)

mesh models health attention-set-unack <Time(s)>
Enable the Health Server attention state for some time without requesting a response.
• Time: Duration of the attention state, in seconds (0 to 255)

**Binary Large Object (BLOB) Transfer Client model**   The BLOB Transfer Client can be added to the mesh shell by enabling the CONFIG_BT_MESH_BLOB_CLI option, and disabling the CONFIG_BT_MESH_DFU_CLI option.

mesh models blob cli target <Addr>
Add a Target node for the next BLOB transfer.
• Addr: Unicast address of the Target node's BLOB Transfer Server model.
mesh models blob cli bounds [\<Group\>]

Get the total boundary parameters of all Target nodes.

- **Group**: Optional group address to use when communicating with Target nodes. If omitted, the BLOB Transfer Client will address each Target node individually.

mesh models blob cli tx \<Id\> \<Size\> \<BlockSizeLog\> \<ChunkSize\> [\<Group\> [\<Mode(push, pull)\>]]

Perform a BLOB transfer to Target nodes. The BLOB Transfer Client will send a dummy BLOB to all Target nodes, then post a message when the transfer is completed. Note that all Target nodes must first be configured to receive the transfer using the `mesh models blob srv rx` command.

- **Id**: 64-bit BLOB transfer ID.
- **Size**: Size of the BLOB in bytes.
- **BlockSizeLog**: Logarithmic representation of the BLOB's block size. The final block size will be $1 << \text{block size log}$ bytes.
- **ChunkSize**: Chunk size in bytes.
- **Group**: Optional group address to use when communicating with Target nodes. If omitted or set to 0, the BLOB Transfer Client will address each Target node individually.
- **Mode**: BLOB transfer mode to use. Must be either `push` (Push BLOB Transfer Mode) or `pull` (Pull BLOB Transfer Mode). If omitted, `push` will be used by default.

mesh models blob cli tx-cancel

Cancel an ongoing BLOB transfer.

mesh models blob cli tx-get [\<Group\>]

Determine the progress of a previously running BLOB transfer. Can be used when not performing a BLOB transfer.

- **Group**: Optional group address to use when communicating with Target nodes. If omitted or set to 0, the BLOB Transfer Client will address each Target node individually.

mesh models blob cli tx-suspend

Suspend the ongoing BLOB transfer.

mesh models blob cli tx-resume

Resume the suspended BLOB transfer.

mesh models blob cli instance-set \<ElemIdx\>

Use the BLOB Transfer Client model instance on the specified element when using the other BLOB Transfer Client model commands.

- **ElemIdx**: The element on which to find the BLOB Transfer Client model instance to use.

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Get a list of all BLOB Transfer Client model instances on the node.

**BLOB Transfer Server model**  The **BLOB Transfer Server** can be added to the mesh shell by enabling the `CONFIG_BT_MESH_BLOB_SRV` option. The BLOB Transfer Server model is capable of receiving any BLOB data, but the implementation in the mesh shell will discard the incoming data.

```
mesh models blob cli instance-get-all
```

Prepare to receive a BLOB transfer.

- **ID**: 64-bit BLOB transfer ID to receive.
- **TimeoutBase**: Optional additional time to wait for client messages, in 10-second increments.

```
mesh models blob srv rx <ID> [TimeoutBase(10s steps)]
```

Cancel an ongoing BLOB transfer.

```
mesh models blob srv rx-cancel
```

Use the BLOB Transfer Server model instance on the specified element when using the other BLOB Transfer Server model commands.

- **ElemIdx**: The element on which to find the BLOB Transfer Server model instance to use.

```
mesh models blob srv instance-set <ElemIdx>
```

Get a list of all BLOB Transfer Server model instances on the node.

```
mesh models blob srv instance-get-all
```

The Firmware Update Client model can be added to the mesh shell by enabling configuration options `CONFIG_BT_MESH_BLOB_CLI` and `CONFIG_BT_MESH_DFU_CLI`. The Firmware Update Client demonstrates the firmware update Distributor role by transferring a dummy firmware update to a set of Target nodes.

```
mesh models dfu slot add <Size> <FwID> [Metadata]
```

Add a virtual DFU image slot that can be transferred as a DFU image. The image slot will be assigned an image slot index, which is printed as a response, and can be used to reference the slot in other commands. To update the image slot, remove it using the `mesh models dfu slot del` shell command and then add it again.

- **Size**: DFU image slot size in bytes.
- **FwID**: Firmware ID, formatted as a hexstring.
- **Metadata**: Optional firmware metadata, formatted as a hexstring.

```
mesh models dfu slot del <SlotIdx>
```

Delete the DFU image slot at the given index.

- **SlotIdx**: Index of the slot to delete.
mesh models dfu slot get <SlotIdx>
Get all available information about a DFU image slot.
  • SlotIdx: Index of the slot to get.

mesh models dfu cli target <Addr> <ImgIdx>
Add a Target node.
  • Addr: Unicast address of the Target node.
  • ImgIdx: Image index to address on the Target node.

mesh models dfu cli target-state
Check the DFU Target state of the device at the configured destination address.

mesh models dfu cli target-imgs [<MaxCount>]
Get a list of DFU images on the device at the configured destination address.
  • MaxCount: Optional maximum number of images to return. If omitted, there's no limit on the number of returned images.

mesh models dfu cli target-check <SlotIdx> <TargetImgIdx>
Check whether the device at the configured destination address will accept a DFU transfer from the given DFU image slot to the Target node's DFU image at the given index, and what the effect would be.
  • SlotIdx: Index of the local DFU image slot to check.
  • TargetImgIdx: Index of the Target node's DFU image to check.

mesh models dfu cli send <SlotIdx> [<Group>]
Start a DFU transfer to all added Target nodes.
  • SlotIdx: Index of the local DFU image slot to send.
  • Group: Optional group address to use when communicating with the Target nodes. If omitted, the Firmware Update Client will address each Target node individually.

mesh models dfu cli cancel [<Addr>]
Cancel the DFU procedure at any state on a specific Target node or on all Target nodes. When a Target node address is provided, the Firmware Update Client model will try to cancel the DFU procedure on the provided Target node. Otherwise, the Firmware Update Client model will try to cancel the ongoing DFU procedure on all Target nodes.
  • Addr: Optional unicast address of a Target node on which to cancel the DFU procedure.

mesh models dfu cli apply
Apply the most recent DFU transfer on all Target nodes. Can only be called after a DFU transfer is completed.

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mesh models dfu cli confirm

Confirm that the most recent DFU transfer was successfully applied on all Target nodes. Can only be called after a DFU transfer is completed and applied.

mesh models dfu cli suspend

Suspend the ongoing DFU transfer.

mesh models dfu cli resume

Resume the suspended DFU transfer.

mesh models dfu cli progress

Check the progress of the current transfer.

mesh models dfu cli instance-set <ElemIdx>

Use the Firmware Update Client model instance on the specified element when using the other Firmware Update Client model commands.

- ElemIdx: The element on which to find the Firmware Update Client model instance to use.

mesh models dfu cli instance-get-all

Get a list of all Firmware Update Client model instances on the node.

Firmware Update Server model  The Firmware Update Server model can be added to the mesh shell by enabling configuration options CONFIG_BT_MESH_BLOB_SRV and CONFIG_BT_MESH_DFU_SRV. The Firmware Update Server demonstrates the firmware update Target role by accepting any firmware update. The mesh shell Firmware Update Server will discard the incoming firmware data, but otherwise behave as a proper firmware update Target node.

mesh models dfu srv applied

Mark the most recent DFU transfer as applied. Can only be called after a DFU transfer is completed, and the Distributor has requested that the transfer is applied.

As the mesh shell Firmware Update Server doesn't actually apply the incoming firmware image, this command can be used to emulate an applied status, to notify the Distributor that the transfer was successful.

mesh models dfu srv progress

Check the progress of the current transfer.

mesh models dfu srv rx-cancel

Cancel incoming DFU transfer.
**mesh models dfu srv instance-set <ElemIdx>**

Use the Firmware Update Server model instance on the specified element when using the other Firmware Update Server model commands.

- **ElemIdx**: The element on which to find the Firmware Update Server model instance to use.

**mesh models dfu srv instance-get-all**

Get a list of all Firmware Update Server model instances on the node.

**Firmware Distribution Server model** The Firmware Distribution Server model commands can be added to the mesh shell by enabling the `CONFIG_BT_MESH_DFD_SRV` configuration option. The shell commands for this model mirror the messages sent to the server by a Firmware Distribution Client model. To use these commands, a Firmware Distribution Server must be instantiated by the application.

**mesh models dfd receivers-add <Addr>,<FwIdx>[;<Addr>,<FwIdx>]...**

Add receivers to the Firmware Distribution Server. Supply receivers as a list of comma-separated `addr,fw_idx` pairs, separated by semicolons, for example, `0x0001,0;0x0002,0;0x0004,1`. Do not use spaces in the receiver list. Repeated calls to this command will continue populating the receivers list until `mesh models dfd receivers-delete-all` is called.

- **Addr**: Address of the receiving node(s).
- **FwIdx**: Index of the firmware slot to send to `Addr`.

**mesh models dfd receivers-delete-all**

Delete all receivers from the server.

**mesh models dfd receivers-get <First> <Count>**

Get a list of info about firmware receivers.

- **First**: Index of the first receiver to get from the receiver list.
- **Count**: The number of receivers for which to get info.

**mesh models dfd capabilities-get**

Get the capabilities of the server.

**mesh models dfd get**

Get information about the current distribution state, phase and the transfer parameters.
Start the firmware distribution.

- **AppKeyIdx**: Application index to use for sending. The common application key should be bound to the Firmware Update and BLOB Transfer models on the Distributor and Target nodes.
- **SlotIdx**: Index of the local image slot to send.
- **Group**: Optional group address to use when communicating with the Target nodes. If omitted, the Firmware Distribution Server will address each Target node individually. To keep addressing each Target node individually while changing other arguments, set this argument value to 0.
- **PolicyApply**: Optional field that corresponds to the update policy. Setting this to true will make the Firmware Distribution Server apply the image immediately after the transfer is completed.
- **TTL**: Optional. TTL value to use when sending. Defaults to configured default TTL.
- **TimeoutBase**: Optional additional value used to calculate timeout values in the firmware distribution process, in 10-second increments.. See Transfer timeout for information about how timeout_base is used to calculate the transfer timeout. Defaults to 0.
- **XferMode**: Optional BLOB transfer mode. 1 = Push mode (Push BLOB Transfer Mode), 2 = Pull mode (Pull BLOB Transfer Mode). Defaults to Push mode.

---

Suspends the ongoing distribution.

Cancel the ongoing distribution.

Apply the distributed firmware.

Get information about the firmware image uploaded to the server.

Get information about the firmware image uploaded to the server in a specific slot.

Delete a firmware image from the server.
mesh models dfd fw-delete-all
Delete all firmware images from the server.

mesh models dfd instance-set <ElemIdx>
Use the Firmware Distribution Server model instance on the specified element when using the other Firmware Distribution Server model commands.
  - ElemIdx: The element on which to find the Firmware Distribution Server model instance to use.

mesh models dfd instance-get-all
Get a list of all Firmware Distribution Server model instances on the node.

DFU metadata  The DFU metadata commands allow generating metadata that can be used by a Target node to check the firmware before accepting it. The commands are enabled through the CONFIG_BT_MESH_DFU_METADATA configuration option.

dfu metadata comp-clear
Clear the stored composition data to be used for the Target node.

dfu metadata comp-add <CID> <ProductID> <VendorID> <Crpl> <Features>
Create a header of the Composition Data Page 0.
  - CID: Company identifier assigned by Bluetooth SIG.
  - ProductID: Vendor-assigned product identifier.
  - VendorID: Vendor-assigned version identifier.
  - Crpl: The size of the replay protection list.
  - Features: Features supported by the node in bit field format:
    - 0: Relay.
    - 1: Proxy.
    - 2: Friend.
    - 3: Low Power.

dfu metadata comp-elem-add <Loc> <NumS> <NumV> {<SigMID>|<VndCID> <VndMID>}...
Add element description of the Target node.
  - Loc: Element location.
  - NumS: Number of SIG models instantiated on the element.
  - NumV: Number of vendor models instantiated on the element.
  - SigMID: SIG Model ID.
  - VndCID: Vendor model company identifier.
  - VndMID: Vendor model identifier.
mesh models dfu metadata comp-hash-get [Key(16 hex)]

Generate a hash of the stored Composition Data to be used in metadata.

- Key: Optional 128-bit key to be used to generate the hash. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.

mesh models dfu metadata encode <Major> <Minor> <Rev> <BuildNum> <Size> <CoreType> <Hash> <Elems> [<UserData>]

Encode metadata for the DFU.

- Major: Major version of the firmware.
- Minor: Minor version of the firmware.
- Rev: Revision number of the firmware.
- BuildNum: Build number.
- Size: Size of the signed bin file.
- CoreType: New firmware core type in bit field format:
  - 0: Application core.
  - 1: Network core.
  - 2: Applications specific BLOB.
- Hash: Hash of the composition data generated using mesh models dfu metadata comp-hash-get command.
- Elms: Number of elements on the new firmware.
- UserData: User data supplied with the metadata.

Segmentation and Reassembly (SAR) Configuration Client  
The SAR Configuration client is an optional mesh model that can be enabled through the CONFIG_BT_MESH_SAR_CFG_CLI configuration option. The SAR Configuration Client model is used to support the functionality of configuring the behavior of the lower transport layer of a node that supports the SAR Configuration Server model.

mesh models sar tx-get

Send SAR Configuration Transmitter Get message.

mesh models sar tx-set <SegIntStep> <UniRetransCnt> <UniRetransWithoutProgCnt> <UniRetransIntStep> <UniRetransIntInc> <MultiRetransCnt> <MultiRetransInt>

Send SAR Configuration Transmitter Set message.

- SegIntStep: SAR Segment Interval Step state.
- UniRetransCnt: SAR Unicast Retransmissions Count state.
- UniRetransWithoutProgCnt: SAR Unicast Retransmissions Without Progress Count state.
- UniRetransIntStep: SAR Unicast Retransmissions Interval Step state.
- UniRetransIntInc: SAR Unicast Retransmissions Interval Increment state.
- MultiRetransCnt: SAR Multicast Retransmissions Count state.
- MultiRetransInt: SAR Multicast Retransmissions Interval state.
**mesh models sar rx-get**

Send SAR Configuration Receiver Get message.

**mesh models sar rx-set <SegThresh> <AckDelayInc> <DiscardTimeout> <RxSegIntStep> <AckRetransCount>**

Send SAR Configuration Receiver Set message.

- **SegThresh**: SAR Segments Threshold state.
- **AckDelayInc**: SAR Acknowledgment Delay Increment state.
- **DiscardTimeout**: SAR Discard Timeout state.
- **RxSegIntStep**: SAR Receiver Segment Interval Step state.
- **AckRetransCount**: SAR Acknowledgment Retransmissions Count state.

**Private Beacon Client**  The Private Beacon Client model is an optional mesh subsystem that can be enabled through the `CONFIG_BT_MESH_PRIV_BEACON_CLI` configuration option.

**mesh models prb priv-beacon-get**

Get the target's Private Beacon state. Possible values:

- **0x00**: The node doesn't broadcast Private beacons.
- **0x01**: The node broadcasts Private beacons.

**mesh models prb priv-beacon-set <Val(off, on)> <RandInt(10s steps)>**

Set the target's Private Beacon state.

- **Val**: Control Private Beacon state.
- **RandInt**: Random refresh interval (in 10-second steps), or 0 to keep current value.

**mesh models prb priv-gatt-proxy-get**

Get the target's Private GATT Proxy state. Possible values:

- **0x00**: The Private Proxy functionality is supported, but disabled.
- **0x01**: The Private Proxy functionality is enabled.
- **0x02**: The Private Proxy functionality is not supported.

**mesh models prb priv-gatt-proxy-set <Val(off, on)>**

Set the target's Private GATT Proxy state.

- **Val**: New Private GATT Proxy value:
  - **0x00**: Disable the Private Proxy functionality.
  - **0x01**: Enable the Private Proxy functionality.
mesh models prb priv-node-id-get <NetKeyIdx>

Get the target's Private Node Identity state. Possible values:

- **0x00**: The node does not advertise with the Private Node Identity.
- **0x01**: The node advertises with the Private Node Identity.
- **0x02**: The node doesn't support advertising with the Private Node Identity.
- **NetKeyIdx**: Network index to get the Private Node Identity state of.

mesh models prb priv-node-id-set <NetKeyIdx> <State>

Set the target's Private Node Identity state.

- **NetKeyIdx**: Network index to set the Private Node Identity state of.
- **State**: New Private Node Identity value:
  - **0x00**: Stop advertising with the Private Node Identity.
  - **0x01**: Start advertising with the Private Node Identity.

**Opcodes Aggregator Client**  The Opcodes Aggregator client is an optional Bluetooth Mesh model that can be enabled through the `CONFIG_BT_MESH_OP_AGG_CLI` configuration option. The Opcodes Aggregator Client model is used to support the functionality of dispatching a sequence of access layer messages to nodes supporting the Opcodes Aggregator Server model.

mesh models opagg seq-start <ElemAddr>

Start the Opcodes Aggregator Sequence message. This command initiates the context for aggregating messages and sets the destination address for next shell commands to `elem_addr`.

- **ElemAddr**: Element address that will process the aggregated opcodes.

mesh models opagg seq-send

Send the Opcodes Aggregator Sequence message. This command completes the procedure, sends the aggregated sequence message to the target node and clears the context.

mesh models opagg seq-abort

Abort the Opcodes Aggregator Sequence message. This command clears the Opcodes Aggregator Client context.

**Remote Provisioning Client**  The Remote Provisioning Client is an optional Bluetooth Mesh model enabled through the `CONFIG_BT_MESH_RPR_CLI` configuration option. The Remote Provisioning Client model provides support for remote provisioning of devices into a mesh network by using the Remote Provisioning Server model.

This shell module can be used to trigger interaction between Remote Provisioning Clients and Remote Provisioning Servers on devices in a mesh network.
mesh models rpr scan <Timeout(s)> [UUID(1-16 hex)]

  Start scanning for unprovisioned devices.
  • Timeout: Scan timeout in seconds. Must be at least 1 second.
  • UUID: Device UUID to scan for. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. If omitted, all devices will be reported.

mesh models rpr scan-ext <Timeout(s)> UUID(1-16 hex) [ADType ...]

  Start the extended scanning for unprovisioned devices.
  • Timeout: Scan timeout in seconds. Valid values from BT_MESH_RPR_EXT_SCAN_TIME_MIN to BT_MESH_RPR_EXT_SCAN_TIME_MAX.
  • UUID: Device UUID to start extended scanning for. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
  • ADType: List of AD types to include in the scan report. Must contain 1 to CONFIG_BT_MESH_RPR_AD_TYPES_MAX entries.

mesh models rpr scan-srv [ADType ...]

  Start the extended scanning for the Remote Provisioning Server.
  • ADType: List of AD types to include in the scan report. Must contain 1 to CONFIG_BT_MESH_RPR_AD_TYPES_MAX entries.

mesh models rpr scan-caps

  Get the scanning capabilities of the Remote Provisioning Server.

mesh models rpr scan-get

  Get the current scanning state of the Remote Provisioning Server.

mesh models rpr scan-stop

  Stop any ongoing scanning on the Remote Provisioning Server.

mesh models rpr link-get

  Get the current link status of the Remote Provisioning Server.

mesh models rpr link-close

  Close any open links on the Remote Provisioning Server.
**mesh models rpr provision-remote <UUID(1-16 hex)> <NetKeyIdx> <Addr>**

Provision a mesh node using the PB-Remote provisioning bearer.

- **UUID**: UUID of the unprovisioned node. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
- **NetKeyIdx**: Network Key Index to give to the unprovisioned node.
- **Addr**: Address to assign to remote device. If addr is 0, the lowest available address will be chosen.

**mesh models rpr reprovision-remote <Addr> [CompChanged(false, true)>]**

Reprovision a mesh node using the PB-Remote provisioning bearer.

- **Addr**: Address to assign to remote device. If addr is 0, the lowest available address will be chosen.
- **CompChanged**: The Target node has indicated that its Composition Data has changed. Defaults to false.

**mesh models rpr instance-set <ElemIdx>**

Use the Remote Provisioning Client model instance on the specified element when using the other Remote Provisioning Client model commands.

- **ElemIdx**: The element on which to find the Remote Provisioning Client model instance to use.

**mesh models rpr instance-get-all**

Get a list of all Remote Provisioning Client model instances on the node.

### Configuration database

The Configuration database is an optional mesh subsystem that can be enabled through the CONFIG_BT_MESH_CDB configuration option. The Configuration database is only available on provisioner devices, and allows them to store all information about the mesh network. To avoid conflicts, there should only be one mesh node in the network with the Configuration database enabled. This node is the Configurator, and is responsible for adding new nodes to the network and configuring them.

**mesh cdb create [NetKey(1-16 hex)]**

Create a Configuration database.

- **NetKey**: Optional network key value of the primary network key (NetKeyIndex=0). Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. Defaults to the default key value if omitted.

**mesh cdb clear**

Clear all data from the Configuration database.

**mesh cdb show**

Show all data in the Configuration database.
mesh cdb node-add <UUID(1-16 hex)> <Addr> <ElemCnt> <NetKeyIdx> [DevKey(1-16 hex)]

Manually add a mesh node to the configuration database. Note that devices provisioned with mesh provision and mesh provision-adv will be added automatically if the Configuration Database is enabled and created.

- **UUID**: 128-bit hexadecimal UUID of the node. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest.
- **Addr**: Unicast address of the node, or 0 to automatically choose the lowest available address.
- **ElemCnt**: Number of elements on the node.
- **NetKeyIdx**: The network key the node was provisioned with.
- **DevKey**: Optional 128-bit device key value for the device. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. If omitted, a random value will be generated.

mesh cdb node-del <Addr>

Delete a mesh node from the Configuration database. If possible, the node should be reset with mesh reset before it is deleted from the Configuration database, to avoid unexpected behavior and uncontrolled access to the network.

- **Addr**: Address of the node to delete.

mesh cdb subnet-add <NetKeyIdx> [<NetKey(1-16 hex)>]

Add a network key to the Configuration database. The network key can later be passed to mesh nodes in the network. Note that adding a key to the Configuration database does not automatically add it to the local node’s list of known network keys.

- **NetKeyIdx**: Key index of the network key to add.
- **NetKey**: Optional 128-bit network key value. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. If omitted, a random value will be generated.

mesh cdb subnet-del <NetKeyIdx>

Delete a network key from the Configuration database.

- **NetKeyIdx**: Key index of the network key to delete.

mesh cdb app-key-add <NetKeyIdx> <AppKeyIdx> [<AppKey(1-16 hex)>]

Add an application key to the Configuration database. The application key can later be passed to mesh nodes in the network. Note that adding a key to the Configuration database does not automatically add it to the local node’s list of known application keys.

- **NetKeyIdx**: Network key index the application key is bound to.
- **AppKeyIdx**: Key index of the application key to add.
- **AppKey**: Optional 128-bit application key value. Providing a hex-string shorter than 16 bytes will populate the N most significant bytes of the array and zero-pad the rest. If omitted, a random value will be generated.

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mesh  cdb  app-key-del  <AppKeyIdx>

Delete an application key from the Configuration database.

• AppKeyIdx: Key index of the application key to delete.

On-Demand Private GATT Proxy Client The On-Demand Private GATT Proxy Client model is an optional mesh subsystem that can be enabled through the CON-FIG_BT_MESH_OD_PRIV_PROXY_CLI configuration option.

mesh models  od_priv_proxy  od-priv-gatt-proxy  [Dur(s)]

Set the On-Demand Private GATT Proxy state on active target, or fetch the value of this state from it.

• Dur: If given, set the state of On-Demand Private GATT Proxy to this value in seconds. Fetch this value otherwise.

Solicitation PDU RPL Client The Solicitation PDU RPL Client model is an optional mesh subsystem that can be enabled through the CONFIG_BT_MESH_SOL_PDU_RPL_CLI configuration option.

mesh models  sol_pdu_rpl  sol-pdu-rpl-clear  <RngStart>  <Ackd>  [RngLen]

Clear active target’s solicitation replay protection list (SRPL) in given range of solicitation source (SSRC) addresses.

• RngStart: Start address of the SSRC range.
• Ackd: This argument decides on whether an acknowledged or unacknowledged message will be sent.
• RngLen: Range length for the SSRC addresses to be cleared from the solicitation RPL list. This parameter is optional; if absent, only a single SSRC address will be cleared.

Frame statistic

mesh  stat  get

Get the frame statistic. The command prints numbers of received frames, as well as numbers of planned and succeeded transmission attempts.

mesh  stat  clear

Clear all statistics collected before.

Bluetooth Microphone Control

API Reference

group  bt_gatt_micp

Microphone Control Profile (MICP)

[Experimental] Users should note that the APIs can change as a part of ongoing development.
Defines

**BT_MICP_MIC_DEV_AICS_CNT**

**BT_MICP_ERR_MUTE_DISABLED**
Application error codes.

**BT_MICP_MUTE_UNMUTED**
Microphone Control Profile mute states.

**BT_MICP_MUTE_MUTED**

**BT_MICP_MUTE_DISABLED**

Functions

**int bt_micp_mic_dev_register (struct bt_micp_mic_dev_register_param *param)**
Initialize the Microphone Control Profile Microphone Device.
This will enable the Microphone Control Service instance and make it discoverable by Microphone Controllers.

**Parameters**

- `param` – Pointer to an initialization structure.

**Returns**

0 if success, errno on failure.

**int bt_micp_mic_dev_included_get (struct bt_micp_included *included)**
Get Microphone Device included services.
Returns a pointer to a struct that contains information about the Microphone Device included Audio Input Control Service instances.
Requires that `CONFIG_BT_MICP_MIC_DEV_AICS` is enabled.

**Parameters**

- `included` – Pointer to store the result in.

**Returns**

0 if success, errno on failure.

**int bt_micp_mic_dev_unmute (void)**
Unmute the Microphone Device.

**Returns**

0 on success, GATT error value on fail.

**int bt_micp_mic_dev_mute (void)**
Mute the Microphone Device.

**Returns**

0 on success, GATT error value on fail.

**int bt_micp_mic_dev_mute_disable (void)**
Disable the mute functionality on the Microphone Device.
Can be reenabled by called `bt_micp_mic_dev_mute` or `bt_micp_mic_dev_unmute`.

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int bt_micp_mic_dev_mute_get(void)
Read the mute state on the Microphone Device.

Returns
0 on success, GATT error value on fail.

int bt_micp_mic_ctlr_included_get(struct bt_micp_mic_ctlr *mic_ctlr, struct bt_micp_included *included)
Get Microphone Control Profile included services.

Returns a pointer to a struct that contains information about the Microphone Control Profile included services instances, such as pointers to the Audio Input Control Service instances.

Requires that CONFIG_BT_MICP_MIC_CTLR_AICS is enabled.

Parameters
• mic_ctlr – Microphone Controller instance pointer.
• included – [out] Pointer to store the result in.

Returns
0 if success, errno on failure.

int bt_micp_mic_ctlr_conn_get(const struct bt_micp_mic_ctlr *mic_ctlr, struct bt_conn **conn)
Get the connection pointer of a Microphone Controller instance.

Get the Bluetooth connection pointer of a Microphone Controller instance.

Parameters
• mic_ctlr – Microphone Controller instance pointer.
• conn – Connection pointer.

Returns
0 if success, errno on failure.

struct bt_micp_mic_ctlr *bt_micp_mic_ctlr_get_by_conn(const struct bt_conn *conn)
Get the volume controller from a connection pointer.

Get the Volume Control Profile Volume Controller pointer from a connection pointer. Only volume controllers that have been initiated via bt_micp_mic_ctlr_discover() can be retrieved.

Parameters
• conn – Connection pointer.

Return values
• Pointer – to a Microphone Control Profile Microphone Controller instance
• NULL – if conn is NULL or if the connection has not done discovery yet

int bt_micp_mic_ctlr_discover(struct bt_conn *conn, struct bt_micp_mic_ctlr **mic_ctlr)
Discover Microphone Control Service.

This will start a GATT discovery and setup handles and subscriptions. This shall be called once before any other actions can be executed for the peer device, and the bt_micp_mic_ctlr_cb::discover callback will notify when it is possible to start remote operations.
Parameters
- **conn** – The connection to initialize the profile for.
- **mic_ctlr** – **[out]** Valid remote instance object on success.

Returns
0 on success, GATT error value on fail.

```c
int bt_micp_mic_ctlr_unmute(struct bt_micp_mic_ctlr *mic_ctlr)
```
Unmute a remote Microphone Device.

Parameters
- **mic_ctlr** – Microphone Controller instance pointer.

Returns
0 on success, GATT error value on fail.

```c
int bt_micp_mic_ctlr_mute(struct bt_micp_mic_ctlr *mic_ctlr)
```
Mute a remote Microphone Device.

Parameters
- **mic_ctlr** – Microphone Controller instance pointer.

Returns
0 on success, GATT error value on fail.

```c
int bt_micp_mic_ctlr_mute_get(struct bt_micp_mic_ctlr *mic_ctlr)
```
Read the mute state of a remote Microphone Device.

Parameters
- **mic_ctlr** – Microphone Controller instance pointer.

Returns
0 on success, GATT error value on fail.

```c
int bt_micp_mic_ctlr_cb_register(struct bt_micp_mic_ctlr_cb *cb)
```
Registers the callbacks used by Microphone Controller.
This can only be done as the client.

Parameters
- **cb** – The callback structure.

Returns
0 if success, errno on failure.

```c
struct bt_micp_mic_dev_register_param
#include <micp.h> Register parameters structure for Microphone Control Service.
```

Public Members

```c
struct bt_micp_mic_dev_cb *cb
```
Microphone Control Profile callback structure.
struct bt_micp_included
#include <micp.h>  Microphone Control Profile included services.

Used for to represent the Microphone Control Profile included service instances, for
either a Microphone Controller or a Microphone Device. The instance pointers either
represent local service instances, or remote service instances.

Public Members

uint8_t aics_cnt
Number of Audio Input Control Service instances.

struct bt_aics **aics
Array of pointers to Audio Input Control Service instances.

struct bt_micp_mic_dev_cb
#include <micp.h>

Public Members

void (*mute)(uint8_t mute)
Callback function for Microphone Device mute.
Called when the value is read with bt_micp_mic_dev_mute_get(), or if the value is
changed by either the Microphone Device or a Microphone Controller.

Param mute
The mute setting of the Microphone Control Service.

struct bt_micp_mic_ctlr_cb
#include <micp.h>

Public Members

void (*mute)(struct bt_micp_mic_ctlr *mic_ctlr, int err, uint8_t mute)
Callback function for Microphone Control Profile mute.
Called when the value is read, or if the value is changed by either the Microphone
Device or a Microphone Controller.

Param mic_ctlr
Microphone Controller instance pointer.

Param err
Error value. 0 on success, GATT error or errno on fail. For notifications,
this will always be 0.

Param mute
The mute setting of the Microphone Control Service.

void (*discover)(struct bt_micp_mic_ctlr *mic_ctlr, int err, uint8_t aics_count)
Callback function for bt_micp_mic_ctlr_discover()
**Param err**
Error value. 0 on success, GATT error or errno on fail.

**Param aics_count**
Number of Audio Input Control Service instances on peer device.

```c
void (*mute_written)(struct bt_micp_mic_ctlr *mic_ctlr, int err)
```
Callback function for Microphone Control Profile mute/unmute.

**Param mic_ctlr**
Microphone Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error or errno on fail.

```c
void (*unmute_written)(struct bt_micp_mic_ctlr *mic_ctlr, int err)
```
Callback function for Microphone Control Profile mute/unmute.

**Param mic_ctlr**
Microphone Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error or errno on fail.

---

**Serial Port Emulation (RFCOMM)**

**API Reference**

**group bt_rfcomm**
RFCOMM.

**Typedefs**

typedef enum `bt_rfcomm_role` `bt_rfcomm_role_t`
Role of RFCOMM session and dlc.
Used only by internal APIs

** Enums**

**Values:**

extentifier `BT_RFCOMM_CHAN_HFP_HF` = 1

extentifier `BT_RFCOMM_CHAN_HFP_AG`

extentifier `BT_RFCOMM_CHAN_HSP_AG`

extentifier `BT_RFCOMM_CHAN_HSP_HS`

extentifier `BT_RFCOMM_CHAN_SPP`
enum bt_rfcomm_role
   Role of RFCOMM session and dlc.
   Used only by internal APIs
   Values:

   enumerator BT_RFCOMM_ROLE_ACCEPTOR

   enumerator BT_RFCOMM_ROLE_INITIATOR

Functions

int bt_rfcomm_server_register(struct bt_rfcomm_server *server)
   Register RFCOMM server.
   Register RFCOMM server for a channel, each new connection is authorized using the
   accept() callback which in case of success shall allocate the dlc structure to be used by
   the new connection.

   Parameters
   • server – Server structure.

   Returns
   0 in case of success or negative value in case of error.

int bt_rfcomm_dlc_connect(struct bt_conn *conn, struct bt_rfcomm_dlc *dlc, uint8_t
   channel)
   Connect RFCOMM channel.
   Connect RFCOMM dlc by channel, once the connection is completed dlc connected() call-
   back will be called. If the connection is rejected disconnected() callback is called
   instead.

   Parameters
   • conn – Connection object.
   • dlc – Dlc object.
   • channel – Server channel to connect to.

   Returns
   0 in case of success or negative value in case of error.

int bt_rfcomm_dlc_send(struct bt_rfcomm_dlc *dlc, struct net_buf *buf)
   Send data to RFCOMM.
   Send data from buffer to the dlc. Length should be less than or equal to mtu.

   Parameters
   • dlc – Dlc object.
   • buf – Data buffer.

   Returns
   Bytes sent in case of success or negative value in case of error.

int bt_rfcomm_dlc_disconnect(struct bt_rfcomm_dlc *dlc)
   Disconnect RFCOMM dlc.
   Disconnect RFCOMM dlc, if the connection is pending it will be canceled and as a result
   the dlc disconnected() callback is called.
Parameters

• dlc – Dlc object.

Returns

0 in case of success or negative value in case of error.

struct net_buf *bt_rfcomm_create_pdu(struct net_buf_pool *pool)

Allocate the buffer from pool after reserving head room for RFCOMM, L2CAP and ACL headers.

Parameters

• pool – Which pool to take the buffer from.

Returns

New buffer.

struct bt_rfcomm_dlc_ops

#include <rfcomm.h> RFCOMM DLC operations structure.

Public Members

void (*connected)(struct bt_rfcomm_dlc *dlc)

DLC connected callback.

If this callback is provided it will be called whenever the connection completes.

Param dlc
The dlc that has been connected

void (*disconnected)(struct bt_rfcomm_dlc *dlc)

DLC disconnected callback.

If this callback is provided it will be called whenever the dlc is disconnected, including when a connection gets rejected or cancelled (both incoming and outgoing)

Param dlc
The dlc that has been Disconnected

void (*recv)(struct bt_rfcomm_dlc *dlc, struct net_buf *buf)

DLC recv callback.

Param dlc
The dlc receiving data.

Param buf
Buffer containing incoming data.

struct bt_rfcomm_dlc

#include <rfcomm.h> RFCOMM DLC structure.

struct bt_rfcomm_server

#include <rfcomm.h>

Public Members

uint8_t channel
Server Channel.
int (*accept)(struct bt_conn *conn, struct bt_rfcomm_dlc **dlc)
Server accept callback.
This callback is called whenever a new incoming connection requires authorization.

**Param conn**
The connection that is requesting authorization

**Param dlc**
Pointer to received the allocated dlc

**Return**
0 in case of success or negative value in case of error.

---

Bluedooth standard services

**Battery Service**

**group bt_bas**
Battery Service (BAS)
[Experimental] Users should note that the APIs can change as a part of ongoing development.

**Functions**

**uint8_t bt_bas_get_battery_level(void)**
Read battery level value.
Read the characteristic value of the battery level

**Returns**
The battery level in percent.

**int bt_bas_set_battery_level(uint8_t level)**
Update battery level value.
Update the characteristic value of the battery level This will send a GATT notification to all current subscribers.

**Parameters**
* level – The battery level in percent.

**Returns**
Zero in case of success and error code in case of error.

**Heart Rate Service**

**group bt_hrs**
Heart Rate Service (HRS)
[Experimental] Users should note that the APIs can change as a part of ongoing development.

**Functions**
int bt_hrs_cb_register(struct bt_hrs_cb *cb)

Heart rate service callback register.

This function will register callbacks that will be called in certain events related to Heart rate service.

**Parameters**

- cb – Pointer to callbacks structure. Must point to memory that remains valid until unregistered.

**Returns**

- 0 on success
- -EINVAL in case cb is NULL

int bt_hrs_cb_unregister(struct bt_hrs_cb *cb)

Heart rate service callback unregister.

This function will unregister callback from Heart rate service.

**Parameters**

- cb – Pointer to callbacks structure

**Returns**

- 0 on success
- -EINVAL in case cb is NULL
- -ENOENT in case the cb was not found in registered callbacks

int bt_hrs_notify(uint16_t heartrate)

Notify heart rate measurement.

This will send a GATT notification to all current subscribers.

**Parameters**

- heartrate – The heartrate measurement in beats per minute.

**Returns**

- Zero in case of success and error code in case of error.

struct bt_hrs_cb

#include <hrs.h> Heart rate service callback structure.

**Public Members**

void (*ntf_changed)(bool enabled)

Heart rate notifications changed.

**Param enabled**

Flag that is true if notifications were enabled, false if they were disabled.

**Immediate Alert Service**

6.1. Bluetooth
**group** bt_ias

Immediate Alert Service (IAS)

[Experimental] Users should note that the APIs can change as a part of ongoing development.

### Defines

**BT_IAS_CB_DEFINE(_name)**

Register a callback structure for immediate alert events.

**Parameters**

- _name – Name of callback structure.

### Enums

**enum bt_ias_alert_lvl**

**Values:**

- enumerator **BT_IAS_ALERT_LVL_NO_ALERT**
  
  No alerting should be done on device.

- enumerator **BT_IAS_ALERT_LVL_MILD_ALERT**
  
  Device shall alert.

- enumerator **BT_IAS_ALERT_LVL_HIGH_ALERT**
  
  Device should alert in strongest possible way.

### Functions

**int bt_ias_local_alert_stop(void)**

Method for stopping alert locally.

**Returns**

Zero in case of success and error code in case of error.

**int bt_ias_client_alert_write(struct bt_conn *conn, enum bt_ias_alert_lvl)**

Set alert level.

**Parameters**

- conn – Bluetooth connection object
- bt_ias_alert_lvl – Level of alert to write

**Returns**

Zero in case of success and error code in case of error.

**int bt_ias_discover(struct bt_conn *conn)**

Discover Immediate Alert Service.

**Parameters**

- conn – Bluetooth connection object
Returns
Zero in case of success and error code in case of error.

int bt_ias_client_cb_register(const struct bt_ias_client_cb *cb)
Register Immediate Alert Client callbacks.

Parameters
- cb – The callback structure

Returns
Zero in case of success and error code in case of error.

struct bt_ias_cb
#include <ias.h> Immediate Alert Service callback structure.

Public Members

void (*no_alert)(void)
Callback function to stop alert.
This callback is called when peer commands to disable alert.

void (*mild_alert)(void)
Callback function for alert level value.
This callback is called when peer commands to alert.

void (*high_alert)(void)
Callback function for alert level value.
This callback is called when peer commands to alert in the strongest possible way.

struct bt_ias_client_cb
#include <ias.h>

Public Members

void (*discover)(struct bt_conn *conn, int err)
Callback function for bt_ias_discover.
This callback is called when discovery procedure is complete.
Param conn
Bluetooth connection object.
Param err
0 on success, ATT error or negative errno otherwise

Object Transfer Service

group bt_ots
Object Transfer Service (OTS)
[Experimental] Users should note that the APIs can change as a part of ongoing development.

6.1. Bluetooth
Defines

**BT_OTS_OBJ_ID_SIZE**
Size of OTS object ID (in bytes).

**BT_OTS_OBJ_ID_MIN**
Minimum allowed value for object ID (except ID for directory listing)

**BT_OTS_OBJ_ID_MAX**
Maximum allowed value for object ID (except ID for directory listing)

**OTS_OBJ_ID_DIR_LIST**
ID of the Directory Listing Object.

**BT_OTS_OBJ_ID_MASK**
Mask for OTS object IDs, preserving the 48 bits.

**BT_OTS_OBJ_ID_STR_LEN**
Length of OTS object ID string (in bytes).

**BT_OTS_OBJ_SET_PROP_DELETE(prop)**
Set **BT_OTS_OBJ_PROP_DELETE** property.

**Parameters**
- **prop** – Object properties.

**BT_OTS_OBJ_SET_PROP_EXECUTE(prop)**
Set **BT_OTS_OBJ_PROP_EXECUTE** property.

**Parameters**
- **prop** – Object properties.

**BT_OTS_OBJ_SET_PROP_READ(prop)**
Set **BT_OTS_OBJ_PROP_READ** property.

**Parameters**
- **prop** – Object properties.

**BT_OTS_OBJ_SET_PROP_WRITE(prop)**
Set **BT_OTS_OBJ_PROP_WRITE** property.

**Parameters**
- **prop** – Object properties.

**BT_OTS_OBJ_SET_PROP_APPEND(prop)**
Set **BT_OTS_OBJ_PROP_APPEND** property.

**Parameters**
- **prop** – Object properties.

**BT_OTS_OBJ_SET_PROP_TRUNCATE(prop)**
Set **BT_OTS_OBJ_PROP_TRUNCATE** property.

**Parameters**
- **prop** – Object properties.
BT_OTS_OBJ_SET_PROP_PATCH(prop)
Set `BT_OTS_OBJ_PROP_PATCH` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_SET_PROP_MARKED(prop)
Set `BT_OTS_OBJ_SET_PROP_MARKED` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_GET_PROP_DELETE(prop)
Get `BT_OTS_OBJ_PROP_DELETE` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_GET_PROP_EXECUTE(prop)
Get `BT_OTS_OBJ_PROP_EXECUTE` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_GET_PROP_READ(prop)
Get `BT_OTS_OBJ_PROP_READ` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_GET_PROP_WRITE(prop)
Get `BT_OTS_OBJ_PROP_WRITE` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_GET_PROP_APPEND(prop)
Get `BT_OTS_OBJ_PROP_APPEND` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_GET_PROP_TRUNCATE(prop)
Get `BT_OTS_OBJ_PROP_TRUNCATE` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_GET_PROP_PATCH(prop)
Get `BT_OTS_OBJ_PROP_PATCH` property.

Parameters
• prop – Object properties.

BT_OTS_OBJ_GET_PROP_MARKED(prop)
Get `BT_OTS_OBJ_PROP_MARKED` property.

Parameters
• prop – Object properties.

6.1. Bluetooth
### BT_ROT_OACP_SET_FEAT_CREATE(Feat)
Set `BT_ROT_OACP_SET_FEAT_CREATE` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_DELETE(Feat)
Set `BT_ROT_OACP_FEAT_DELETE` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_CHECKSUM(Feat)
Set `BT_ROT_OACP_FEAT_CHECKSUM` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_EXECUTE(Feat)
Set `BT_ROT_OACP_FEAT_EXECUTE` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_READ(Feat)
Set `BT_ROT_OACP_FEAT_READ` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_WRITE(Feat)
Set `BT_ROT_OACP_FEAT_WRITE` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_APPEND(Feat)
Set `BT_ROT_OACP_FEAT_APPEND` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_TRUNCATE(Feat)
Set `BT_ROT_OACP_FEAT_TRUNCATE` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_PATCH(Feat)
Set `BT_ROT_OACP_FEAT_PATCH` feature.

**Parameters**
- **feat** – OTS features.

### BT_ROT_OACP_SET_FEAT_ABORT(Feat)
Set `BT_ROT_OACP_FEAT_ABORT` feature.

**Parameters**
- **feat** – OTS features.
BT_OTS_OACP_GET_FEAT_CREATE(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_CREATE} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_DELETE(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_DELETE} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_CHECKSUM(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_CHECKSUM} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_EXECUTE(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_EXECUTE} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_READ(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_READ} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_WRITE(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_WRITE} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_APPEND(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_APPEND} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_TRUNCATE(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_TRUNCATE} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_PATCH(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_PATCH} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}

BT_OTS_OACP_GET_FEAT_ABORT(feat)
Get \texttt{BT\_OTS\_OACP\_FEAT\_ABORT} feature.

\textbf{Parameters}
\begin{itemize}
  \item feat – OTS features.
\end{itemize}
BT_OTS_OLCP_SET_FEAT_GO_TO(\texttt{feat})
Set \textit{BT\_OTS\_OLCP\_FEAT\_GO\_TO} feature.

\textbf{Parameters}
\begin{itemize}
\item \texttt{feat} – OTS features.
\end{itemize}

BT_OTS_OLCP_SET_FEAT_ORDER(\texttt{feat})
Set \textit{BT\_OTS\_OLCP\_FEAT\_ORDER} feature.

\textbf{Parameters}
\begin{itemize}
\item \texttt{feat} – OTS features.
\end{itemize}

BT_OTS_OLCP_SET_FEAT_NUM_REQ(\texttt{feat})
Set \textit{BT\_OTS\_OLCP\_FEAT\_NUM\_REQ} feature.

\textbf{Parameters}
\begin{itemize}
\item \texttt{feat} – OTS features.
\end{itemize}

BT_OTS_OLCP_SET_FEAT_CLEAR(\texttt{feat})
Set \textit{BT\_OTS\_OLCP\_FEAT\_CLEAR} feature.

\textbf{Parameters}
\begin{itemize}
\item \texttt{feat} – OTS features.
\end{itemize}

BT_OTS_OLCP_GET_FEAT_GO_TO(\texttt{feat})
Get \textit{BT\_OTS\_OLCP\_GET\_FEAT\_GO\_TO} feature.

\textbf{Parameters}
\begin{itemize}
\item \texttt{feat} – OTS features.
\end{itemize}

BT_OTS_OLCP_GET_FEAT_ORDER(\texttt{feat})
Get \textit{BT\_OTS\_OLCP\_GET\_FEAT\_ORDER} feature.

\textbf{Parameters}
\begin{itemize}
\item \texttt{feat} – OTS features.
\end{itemize}

BT_OTS_OLCP_GET_FEAT_NUM_REQ(\texttt{feat})
Get \textit{BT\_OTS\_OLCP\_GET\_FEAT\_NUM\_REQ} feature.

\textbf{Parameters}
\begin{itemize}
\item \texttt{feat} – OTS features.
\end{itemize}

BT_OTS_OLCP_GET_FEAT_CLEAR(\texttt{feat})
Get \textit{BT\_OTS\_OLCP\_GET\_FEAT\_CLEAR} feature.

\textbf{Parameters}
\begin{itemize}
\item \texttt{feat} – OTS features.
\end{itemize}

\texttt{BT\_OTS\_DATE\_TIME\_FIELD\_SIZE}

\texttt{BT\_OTS\_STOP}

\texttt{BT\_OTS\_CONTINUE}
### Typedefs

typedef int (*bt_ots_client_dirlisting_cb)(struct bt_ots_obj_metadata *meta)

Directory listing object metadata callback.

If a directory listing is decoded using `bt_ots_client_decode_dirlisting()`, this callback will be called for each object in the directory listing.

**Param meta**
The metadata of the decoded object

**Return**
`int BT_OTS_STOP` or `BT_OTS_CONTINUE`. `BT_OTS_STOP` can be used to stop the decoding.

### Enums

Properties of an OTS object.

**Values:**

- `enumerator BT_OTS_OBJ_PROP_DELETE = 0` Bit 0 Deletion of this object is permitted.
- `enumerator BT_OTS_OBJ_PROP_EXECUTE = 1` Bit 1 Execution of this object is permitted.
- `enumerator BT_OTS_OBJ_PROP_READ = 2` Bit 2 Reading this object is permitted.
- `enumerator BT_OTS_OBJ_PROP_WRITE = 3` Bit 3 Writing data to this object is permitted.
- `enumerator BT_OTS_OBJ_PROP_APPEND = 4` Bit 4 Appending data to this object is permitted. 
  
  Appending data increases its Allocated Size.

- `enumerator BT_OTS_OBJ_PROP_TRUNCATE = 5` Bit 5 Truncation of this object is permitted.

- `enumerator BT_OTS_OBJ_PROP_PATCH = 6` Bit 6 Patching this object is permitted.

  Patching this object overwrites some of the object's existing contents.

- `enumerator BT_OTS_OBJ_PROP_MARKED = 7` Bit 7 This object is a marked object.
Object Action Control Point Feature bits.

Values:

- **enumerator** `BT_OTS_OACP_FEAT_CREATE = 0`
  - Bit 0 OACP Create Op Code Supported.
- **enumerator** `BT_OTS_OACP_FEAT_DELETE = 1`
  - Bit 1 OACP Delete Op Code Supported.
- **enumerator** `BT_OTS_OACP_FEAT_CHECKSUM = 2`
  - Bit 2 OACP Calculate Checksum Op Code Supported.
- **enumerator** `BT_OTS_OACP_FEAT_EXECUTE = 3`
  - Bit 3 OACP Execute Op Code Supported.
- **enumerator** `BT_OTS_OACP_FEAT_READ = 4`
  - Bit 4 OACP Read Op Code Supported.
- **enumerator** `BT_OTS_OACP_FEAT_WRITE = 5`
  - Bit 5 OACP Write Op Code Supported.
- **enumerator** `BT_OTS_OACP_FEAT_APPEND = 6`
  - Bit 6 Appending Additional Data to Objects Supported.
- **enumerator** `BT_OTS_OACP_FEAT_TRUNCATE = 7`
  - Bit 7 Truncation of Objects Supported.
- **enumerator** `BT_OTS_OACP_FEAT_PATCH = 8`
  - Bit 8 Patching of Objects Supported.
- **enumerator** `BT_OTS_OACP_FEAT_ABORT = 9`
  - Bit 9 OACP Abort Op Code Supported.

**enum** `bt_ots_oacp_write_op_mode`

Values:

- **enumerator** `BT_OTS_OACP_WRITE_OP_MODE_NONE = 0`
- **enumerator** `BT_OTS_OACP_WRITE_OP_MODE_TRUNCATE = BIT(1)`

Object List Control Point Feature bits.

Values:

- **enumerator** `BT_OTS_OLCP_FEAT_GO_TO = 0`
  - Bit 0 OLCP Go To Op Code Supported.
enumerator BT_OTS_OLCPP_FEAT_ORDER = 1
    Bit 1 OLCP Order Op Code Supported.

everenumerator BT_OTS_OLCPP_FEAT_NUM_REQ = 2
    Bit 2 OLCP Request Number of Objects Op Code Supported.

everenumerator BT_OTS_OLCPP_FEAT_CLEAR = 3
    Bit 3 OLCP Clear Marking Op Code Supported.

Object metadata request bit field values.

Values:

everenumerator BT_OTS_METADATA_REQ_NAME = BIT(0)
    Request object name.

everenumerator BT_OTS_METADATA_REQ_TYPE = BIT(1)
    Request object type.

everenumerator BT_OTS_METADATA_REQ_SIZE = BIT(2)
    Request object size.

everenumerator BT_OTS_METADATA_REQ_CREATED = BIT(3)
    Request object first created time.

everenumerator BT_OTS_METADATA_REQ_MODIFIED = BIT(4)
    Request object last modified time.

everenumerator BT_OTS_METADATA_REQ_ID = BIT(5)
    Request object ID.

everenumerator BT_OTS_METADATA_REQ_PROPS = BIT(6)
    Request object properties.

everenumerator BT_OTS_METADATA_REQ_ALL = 0x7F
    Request all object metadata.

Functions

int bt_ots_obj_add(struct bt_ots *ots, const struct bt_ots_obj_add_param *param)

Add an object to the OTS instance.

This function adds an object to the OTS database. When the object is being added, a
callback obj_created() is called to notify the user about a new object ID.

Parameters

- ots – OTS instance.
- param – Object addition parameters.
Returns
ID of created object in case of success.

Returns
negative value in case of error.

int bt_ots_obj_delete(struct bt_ots *ots, uint64_t id)
Delete an object from the OTS instance.
This function deletes an object from the OTS database. When the object is deleted a
callback obj_deleted() is called to notify the user about this event. At this point, it is
possible to free allocated buffer for object data.

Parameters
• ots – OTS instance.
• id – ID of the object to be deleted (uint48).

Returns
0 in case of success or negative value in case of error.

void *bt_ots_svc_decl_get(struct bt_ots *ots)
Get the service declaration attribute.
This function is enabled for CONFIG_BT_OTS_SECONDARY_SVC configuration. The first
service attribute can be included in any other GATT service.

Parameters
• ots – OTS instance.

Returns
The first OTS attribute instance.

int bt_ots_init(struct bt_ots *ots, struct bt_ots_init_param *ots_init)
Initialize the OTS instance.

Parameters
• ots – OTS instance.
• ots_init – OTS initialization descriptor.

Returns
0 in case of success or negative value in case of error.

struct bt_ots *bt_ots_free_instance_get(void)
Get a free instance of OTS from the pool.

Returns
OTS instance in case of success or NULL in case of error.

int bt_ots_client_register(struct bt_ots_client *ots_inst)
Register an Object Transfer Service Instance.
Register an Object Transfer Service instance discovered on the peer. Call this function
when an OTS instance is discovered (discovery is to be handled by the higher layer).

Parameters

Returns
int 0 if success, ERRNO on failure.
int bt_ots_client_unregister(uint8_t index)

Unregister an Object Transfer Service Instance.

Unregister an Object Transfer Service instance when disconnect from the peer. Call this function when an ACL using OTS instance is disconnected.

**Parameters**

- `index` – [in] Index of OTS instance.

**Returns**

int 0 if success, ERRNO on failure.

uint8_t bt_ots_client_indicate_handler(struct bt_conn *conn, struct bt_gatt_subscribe_params *params, const void *data, uint16_t length)

OTS Indicate Handler function.

Set this function as callback for indicate handler when discovering OTS.

**Parameters**

- `conn` – Connection object. May be NULL, indicating that the peer is being unpaired.
- `params` – Subscription parameters.
- `data` – Attribute value data. If NULL then subscription was removed.
- `length` – Attribute value length.

int bt_ots_client_read_feature(struct bt_ots_client *otc_inst, struct bt_conn *conn)

Read the OTS feature characteristic.

**Parameters**

- `otc_inst` – Pointer to the OTC instance.
- `conn` – Pointer to the connection object.

**Returns**

int 0 if success, ERRNO on failure.

int bt_ots_client_select_id(struct bt_ots_client *otc_inst, struct bt_conn *conn, uint64_t obj_id)

Select an object by its Object ID.

**Parameters**

- `otc_inst` – Pointer to the OTC instance.
- `conn` – Pointer to the connection object.
- `obj_id` – Object’s ID.

**Returns**

int 0 if success, ERRNO on failure.

int bt_ots_client_select_first(struct bt_ots_client *otc_inst, struct bt_conn *conn)

Select the first object.

**Parameters**

- `otc_inst` – Pointer to the OTC instance.
- `conn` – Pointer to the connection object.

**Returns**

int 0 if success, ERRNO on failure.
int bt_ots_client_select_last(struct bt_ots_client *otc_inst, struct bt_conn *conn)
Select the last object.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.

Returns
int 0 if success, ERRNO on failure.

int bt_ots_client_select_next(struct bt_ots_client *otc_inst, struct bt_conn *conn)
Select the next object.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.

Returns
int 0 if success, ERRNO on failure.

int bt_ots_client_select_prev(struct bt_ots_client *otc_inst, struct bt_conn *conn)
Select the previous object.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.

Returns
int 0 if success, ERRNO on failure.

int bt_ots_client_read_object_metadata(struct bt_ots_client *otc_inst, struct bt_conn *conn, uint8_t metadata)
Read the metadata of the current object.
The metadata are returned in the obj_metadata_read() callback.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.
• metadata – Bitfield (BT_OTS_METADATA_REQ_*) of the metadata to read.

Returns
int 0 if success, ERRNO on failure.

int bt_ots_client_read_object_data(struct bt_ots_client *otc_inst, struct bt_conn *conn)
Read the data of the current selected object.
This will trigger an OACP read operation for the current size of the object with a 0 offset and then expect receiving the content via the L2CAP CoC.
The data of the object are returned in the obj_data_read() callback.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.

Returns
int 0 if success, ERRNO on failure.
bt_ots_client_write_object_data

Write the data of the current selected object.
This will trigger an OACP write operation for the current object with a specified offset and then expect transferring the content via the L2CAP CoC.
The length of the data written to object is returned in the obj_data_written() callback.

**Parameters**
- `otc_inst` – Pointer to the OTC instance.
- `conn` – Pointer to the connection object.
- `buf` – Pointer to the data buffer to be written.
- `len` – Size of data.
- `offset` – Offset to write, usually 0.

**Returns**
- `int 0` if success, `ERRNO` on failure.

bt_ots_client_get_object_checksum

Get the checksum of the current selected object.
This will trigger an OACP calculate checksum operation for the current object with a specified offset and length.
The checksum goes to OACP IND and obj_checksum_calculated() callback.

**Parameters**
- `otc_inst` – Pointer to the OTC instance.
- `conn` – Pointer to the connection object.
- `offset` – Offset to calculate, usually 0.
- `len` – Len of data to calculate checksum for. May be less than the current object's size, but shall not be larger.

**Returns**
- `int 0` if success, `ERRNO` on failure.

bt_ots_client_decode_dirlisting

Decode Directory Listing object into object metadata.
If the Directory Listing object contains multiple objects, then the callback will be called for each of them.

**Parameters**
- `data` – The data received for the directory listing object.
- `length` – Length of the data.
- `cb` – The callback that will be called for each object.

static inline int bt_ots_obj_id_to_str

Converts binary OTS Object ID to string.

**Parameters**
• **obj_id** – Object ID.
• **str** – Address of user buffer with enough room to store formatted string containing binary Object ID.
• **len** – Length of data to be copied to user string buffer. Refer to BTOTSOBJ_ID_STR_LEN about recommended value.

**Returns**
Number of successfully formatted bytes from binary ID.

```c
void bt_ots_metadata_display(struct bt_ots_obj_metadata *metadata, uint16_t count)
```
Displays one or more object metadata as text with LOG_INF.

**Parameters**
• **metadata** – Pointer to the first (or only) metadata in an array.
• **count** – Number of metadata objects to display information of.

`struct bt_ots_obj_type`

`#include <ots.h>` Type of an OTS object.

`struct bt_ots_obj_size`

`#include <ots.h>` Descriptor for OTS Object Size parameter.

**Public Members**

```c
tuint32_t cur
    Current Size.

tuint32_t alloc
    Allocated Size.
```

`struct bt_ots_feat`

`#include <ots.h>` Features of the OTS.

`struct bt_ots_date_time`

`#include <ots.h>` Date and Time structure.

`struct bt_ots_obj_metadata`

`#include <ots.h>` Metadata of an OTS object.

Used by the server as a descriptor for OTS object initialization. Used by the client to present object metadata to the application.

**Public Members**

```c
struct bt_ots_obj_type type
    Object Type.

struct bt_ots_obj_size size
    Object Size.
```
uint32_t props
    Object Properties.

struct bt_ots_obj_add_param
    #include <ots.h> Descriptor for OTS object addition.

Public Members

tuint32_t size
    Object size to allocate.

struct bt_ots_obj_type type
    Object type.

struct bt_ots_obj_created_desc
    #include <ots.h> Descriptor for OTS created object.

Descriptor for OTS object created by the application. This descriptor is returned by
bt_ots_cb::obj_created callback which contains further documentation on distinguish-
ing between server and client object creation.

Public Members

char *name
    Object name.

    The object name as a NULL terminated string.

    When the server creates a new object the name shall be > 0 and <=
    BT_OTS_OBJ_MAX_NAME_LEN When the client creates a new object the name shall
    be an empty string

struct bt_ots_obj_size size
    Object size.

    bt_ots_obj_size::alloc shall be >= bt_ots_obj_add_param::size

    When the server creates a new object bt_ots_obj_size::cur shall be
    <= bt_ots_obj_add_param::size When the client creates a new object
    bt_ots_obj_size::cur shall be 0

uint32_t props
    Object properties.

struct bt_ots_cb
    #include <ots.h> OTS callback structure.

Public Members
int (*obj_created)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, const struct bt_ots_obj_add_param *add_param, struct bt_ots_obj_created_desc *created_desc)

Object created callback.

This callback is called whenever a new object is created. Application can reject this request by returning an error when it does not have necessary resources to hold this new object. This callback is also triggered when the server creates a new object with `bt_ots_obj_add()` API.

**Param ots**
OTS instance.

**Param conn**
The connection that is requesting object creation or NULL if object is created by `bt_ots_obj_add()`.

**Param id**
Object ID.

**Param add_param**
Object creation requested parameters.

**Param created_desc**
Created object descriptor that shall be filled by the receiver of this callback.

**Return**
0 in case of success or negative value in case of error.

- **Return** -ENOTSUP if object type is not supported
- **Return** -ENOMEM if no available space for new object.
- **Return** -EINVAL if an invalid parameter is provided
- **Return** other negative values are treated as a generic operation failure

int (*obj_deleted)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id)

Object deleted callback.

This callback is called whenever an object is deleted. It is also triggered when the server deletes an object with `bt_ots_obj_delete()` API.

**Param ots**
OTS instance.

**Param conn**
The connection that deleted the object or NULL if this request came from the server.

**Param id**
Object ID.

**Return When**
an error is indicated by using a negative value, the object delete procedure is aborted and a corresponding failed status is returned to the client.

**Return**
0 in case of success.

- **Return** -EBUSY if the object is locked. This is generally not expected to be returned by the application as the OTS layer tracks object accesses. An object locked status is returned to the client.
- **Return** Other negative values in case of error. A generic operation failed status is returned to the client.

void (*obj_selected)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id)
Object selected callback.
This callback is called on successful object selection.

- **Param ots**
  OTS instance.

- **Param conn**
  The connection that selected new object.

- **Param id**
  Object ID.

```c
ssize_t (*obj_read)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, void **data, size_t len, off_t offset)
```
Object read callback.
This callback is called multiple times during the Object read operation. OTS module will keep requesting successive Object fragments from the application until the read operation is completed. The end of read operation is indicated by NULL data parameter.

- **Param ots**
  OTS instance.

- **Param conn**
  The connection that read object.

- **Param id**
  Object ID.

- **Param data**
  In: NULL once the read operations is completed. Out: Next chunk of data to be sent.

- **Param len**
  Remaining length requested by the client.

- **Param offset**
  Object data offset.

**Return**
Data length to be sent via data parameter. This value shall be smaller or equal to the len parameter.

**Return**
Negative value in case of an error.

```c
ssize_t (*obj_write)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, const void *data, size_t len, off_t offset, size_t rem)
```
Object write callback.
This callback is called multiple times during the Object write operation. OTS module will keep providing successive Object fragments to the application until the write operation is completed. The offset and length of each write fragment is validated by the OTS module to be within the allocated size of the object. The remaining length indicates data length remaining to be written and will decrease each write iteration until it reaches 0 in the last write fragment.

- **Param ots**
  OTS instance.

- **Param conn**
  The connection that wrote object.

- **Param id**
  Object ID.

- **Param data**
  Next chunk of data to be written.

- **Param len**
  Length of the current chunk of data in the buffer.

- **Param offset**
  Object data offset.
Param rem
Remaining length in the write operation.

Return
Number of bytes written in case of success, if the number of bytes written
does not match len, -EIO is returned to the L2CAP layer.

Return
A negative value in case of an error.

Return
-EINPROGRESS has a special meaning and is unsupported at the moment.
It should not be returned.

void (*obj_name_written)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, const
char *cur_name, const char *new_name)
Object name written callback.

This callback is called when the object name is written. This is a notification to the
application that the object name will be updated by the OTS service implementa-
tion.

Param ots
OTS instance.

Param conn
The connection that wrote object name.

Param id
Object ID.

Param cur_name
Current object name.

Param new_name
New object name.

int (*obj_cal_checksum)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, off_t
offset, size_t len, void **data)
Object Calculate checksum callback.

This callback is called when the OACP Calculate Checksum procedure is performed.
Because object data is opaque to OTS, the application is the only one who knows
where data is and should return pointer of actual object data.

Param ots
[in] OTS instance.

Param conn
[in] The connection that wrote object.

Param id
[in] Object ID.

Param offset
[in] The first octet of the object contents need to be calculated.

Param len
[in] The length number of octets object name.

Param data
[out] Pointer of actual object data.

Return
0 to accept, or any negative value to reject.

struct bt_ots_init_param

#include <ots.h> Descriptor for OTS initialization.

struct bt_ots_client

#include <ots.h> OTS client instance.
struct bt_ots_client_cb

#include <ots.h> OTS client callback structure.

Public Members

void (*obj_selected)(struct bt_ots_client *ots_inst, struct bt_conn *conn, int err)
Callback function when a new object is selected.
Called when a new object is selected and the current object has changed. The cur_object in ots_inst will have been reset, and metadata should be read again with bt_ots_client_read_object_metadata().

Param ots_inst
   Pointer to the OTC instance.

Param conn
   The connection to the peer device.

Param err
   Error code (bt_ots_olcp_res_code).

int (*obj_data_read)(struct bt_ots_client *ots_inst, struct bt_conn *conn, uint32_t offset, uint32_t len, uint8_t *data_p, bool is_complete)
Callback function for the data of the selected object.
Called when the data of the selected object are read using bt_ots_client_read_object_data().

Param ots_inst
   Pointer to the OTC instance.

Param conn
   The connection to the peer device.

Param offset
   Offset of the received data.

Param len
   Length of the received data.

Param data_p
   Pointer to the received data.

Param is_complete
   Indicate if the whole object has been received.

Return
   int BT_OTS_STOP or BT_OTS_CONTINUE. BT_OTS_STOP can be used to stop reading.

void (*obj_metadata_read)(struct bt_ots_client *ots_inst, struct bt_conn *conn, int err, uint8_t metadata_read)
Callback function for metadata of the selected object.
Called when metadata of the selected object are read using bt_ots_client_read_object_metadata(). Not all of the metadata may have been initialized.

Param ots_inst
   Pointer to the OTC instance.

Param conn
   The connection to the peer device.

Param err
   Error value. 0 on success, GATT error or ERRNO on fail.

Param metadata_read
   Bitfield of the metadata that was successfully read.
void (*obj_data_written)(struct bt_ots_client *ots_inst, struct bt_conn *conn, size_t len)

Callback function for the data of the write object.
Called when the data of the selected object is written using
bt_ots_client_write_object_data().
  \textbf{Param} ots_inst
  Pointer to the OTC instance.
  \textbf{Param} conn
  The connection to the peer device.
  \textbf{Param} len
  Length of the written data.

void (*obj_checksum_calculated)(struct bt_ots_client *ots_inst, struct bt_conn *conn, int err, uint32_t checksum)

Callback function when checksum indication is received.
Called when the oacp_ind_handler received response of OP
BT_GATT_OTS_OACP_PROC_CHECKSUM_CALC.
  \textbf{Param} ots_inst
  Pointer to the OTC instance.
  \textbf{Param} conn
  The connection to the peer device.
  \textbf{Param} err
  Error code (bt_gatt_ots_oacp_res_code).
  \textbf{Param} checksum
  Checksum if error code is BT_GATT_OTS_OACP_RES_SUCCESS, otherwise 0.

Service Discovery Protocol (SDP)

API Reference

\textit{group} bt_sdp

Service class identifiers of standard services and service groups

\texttt{BT_SDP_SDP_SERVER_SVCLASS}
  Service Discovery Server.

\texttt{BT_SDP_BROWSE_GRP_DESC_SVCLASS}
  Browse Group Descriptor.

\texttt{BT_SDP_PUBLIC_BROWSE_GROUP}
  Public Browse Group.

\texttt{BT_SDP_SERIAL_PORT_SVCLASS}
  Serial Port.

\texttt{BT_SDP_LAN_ACCESS_SVCLASS}
  LAN Access Using PPP.
**BT_SDP_DIALUP_NET_SVCLASS**
Dialup Networking.

**BT_SDP_IRMC_SYNC_SVCLASS**
IrMC Sync.

**BT_SDP_OBEX_OBJPUSH_SVCLASS**
OBEX Object Push.

**BT_SDP_OBEX_FILETRANS_SVCLASS**
OBEX File Transfer.

**BT_SDP_IRMC_SYNC_CMD_SVCLASS**
IrMC Sync Command.

**BT_SDP_HEADSET_SVCLASS**
Headset.

**BT_SDP_CORDLESS_TELEPHONY_SVCLASS**
Cordless Telephony.

**BT_SDP_AUDIO_SOURCE_SVCLASS**
Audio Source.

**BT_SDP_AUDIO_SINK_SVCLASS**
Audio Sink.

**BT_SDP_AV_REMOTE_TARGET_SVCLASS**
A/V Remote Control Target.

**BT_SDP_ADVANCED_AUDIO_SVCLASS**
Advanced Audio Distribution.

**BT_SDP_AV_REMOTE_SVCLASS**
A/V Remote Control.

**BT_SDP_AV_REMOTE_CONTROLLER_SVCLASS**
A/V Remote Control Controller.

**BT_SDP_INTERCOM_SVCLASS**
Intercom.

**BT_SDP_FAX_SVCLASS**
Fax.

**BT_SDP_HEADSET_AGW_SVCLASS**
Headset AG.
BT_SDP_WAP_SVCLASS
  WAP.

BT_SDP_WAP_CLIENT_SVCLASS
  WAP Client.

BT_SDP_PANU_SVCLASS
  Personal Area Networking User.

BT_SDP_NAP_SVCLASS
  Network Access Point.

BT_SDP_GN_SVCLASS
  Group Network.

BT_SDP_DIRECT_PRINTING_SVCLASS
  Direct Printing.

BT_SDP_REFERENCE_PRINTING_SVCLASS
  Reference Printing.

BT_SDP_IMAGING_SVCLASS
  Basic Imaging Profile.

BT_SDP_IMAGING_RESPONDER_SVCLASS
  Imaging Responder.

BT_SDP_IMAGING_ARCHIVE_SVCLASS
  Imaging Automatic Archive.

BT_SDP_IMAGING_REFOBJ_SVCLASS
  Imaging Referenced Objects.

BT_SDP_HANDSFREE_SVCLASS
  Handsfree.

BT_SDP_HANDSFREE_AGW_SVCLASS
  Handsfree Audio Gateway.

BT_SDP_DIRECT_PRT_REFOBJ_SVCLASS
  Direct Printing Reference Objects Service.

BT_SDP_REFLECTED_UI_SVCLASS
  Reflected UI.

BT_SDP_BASIC_PRINTING_SVCLASS
  Basic Printing.
BT_SDP_PRINTING_STATUS_SVCLASS
Printing Status.

BT_SDP_HID_SVCLASS
Human Interface Device Service.

BT_SDP_HCR_SVCLASS
Hardcopy Cable Replacement.

BT_SDP_HCR_PRINT_SVCLASS
HCR Print.

BT_SDP_HCR_SCAN_SVCLASS
HCR Scan.

BT_SDP_CIP_SVCLASS
Common ISDN Access.

BT_SDP_VIDEO_CONF_GW_SVCLASS
Video Conferencing Gateway.

BT_SDP_UDI_MT_SVCLASS
UDI MT.

BT_SDP_UDI_TA_SVCLASS
UDI TA.

BT_SDP_AV_SVCLASS
Audio/Video.

BT_SDP_SAP_SVCLASS
SIM Access.

BT_SDP_PBAP_PCE_SVCLASS
Phonebook Access Client.

BT_SDP_PBAP_PSE_SVCLASS
Phonebook Access Server.

BT_SDP_PBAP_SVCLASS
Phonebook Access.

BT_SDP_MAP_MSE_SVCLASS
Message Access Server.

BT_SDP_MAP_MCE_SVCLASS
Message Notification Server.
BT_SDPMAP_SVCLASS
    Message Access Profile.

BT_SDP_GNSS_SVCLASS
    GNSS.

BT_SDP_GNSS_SERVER_SVCLASS
    GNSS Server.

BT_SDP_MPS_SC_SVCLASS
    MPS SC.

BT_SDP_MPS_SVCLASS
    MPS.

BT_SDP_PNP_INFO_SVCLASS
    PnP Information.

BT_SDP_GENERIC_NETWORKING_SVCLASS
    Generic Networking.

BT_SDP_GENERIC_FILETRANS_SVCLASS
    Generic File Transfer.

BT_SDP_GENERIC_AUDIO_SVCLASS
    Generic Audio.

BT_SDP_GENERIC_TELEPHONY_SVCLASS
    Generic Telephony.

BT_SDP_UPNP_SVCLASS
    UPnP Service.

BT_SDP_UPNP_IP_SVCLASS
    UPnP IP Service.

BT_SDP_UPNP_PAN_SVCLASS
    UPnP IP PAN.

BT_SDP_UPNP_LAP_SVCLASS
    UPnP IP LAP.

BT_SDP_UPNP_L2CAP_SVCLASS
    UPnP IP L2CAP.

BT_SDP_VIDEO_SOURCE_SVCLASS
    Video Source.
**BT_SDP_VIDEO_SINK_SVCLASS**  
Video Sink.

**BT_SDP_VIDEO_DISTRIBUTION_SVCLASS**  
Video Distribution.

**BT_SDP_HDP_SVCLASS**  
HDP.

**BT_SDP_HDP_SOURCE_SVCLASS**  
HDP Source.

**BT_SDP_HDP_SINK_SVCLASS**  
HDP Sink.

**BT_SDP_GENERIC_ACCESS_SVCLASS**  
Generic Access Profile.

**BT_SDP_GENERIC_ATTRIB_SVCLASS**  
Generic Attribute Profile.

**BT_SDP_APPLE_AGENT_SVCLASS**  
Apple Agent.

### Attribute identifier codes

Possible values for attribute-id are listed below.  
See SDP Spec, section “Service Attribute Definitions” for more details.

**BT_SDP_ATTR_RECORD_HANDLE**  
Service Record Handle.

**BT_SDP_ATTR_SVCLASS_ID_LIST**  
Service Class ID List.

**BT_SDP_ATTR_RECORD_STATE**  
Service Record State.

**BT_SDP_ATTR_SERVICE_ID**  
Service ID.

**BT_SDP_ATTR_PROTO_DESC_LIST**  
Protocol Descriptor List.

**BT_SDP_ATTR_BROWSE_GRP_LIST**  
Browse Group List.
BT_SDP_ATTR_LANG_BASE_ATTR_ID_LIST
Language Base Attribute ID List.

BT_SDP_ATTR_SVCINFO_TTL
Service Info Time to Live.

BT_SDP_ATTR_SERVICE_AVAILABILITY
Service Availability.

BT_SDP_ATTR_PROFILE_DESC_LIST
Bluetooth Profile Descriptor List.

BT_SDP_ATTR_DOC_URL
Documentation URL.

BT_SDP_ATTR_CLNT_EXEC_URL
Client Executable URL.

BT_SDP_ATTR_ICON_URL
Icon URL.

BT_SDP_ATTR_ADD_PROTO_DESC_LIST
Additional Protocol Descriptor List.

BT_SDP_ATTR_GROUP_ID
Group ID.

BT_SDP_ATTR_IP_SUBNET
IP Subnet.

BT_SDP_ATTR_VERSION_NUM_LIST
Version Number List.

BT_SDP_ATTR_SUPPORTED_FEATURES_LIST
Supported Features List.

BT_SDP_ATTR_GOEP_L2CAP_PSM
GOEP L2CAP PSM.

BT_SDP_ATTR_SVCDB_STATE
Service Database State.

BT_SDP_ATTR_MPSD_SCENARIOS
MPSD Scenarios.

BT_SDP_ATTR_MPMD_SCENARIOS
MPMD Scenarios.
BT_SDP_ATTR_MPS_DEPENDENCIES
   Supported Profiles & Protocols.

BT_SDP_ATTR_SERVICE_VERSION
   Service Version.

BT_SDP_ATTR_EXTERNAL_NETWORK
   External Network.

BT_SDP_ATTR_SUPPORTED_DATASTORES_LIST
   Supported Data Stores List.

BT_SDP_ATTR_DATA_EXCHANGE_SPEC
   Data Exchange Specification.

BT_SDP_ATTR_NETWORK
   Network.

BT_SDP_ATTR_FAX_CLASS1_SUPPORT
   Fax Class 1 Support.

BT_SDP_ATTR_REMOTE_AUDIO_VOLUME_CONTROL
   Remote Audio Volume Control.

BT_SDP_ATTR_MCAP_SUPPORTEDPROCEDURES
   MCAP Supported Procedures.

BT_SDP_ATTR_FAX_CLASS20_SUPPORT
   Fax Class 2.0 Support.

BT_SDP_ATTR_SUPPORTEDFORMATS_LIST
   Supported Formats List.

BT_SDP_ATTR_FAX_CLASS2_SUPPORT
   Fax Class 2 Support (vendor-specific)

BT_SDP_ATTR_AUDIO_FEEDBACK_SUPPORT
   Audio Feedback Support.

BT_SDP_ATTR_NETWORKADDRESS
   Network Address.

BT_SDP_ATTR_WAP_GATEWAY
   WAP Gateway.

BT_SDP_ATTR_HOMEPAGE_URL
   Homepage URL.
BT_SDP_ATTR_WAP_STACK_TYPE
WAP Stack Type.

BT_SDP_ATTR_SECURITY_DESC
Security Description.

BT_SDP_ATTR_NET_ACCESS_TYPE
Net Access Type.

BT_SDP_ATTR_MAX_NET_ACCESSRATE
Max Net Access Rate.

BT_SDP_ATTR_IP4_SUBNET
IPv4 Subnet.

BT_SDP_ATTR_IP6_SUBNET
IPv6 Subnet.

BT_SDP_ATTR_SUPPORTED_CAPABILITIES
BIP Supported Capabilities.

BT_SDP_ATTR_SUPPORTED_FEATURES
BIP Supported Features.

BT_SDP_ATTR_SUPPORTED_FUNCTIONS
BIP Supported Functions.

BT_SDP_ATTR_TOTAL_IMAGING_DATA_CAPACITY
BIP Total Imaging Data Capacity.

BT_SDP_ATTR_SUPPORTED_REPOSITORIES
Supported Repositories.

BT_SDP_ATTR_MAS_INSTANCE_ID
MAS Instance ID.

BT_SDP_ATTR_SUPPORTED_MESSAGE_TYPES
Supported Message Types.

BT_SDP_ATTR_PBAP_SUPPORTED_FEATURES
PBAP Supported Features.

BT_SDP_ATTR_MAP_SUPPORTED_FEATURES
MAP Supported Features.

BT_SDP_ATTR_SPECIFICATION_ID
Specification ID.
BT_SDAPR VENDOR_ID
Vendor ID.

BT_SDAPR PRODUCT_ID
Product ID.

BT_SDAPR VERSION
Version.

BT_SDAPR PRIMARY_RECORD
Primary Record.

BT_SDAPR VENDOR_ID_SOURCE
Vendor ID Source.

BT_SDAPR HID_DEVICE_RELEASE_NUMBER
HID Device Release Number.

BT_SDAPR HID_PARSER_VERSION
HID Parser Version.

BT_SDAPR HID_DEVICE_SUBCLASS
HID Device Subclass.

BT_SDAPR HID_COUNTRY_CODE
HID Country Code.

BT_SDAPR HID_VIRTUAL_CABLE
HID Virtual Cable.

BT_SDAPR HID_RECONNECT_INITIATE
HID Reconnect Initiate.

BT_SDAPR HID_DESCRIPTOR_LIST
HID Descriptor List.

BT_SDAPR HID_LANG_ID_BASE_LIST
HID Language ID Base List.

BT_SDAPR HID_SDAP_DISABLE
HID SDP Disable.

BT_SDAPR HID_BATTERY_POWER
HID Battery Power.

BT_SDAPR HID_REMOTE_WAKEUP
HID Remote Wakeup.
BT_SDP_ATTR_HID_PROFILE_VERSION
HID Profile Version.

BT_SDP_ATTR_HID_SUPERVISION_TIMEOUT
HID Supervision Timeout.

BT_SDP_ATTR_HID_NORMALLY_CONNECTABLE
HID Normally Connectable.

BT_SDP_ATTR_HID_BOOT_DEVICE
HID Boot Device.

The Data representation in SDP PDUs (pps 339, 340 of BT SDP Spec)

These are the exact data type+size descriptor values that go into the PDU buffer.
The datatype (leading 5 bits) + size descriptor (last 3 bits) is 8 bits. The size descriptor is
critical to extract the right number of bytes for the data value from the PDU.

For most basic types, the datatype+size descriptor is straightforward. However for con-
structed types and strings, the size of the data is in the next “n” bytes following the 8 bits
(datatype+size) descriptor. Exactly what the “n” is specified in the 3 bits of the data size
descriptor.

TextString and URLString can be of size $2^{8, 16, 32}$ bytes DataSequence and DataSe-
quenceAlternates can be of size $2^{8, 16, 32}$ The size are computed post-facto in the API
and are not known apriori.

BT_SDP_DATA_NIL
Nil, the null type.

BT_SDP_UINT8
Unsigned 8-bit integer.

BT_SDP_UINT16
Unsigned 16-bit integer.

BT_SDP_UINT32
Unsigned 32-bit integer.

BT_SDP_UINT64
Unsigned 64-bit integer.

BT_SDP_UINT128
Unsigned 128-bit integer.

BT_SDP_INT8
Signed 8-bit integer.

BT_SDP_INT16
Signed 16-bit integer.
BT_SDP_INT32
Signed 32-bit integer.

BT_SDP_INT64
Signed 64-bit integer.

BT_SDP_INT128
Signed 128-bit integer.

BT_SDP_UUID_UNSPEC
UUID, unspecified size.

BT_SDP_UUID16
UUID, 16-bit.

BT_SDP_UUID32
UUID, 32-bit.

BT_SDP_UUID128
UUID, 128-bit.

BT_SDP_TEXT_STR_UNSPEC
Text string, unspecified size.

BT_SDP_TEXT_STR8
Text string, 8-bit length.

BT_SDP_TEXT_STR16
Text string, 16-bit length.

BT_SDP_TEXT_STR32
Text string, 32-bit length.

BT_SDP_BOOL
Boolean.

BT_SDP_SEQ_UNSPEC
Data element sequence, unspecified size.

BT_SDP_SEQ8
Data element sequence, 8-bit length.

BT_SDP_SEQ16
Data element sequence, 16-bit length.

BT_SDP_SEQ32
Data element sequence, 32-bit length.
BT_SDP_ALT_UNSPEC
  Data element alternative, unspecified size.

BT_SDP_ALT8
  Data element alternative, 8-bit length.

BT_SDP_ALT16
  Data element alternative, 16-bit length.

BT_SDP_ALT32
  Data element alternative, 32-bit length.

BT_SDP_URL_STR_UNSPEC
  URL string, unspecified size.

BT_SDP_URL_STR8
  URL string, 8-bit length.

BT_SDP_URL_STR16
  URL string, 16-bit length.

BT_SDP_URL_STR32
  URL string, 32-bit length.

Defines

BT_SDP_SERVER_RECORD_HANDLE

BT_SDP_PRIMARY_LANG_BASE

BT_SDP_ATTR_SVCNAME_PRIMARY

BT_SDP_ATTR_SVCDESC_PRIMARY

BT_SDP_ATTR_PROVNAME_PRIMARY

BT_SDP_TYPE_DESC_MASK

BT_SDP_SIZE_DESC_MASK

BT_SDP_SIZE_INDEX_OFFSET

BT_SDP_ARRAY_8(...)
  Declare an array of 8-bit elements in an attribute.

BT_SDP_ARRAY_16(...)
  Declare an array of 16-bit elements in an attribute.
**BT_SDP_ARRAY_32(...)**
Declare an array of 32-bit elements in an attribute.

**BT_SDP_TYPE_SIZE(_type)**
Declare a fixed-size data element header.

**Parameters**
- _type – Data element header containing type and size descriptors.

**BT_SDP_TYPE_SIZE_VAR(_type, _size)**
Declare a variable-size data element header.

**Parameters**
- _type – Data element header containing type and size descriptors.
- _size – The actual size of the data.

**BT_SDP_DATA_ELEM_LIST(...)**
Declare a list of data elements.

**BT_SDP_NEW_SERVICE**
SDP New Service Record Declaration Macro.
Helper macro to declare a new service record. Default attributes: Record Handle, Record State, Language Base, Root Browse Group

**BT_SDP_LIST(_att_id, _type_size, _data_elem_seq)**
Generic SDP List Attribute Declaration Macro.
Helper macro to declare a list attribute.

**Parameters**
- _att_id – List Attribute ID.
- _data_elem_seq – Data element sequence for the list.
- _type_size – SDP type and size descriptor.

**BT_SDP_SERVICE_ID(_uuid)**
SDP Service ID Attribute Declaration Macro.
Helper macro to declare a service ID attribute.

**Parameters**
- _uuid – Service ID 16bit UUID.

**BT_SDP_SERVICE_NAME(_name)**
SDP Name Attribute Declaration Macro.
Helper macro to declare a service name attribute.

**Parameters**
- _name – Service name as a string (up to 256 chars).

**BT_SDP_SUPPORTED_FEATURES(_features)**
SDP Supported Features Attribute Declaration Macro.
Helper macro to declare supported features of a profile/protocol.

**Parameters**
- _features – Feature mask as 16bit unsigned integer.
**BT_SDP_RECORD**(_attrs_
  
  SDP Service Declaration Macro.
  
  Helper macro to declare a service.
  
  **Parameters**
  
  • _attrs_ – List of attributes for the service record.

**Typedefs**

```c
typedef uint8_t (*bt_sdp_discover_func_t)(struct bt_conn *conn, struct bt_sdp_client_result *result)
```

Callback type reporting to user that there is a resolved result on remote for given UUID and the result record buffer can be used by user for further inspection.

A function of this type is given by the user to the `bt_sdp_discover_params` object. It'll be called on each valid record discovery completion for given UUID. When UUID resolution gives back no records then NULL is passed to the user. Otherwise user can get valid record(s) and then the internal hint ‘next record’ is set to false saying the UUID resolution is complete or the hint can be set by caller to true meaning that next record is available for given UUID. The returned function value allows the user to control retrieving follow-up resolved records if any. If the user doesn't want to read more resolved records for given UUID since current record data fulfills its requirements then should return **BT_SDP_DISCOVER_UUID_STOP**. Otherwise returned value means more subcall iterations are allowable.

**Param conn**
  
  Connection object identifying connection to queried remote.

**Param result**
  
  Object pointing to logical unparsed SDP record collected on base of response driven by given UUID.

**Return**
  
  **BT_SDP_DISCOVER_UUID_STOP** in case of no more need to read next record data and continue discovery for given UUID. By returning **BT_SDP_DISCOVER_UUID_CONTINUE** user allows this discovery continuation.

**Enums**

Helper enum to be used as return value of `bt_sdp_discover_func_t`.

The value informs the caller to perform further pending actions or stop them.

**Values:**

```c
enumerator BT_SDP_DISCOVER_UUID_STOP = 0
enumerator BT_SDP_DISCOVER_UUID_CONTINUE
```

**Enum `bt_sdp_proto`**

Protocols to be asked about specific parameters.

**Values:**
enumerator BT_SDP_PROTO_RFCOMM = 0x0003

enumerator BT_SDPPROTO_L2CAP = 0x0100

Functions

int bt_sdp_register_service(struct bt_sdp_record *service)

Register a Service Record. Applications can make use of macros such as BT_SDP_DECLARE_SERVICE, BT_SDP_LIST, BT_SDP_SERVICE_ID, BT_SDP_SERVICE_NAME, etc. A service declaration must start with BT_SDP_NEW_SERVICE.

Parameters
• service – Service record declared using BT_SDP_DECLARE_SERVICE.

Returns
0 in case of success or negative value in case of error.

int bt_sdp_discover (struct bt_conn *conn, const struct bt_sdp_discover_params *params)

Allows user to start SDP discovery session.

The function performs SDP service discovery on remote server driven by user delivered discovery parameters. Discovery session is made as soon as no SDP transaction is ongoing between peers and if any then this one is queued to be processed at discovery completion of previous one. On the service discovery completion the callback function will be called to get feedback to user about findings.

Parameters
• conn – Object identifying connection to remote.
• params – SDP discovery parameters.

Returns
0 in case of success or negative value in case of error.

int bt_sdp_discover_cancel (struct bt_conn *conn, const struct bt_sdp_discover_params *params)

Release waiting SDP discovery request.

It can cancel valid waiting SDP client request identified by SDP discovery parameters object.

Parameters
• conn – Object identifying connection to remote.
• params – SDP discovery parameters.

Returns
0 in case of success or negative value in case of error.

int bt_sdp_get_proto_param (const struct net_buf *buf, enum bt_sdp_proto proto, uint16_t *param)

Give to user parameter value related to given stacked protocol UUID.

API extracts specific parameter associated with given protocol UUID available in Protocol Descriptor List attribute.

Parameters
• **buf** – Original buffered raw record data.
• **proto** – Known protocol to be checked like RFCOMM or L2CAP.
• **param** – On success populated by found parameter value.

**Returns**
0 on success when specific parameter associated with given protocol value is found, or negative if error occurred during processing.

```c
int bt_sdp_get_addl_proto_param(const struct net_buf *buf, enum bt_sdp_proto proto,
                                uint8_t param_index, uint16_t *param)
```

Get additional parameter value related to given stacked protocol UUID.

API extracts specific parameter associated with given protocol UUID available in Additional Protocol Descriptor List attribute.

**Parameters**
- **buf** – Original buffered raw record data.
- **proto** – Known protocol to be checked like RFCOMM or L2CAP.
- **param_index** – There may be more than one parameter related to the given protocol UUID. This function returns the result that is indexed by this parameter. It's value is from 0, 0 means the first matched result, 1 means the second matched result.
- **param** – [out] On success populated by found parameter value.

**Returns**
0 on success when a specific parameter associated with a given protocol value is found, or negative if error occurred during processing.

```c
int bt_sdp_get_profile_version(const struct net_buf *buf, uint16_t profile, uint16_t *version)
```

Get profile version.

Helper API extracting remote profile version number. To get it proper generic profile parameter needs to be selected usually listed in SDP Interoperability Requirements section for given profile specification.

**Parameters**
- **buf** – Original buffered raw record data.
- **profile** – Profile family identifier the profile belongs.
- **version** – On success populated by found version number.

**Returns**
0 on success, negative value if error occurred during processing.

```c
int bt_sdp_get_features(const struct net_buf *buf, uint16_t *features)
```

Get SupportedFeatures attribute value.

Allows if exposed by remote retrieve SupportedFeature attribute.

**Parameters**
- **buf** – Buffer holding original raw record data from remote.
- **features** – On success object to be populated with SupportedFeature mask.

**Returns**
0 on success if feature found and valid, negative in case any error
struct bt_sdp_data_elem
#include <sdp.h>  SDP Generic Data Element Value.

Public Members

uint8_t type
Type of the data element.

uint32_t data_size
Size of the data element.

uint32_t total_size
Total size of the data element.

struct bt_sdp_attribute
#include <sdp.h>  SDP Attribute Value.

Public Members

uint16_t id
Attribute ID.

struct bt_sdp_data_elem *val
Attribute data.

struct bt_sdp_record
#include <sdp.h>  SDP Service Record Value.

Public Members

uint32_t handle
Redundant, for quick ref.

struct bt_sdp_attribute **attrs
Base addr of attr array.

size_t attr_count
Number of attributes.

uint8_t index
Index of the record in LL.

struct bt_sdp_record *next
Next service record.

struct bt_sdp_client_result
#include <sdp.h>  Generic SDP Client Query Result data holder.

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Public Members

```c
struct net_buf *resp_buf
    buffer containing unparsed SDP record result for given UUID

bool next_record_hint
    flag pointing that there are more result chunks for given UUID

const struct bt_uuid *uuid
    Reference to UUID object on behalf one discovery was started.
```

```c
struct bt_sdp_discover_params
    #include <sdp.h> Main user structure used in SDP discovery of remote.
```

**Public Members**

```c
const struct bt_uuid *uuid
    UUID (service) to be discovered on remote SDP entity.

bt_sdp_discover_func_t func
    Discover callback to be called on resolved SDP record.

struct net_buf_pool *pool
    Memory buffer enabled by user for SDP query results
```

**Bluetooth Audio Volume Control**

**API Reference**

*group bt_gatt_vcp*

Volume Control Profile (VCP)

[Experimental] Users should note that the APIs can change as a part of ongoing development.

**Defines**

```c
BT_VCP_VOL_REND_VOCS_CNT

BT_VCP_VOL_REND_AICS_CNT

BT_VCP_ERR_INVALID_COUNTER
    Volume Control Service Error codes.

BT_VCP_ERR_OP_NOT_SUPPORTED
```
BT_VCP_STATE_UNMUTED
Volume Control Service Mute Values.

BT_VCP_STATE_MUTED

Functions

int bt_vcp_vol_rend_included_get(struct bt_vcp_included *included)
Get Volume Control Service included services.
Returns a pointer to a struct that contains information about the Volume Control Service included service instances, such as pointers to the Volume Offset Control Service (Volume Offset Control Service) or Audio Input Control Service (AICS) instances.

Parameters
• included – [out] Pointer to store the result in.

Returns
0 if success, errno on failure.

int bt_vcp_vol_rend_register(struct bt_vcp_vol_rend_register_param *param)
Register the Volume Control Service.
This will register and enable the service and make it discoverable by clients.

Parameters
• param – Volume Control Service register parameters.

Returns
0 if success, errno on failure.

int bt_vcp_vol_rend_set_step(uint8_t volume_step)
Set the Volume Control Service volume step size.
Set the value that the volume changes, when changed relatively with e.g. bt_vcp_vol_rend_vol_down or bt_vcp_vol_rend_vol_up.
This can only be done as the server.

Parameters
• volume_step – The volume step size (1-255).

Returns
0 if success, errno on failure.

int bt_vcp_vol_rend_get_state(void)
Get the Volume Control Service volume state.

Returns
0 if success, errno on failure.

int bt_vcp_vol_rend_get_flags(void)
Get the Volume Control Service flags.

Returns
0 if success, errno on failure.

int bt_vcp_vol_rend_vol_down(void)
Turn the volume down by one step on the server.

Returns
0 if success, errno on failure.
int bt_vcp_vol_rend_vol_up(void)
   Turn the volume up by one step on the server.

   Returns
   0 if success, errno on failure.

int bt_vcp_vol_rend_unmute_vol_down(void)
   Turn the volume down and unmute the server.

   Returns
   0 if success, errno on failure.

int bt_vcp_vol_rend_unmute_vol_up(void)
   Turn the volume up and unmute the server.

   Returns
   0 if success, errno on failure.

int bt_vcp_vol_rend_set_vol(uint8_t volume)
   Set the volume on the server.

   Parameters
   • volume – The absolute volume to set.

   Returns
   0 if success, errno on failure.

int bt_vcp_vol_rend_unmute(void)
   Unmute the server.

   Returns
   0 if success, errno on failure.

int bt_vcp_vol_rend_mute(void)
   Mute the server.

   Returns
   0 if success, errno on failure.

int bt_vcp_vol_ctlr_cb_register(struct bt_vcp_vol_ctlr_cb *cb)
   Registers the callbacks used by the Volume Controller.

   Parameters
   • cb – The callback structure.

   Return values
   • 0 – on success
   • -EINVAL – if cb is NULL
   • -EALREADY – if cb was already registered

int bt_vcp_vol_ctlr_cb_unregister(struct bt_vcp_vol_ctlr_cb *cb)
   Unregisters the callbacks used by the Volume Controller.

   Parameters
   • cb – The callback structure.

   Return values
   • 0 – on success
   • -EINVAL – if cb is NULL
   • -EALREADY – if cb was not registered
int bt_vcp_vol_ctlr_discover(struct bt_conn *conn, struct bt_vcp_vol_ctlr **vol_ctlr)
Discover Volume Control Service and included services.

This will start a GATT discovery and setup handles and subscriptions. This shall be
called once before any other actions can be executed for the peer device, and the
bt_vcp_volCtlr_ch:discover callback will notify when it is possible to start remote op-
erations.

This shall only be done as the client,

**Parameters**
- conn – The connection to discover Volume Control Service for.

**Returns**
0 if success, errno on failure.

struct bt_vcp_vol_ctlr *bt_vcp_vol_ctlr_get_by_conn(const struct bt_conn *conn)
Get the volume controller from a connection pointer.

Get the Volume Control Profile Volume Controller pointer from a connection pointer. Only
volume controllers that have been initiated via bt_vcp_vol_ctlr_discover() can be
retrieved.

**Parameters**
- conn – Connection pointer.

**Return values**
- Pointer – to a Volume Control Profile Volume Controller instance
- NULL – if conn is NULL or if the connection has not done discovery yet

int bt_vcp_vol_ctlr_conn_get(const struct bt_vcp_vol_ctlr *vol_ctlr, struct bt_conn **conn)
Get the connection pointer of a client instance.

Get the Bluetooth connection pointer of a Volume Control Service client instance.

**Parameters**
- vol_ctlr – Volume Controller instance pointer.
- conn – [out] Connection pointer.

**Returns**
0 if success, errno on failure.

int bt_vcp_vol_ctlr_included_get(struct bt_vcp_vol_ctlr *vol_ctlr, struct bt_vcp_included *included)
Get Volume Control Service included services.

Returns a pointer to a struct that contains information about the Volume Control Ser-
vice included service instances, such as pointers to the Volume Offset Control Service
(Volume Offset Control Service) or Audio Input Control Service (AICS) instances.

Requires that CONFIG_BT_VCP_VOL_CTLR_VOCS or CONFIG_BT_VCP_VOL_CTLR_AICS is en-
abled.

**Parameters**
- vol_ctlr – Volume Controller instance pointer.
- included – [out] Pointer to store the result in.

**Returns**
0 if success, errno on failure.
int `bt_vcp_vol_ctlr_read_state` (struct `bt_vcp_vol_ctlr` *`vol_ctlr`)
Read the volume state of a remote Volume Renderer.

**Parameters**
- `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

int `bt_vcp_vol_ctlr_read_flags` (struct `bt_vcp_vol_ctlr` *`vol_ctlr`)
Read the volume flags of a remote Volume Renderer.

**Parameters**
- `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

int `bt_vcp_vol_ctlr_vol_down` (struct `bt_vcp_vol_ctlr` *`vol_ctlr`)
Turn the volume down one step on a remote Volume Renderer.

**Parameters**
- `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

int `bt_vcp_vol_ctlr_vol_up` (struct `bt_vcp_vol_ctlr` *`vol_ctlr`)
Turn the volume up one step on a remote Volume Renderer.

**Parameters**
- `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

int `bt_vcp_vol_ctlr_unmute_vol_down` (struct `bt_vcp_vol_ctlr` *`vol_ctlr`)
Turn the volume down one step and unmute on a remote Volume Renderer.

**Parameters**
- `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

int `bt_vcp_vol_ctlr_unmute_vol_up` (struct `bt_vcp_vol_ctlr` *`vol_ctlr`)
Turn the volume up one step and unmute on a remote Volume Renderer.

**Parameters**
- `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

int `bt_vcp_vol_ctlr_set_vol` (struct `bt_vcp_vol_ctlr` *`vol_ctlr`, uint8_t `volume`)
Set the absolute volume on a remote Volume Renderer.

**Parameters**
- `vol_ctlr` – Volume Controller instance pointer.
  - `volume` – The absolute volume to set.

**Returns**
0 if success, errno on failure.
int bt_vcp_vol_ctlr_unmute(struct bt_vcp_vol_ctlr *vol_ctlr)
    Unmute a remote Volume Renderer.

    **Parameters**
    - `vol_ctlr` – Volume Controller instance pointer.

    **Returns**
    0 if success, errno on failure.

int bt_vcp_vol_ctlr_mute(struct bt_vcp_vol_ctlr *vol_ctlr)
    Mute a remote Volume Renderer.

    **Parameters**
    - `vol_ctlr` – Volume Controller instance pointer.

    **Returns**
    0 if success, errno on failure.

struct bt_vcp_vol_rend_register_param
#include <vcp.h> Register structure for Volume Control Service.

    **Public Members**

    `uint8_t step`
        Initial step size (1-255)

    `uint8_t mute`
        Initial mute state (0-1)

    `uint8_t volume`
        Initial volume level (0-255)

    `struct bt_vocs_register_param vocs_param[0]`
        Register parameters for Volume Offset Control Services.

    `struct bt_aics_register_param aics_param[0]`
        Register parameters for Audio Input Control Services.

    `struct bt_vcp_vol_rend_cb *cb`
        Volume Control Service callback structure.

struct bt_vcp_included
#include <vcp.h> Volume Control Service included services.

    **Public Members**

    `uint8_t vocs_cnt`
        Number of Volume Offset Control Service instances.
struct bt_vocs **vocs
    Array of pointers to Volume Offset Control Service instances.

uint8_t aics_cnt
    Number of Audio Input Control Service instances.

struct bt_aics **aics
    Array of pointers to Audio Input Control Service instances.

struct bt_vcp_vol_rend_cb
    #include <vcp.h>

Public Members

void (*state)(int err, uint8_t volume, uint8_t mute)
    Callback function for Volume Control Service volume state.
    Called when the value is locally read with bt_vcp_vol_rend_get_state(), or if the state
    is changed by either the Volume Renderer or a remote Volume Controller.
    
    Param err
        Error value. 0 on success, GATT error on positive value or errno on neg-
        ative value.

    Param volume
        The volume of the Volume Control Service server.

    Param mute
        The mute setting of the Volume Control Service server.

void (*flags)(int err, uint8_t flags)
    Callback function for Volume Control Service flags.
    Called when the value is locally read as the server. Called when the value is re-
    motely read as the client. Called if the value is changed by either the server or
    client.
    
    Param err
        Error value. 0 on success, GATT error on positive value or errno on neg-
        ative value.

    Param flags
        The flags of the Volume Control Service server.

struct bt_vcp_vol_ctlr_cb
    #include <vcp.h>

Public Members

void (*state)(struct bt_vcp_vol_ctlr *vol_ctlr, int err, uint8_t volume, uint8_t mute)
    Callback function for Volume Control Profile volume state.
    Called when the value is remotely read as the Volume Controller. Called if the value
    is changed by either the Volume Renderer or Volume Controller, and notified to the
    to Volume Controller.
    
    Param vol_ctlr
        Volume Controller instance pointer.
**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param volume**
The volume of the Volume Renderer.

**Param mute**
The mute setting of the Volume Renderer.

```c
void (*flags)(struct bt_vcp_vol_ctlr *vol_ctlr, int err, uint8_t flags)
```
Callback function for Volume Control Profile volume flags.
Called when the value is remotely read as the Volume Controller. Called if the value is changed by the Volume Renderer.
A non-zero value indicates the the volume has been changed on the Volume Renderer since it was booted.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param flags**
The flags of the Volume Renderer.

```c
void (*discover)(struct bt_vcp_vol_ctlr *vol_ctlr, int err, uint8_t vocs_count, uint8_t aics_count)
```
Callback function for `bt_vcp_vol_ctlr_discover()`.
This callback is called once the discovery procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param vocs_count**
Number of Volume Offset Control Service instances on the remote Volume Renderer.

**Param aics_count**
Number of Audio Input Control Service instances the remote Volume Renderer.

```c
void (*vol_down)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```
Callback function for `bt_vcp_vol_ctlr_vol_down()`.
Called when the volume down procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*vol_up)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```
Callback function for `bt_vcp_vol_ctlr_vol_up()`.
Called when the volume up procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.
**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*mute)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```
Callback function for `bt_vcp_vol_ctlr_mute()`.
Called when the mute procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*unmute)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```
Callback function for `bt_vcp_vol_ctlr_unmute()`.
Called when the unmute procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*vol_down_unmute)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```
Callback function for `bt_vcp_vol_ctlr_vol_down_unmute()`.
Called when the volume down and unmute procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*vol_up_unmute)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```
Callback function for `bt_vcp_vol_ctlr_vol_up_unmute()`.
Called when the volume up and unmute procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*vol_set)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```
Callback function for `bt_vcp_vol_ctlr_vol_set()`.
Called when the set absolute volume procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

### Universal Unique Identifiers (UUIDs)

**API Reference**
group bt_uuid

UUIDs.

Defines

BT_UUID_SIZE_16
Size in octets of a 16-bit UUID.

BT_UUID_SIZE_32
Size in octets of a 32-bit UUID.

BT_UUID_SIZE_128
Size in octets of a 128-bit UUID.

BT_UUID_INIT_16(value)
Initialize a 16-bit UUID.

Parameters
• value – 16-bit UUID value in host endianness.

BT_UUID_INIT_32(value)
Initialize a 32-bit UUID.

Parameters
• value – 32-bit UUID value in host endianness.

BT_UUID_INIT_128(value...)
Initialize a 128-bit UUID.

Parameters
• value – 128-bit UUID array values in little-endian format. Can be combined with BT_UUID_128_ENCODE to initialize a UUID from the readable form of UUIDs.

BT_UUID_DECLARE_16(value)
Helper to declare a 16-bit UUID inline.

Parameters
• value – 16-bit UUID value in host endianness.

Returns
Pointer to a generic UUID.

BT_UUID_DECLARE_32(value)
Helper to declare a 32-bit UUID inline.

Parameters
• value – 32-bit UUID value in host endianness.

Returns
Pointer to a generic UUID.

BT_UUID_DECLARE_128(value...)
Helper to declare a 128-bit UUID inline.

Parameters
• value – 128-bit UUID array values in little-endian format. Can be combined with BT_UUID_128_ENCODE to declare a UUID from the readable form of UUIDs.

Returns
Pointer to a generic UUID.

BT_UUID_16(__u)
Helper macro to access the 16-bit UUID from a generic UUID.

BT_UUID_32(__u)
Helper macro to access the 32-bit UUID from a generic UUID.

BT_UUID_128(__u)
Helper macro to access the 128-bit UUID from a generic UUID.

BT_UUID_128_ENCODE(w32, w1, w2, w3, w48)
Encode 128 bit UUID into array values in little-endian format.
Helper macro to initialize a 128-bit UUID array value from the readable form of UUIDs, or encode 128-bit UUID values into advertising data Can be combined with BT_UUID_DECLARE_128 to declare a 128-bit UUID.

Example of how to declare the UUID 6E400001-B5A3-F393-E0A9-E50E24DCCA9E

BT_UUID_DECLARE_128(BT_UUID_128_ENCODE(0x6E400001, 0xB5A3, 0xF393, 0xE0A9, 0xE50E24DCCA9E))

Example of how to encode the UUID 6E400001-B5A3-F393-E0A9-E50E24DCCA9E into advertising data.

BT_DATA_BYTES(BT_DATA_UUID128_ALL, BT_UUID_128_ENCODE(0x6E400001, 0xB5A3, 0xF393, 0xE0A9, 0xE50E24DCCA9E))

Just replace the hyphen by the comma and add 0x prefixes.

Parameters
• w32 – First part of the UUID (32 bits)
• w1 – Second part of the UUID (16 bits)
• w2 – Third part of the UUID (16 bits)
• w3 – Fourth part of the UUID (16 bits)
• w48 – Fifth part of the UUID (48 bits)

Returns
The comma separated values for UUID 128 initializer that may be used directly as an argument for BT_UUID_INIT_128 or BT_UUID_DECLARE_128

BT_UUID_16_ENCODE(w16)
Encode 16-bit UUID into array values in little-endian format.
Helper macro to encode 16-bit UUID values into advertising data.
Example of how to encode the UUID 0x180a into advertising data.

BT_DATA_BYTES(BT_DATA_UUID16_ALL, BT_UUID_16_ENCODE(0x180a))

Parameters
• w16 – UUID value (16-bits)
**Returns**
The comma separated values for UUID 16 value that may be used directly as an argument for *BT_DATA_BYTES*.

**BT_UUID_32_ENCODE**(*w32*)
Encode 32-bit UUID into array values in little-endian format.
Helper macro to encode 32-bit UUID values into advertising data.
Example of how to encode the UUID 0x180a01af into advertising data.
```
BT_DATA_BYTES(BT_DATA_UUID32_ALL, BT_UUID_32_ENCODE(0x180a01af))
```

**Parameters**
- *w32* – UUID value (32-bits)

**Returns**
The comma separated values for UUID 32 value that may be used directly as an argument for *BT_DATA_BYTES*.

**BT_UUID_STR_LEN**
Recommended length of user string buffer for Bluetooth UUID.
The recommended length guarantee the output of UUID conversion will not lose valuable information about the UUID being processed. If the length of the UUID is known the string can be shorter.

**BT_UUID_GAP_VAL**
Generic Access UUID value.

**BT_UUID_GAP**
Generic Access.

**BT_UUID_GATT_VAL**
Generic attribute UUID value.

**BT_UUID_GATT**
Generic Attribute.

**BT_UUID_IAS_VAL**
Immediate Alert Service UUID value.

**BT_UUID_IAS**
Immediate Alert Service.

**BT_UUID_LLS_VAL**
Link Loss Service UUID value.

**BT_UUID_LLS**
Link Loss Service.

**BT_UUID_TPS_VAL**
Tx Power Service UUID value.
**BT_UUID_TPS**
Tx Power Service.

**BT_UUID_CTS_VAL**
Current Time Service UUID value.

**BT_UUID_CTS**
Current Time Service.

**BT_UUID_RTUS_VAL**
Reference Time Update Service UUID value.

**BT_UUID_RTUS**
Reference Time Update Service.

**BT_UUID_NDSTS_VAL**
Next DST Change Service UUID value.

**BT_UUID_NDSTS**
Next DST Change Service.

**BT_UUID_GS_VAL**
Glucose Service UUID value.

**BT_UUID_GS**
Glucose Service.

**BT_UUID_HTS_VAL**
Health Thermometer Service UUID value.

**BT_UUID_HTS**
Health Thermometer Service.

**BT_UUID_DIS_VAL**
Device Information Service UUID value.

**BT_UUID_DIS**
Device Information Service.

**BT_UUID_NAS_VAL**
Network Availability Service UUID value.

**BT_UUID_NAS**
Network Availability Service.

**BT_UUID_WDS_VAL**
Watchdog Service UUID value.
BT_UUID_WDS
   Watchdog Service.

BT_UUID_HRS_VAL
   Heart Rate Service UUID value.

BT_UUID_HRS
   Heart Rate Service.

BT_UUID_PAS_VAL
   Phone Alert Service UUID value.

BT_UUID_PAS
   Phone Alert Service.

BT_UUID_BAS_VAL
   Battery Service UUID value.

BT_UUID_BAS
   Battery Service.

BT_UUID_BPS_VAL
   Blood Pressure Service UUID value.

BT_UUID_BPS
   Blood Pressure Service.

BT_UUID_ANS_VAL
   Alert Notification Service UUID value.

BT_UUID_ANS
   Alert Notification Service.

BT_UUID_HIDS_VAL
   HID Service UUID value.

BT_UUID_HIDS
   HID Service.

BT_UUID_SPS_VAL
   Scan Parameters Service UUID value.

BT_UUID_SPS
   Scan Parameters Service.

BT_UUID_RSCS_VAL
   Running Speed and Cadence Service UUID value.

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BT_UUID_RSCS
   Running Speed and Cadence Service.

BT_UUID_AIOS_VAL
   Automation IO Service UUID value.

BT_UUID_AIOS
   Automation IO Service.

BT_UUID_CSC_VAL
   Cycling Speed and Cadence Service UUID value.

BT_UUID_CSC
   Cycling Speed and Cadence Service.

BT_UUID_CPS_VAL
   Cycling Power Service UUID value.

BT_UUID_CPS
   Cycling Power Service.

BT_UUID_LNS_VAL
   Location and Navigation Service UUID value.

BT_UUID_LNS
   Location and Navigation Service.

BT_UUID_ESS_VAL
   Environmental Sensing Service UUID value.

BT_UUID_ESS
   Environmental Sensing Service.

BT_UUID_BCS_VAL
   Body Composition Service UUID value.

BT_UUID_BCS
   Body Composition Service.

BT_UUID_UDS_VAL
   User Data Service UUID value.

BT_UUID_UDS
   User Data Service.

BT_UUID_WSS_VAL
   Weight Scale Service UUID value.
BT_UUID_WSS
   Weight Scale Service.

BT_UUID_BMS_VAL
   Bond Management Service UUID value.

BT_UUID_BMS
   Bond Management Service.

BT_UUID_CGMS_VAL
   Continuous Glucose Monitoring Service UUID value.

BT_UUID_CGMS
   Continuous Glucose Monitoring Service.

BT_UUID_IPSS_VAL
   IP Support Service UUID value.

BT_UUID_IPSS
   IP Support Service.

BT_UUID_IPS_VAL
   Indoor Positioning Service UUID value.

BT_UUID_IPS
   Indoor Positioning Service.

BT_UUID_POS_VAL
   Pulse Oximeter Service UUID value.

BT_UUID_POS
   Pulse Oximeter Service.

BT_UUID_HPS_VAL
   HTTP Proxy Service UUID value.

BT_UUID_HPS
   HTTP Proxy Service.

BT_UUID_TDS_VAL
   Transport Discovery Service UUID value.

BT_UUID_TDS
   Transport Discovery Service.

BT_UUID_OTS_VAL
   Object Transfer Service UUID value.
BT_UUID_OTS
Object Transfer Service.

BT_UUID_FMS_VAL
Fitness Machine Service UUID value.

BT_UUID_FMS
Fitness Machine Service.

BT_UUID_MESH_PROV_VAL
Mesh Provisioning Service UUID value.

BT_UUID_MESH_PROV
Mesh Provisioning Service.

BT_UUID_MESH_PROXY_VAL
Mesh Proxy Service UUID value.

BT_UUID_MESH_PROXY
Mesh Proxy Service.

BT_UUID_MESH_PROXY_SOLICITATION_VAL
Proxy Solicitation UUID value.

BT_UUID_RCSRV_VAL
Reconnection Configuration Service UUID value.

BT_UUID_RCSRV
Reconnection Configuration Service.

BT_UUID_IDS_VAL
Insulin Delivery Service UUID value.

BT_UUID_IDS
Insulin Delivery Service.

BT_UUID_BSS_VAL
Binary Sensor Service UUID value.

BT_UUID_BSS
Binary Sensor Service.

BT_UUID_ECS_VAL
Emergency Configuration Service UUID value.

BT_UUID_ECS
Emergency Configuration Service.
BT_UUID_ACLS_VAL
Authorization Control Service UUID value.

BT_UUID_ACLS
Authorization Control Service.

BT_UUID_PAMS_VAL
Physical Activity Monitor Service UUID value.

BT_UUID_PAMS
Physical Activity Monitor Service.

BT_UUID_AICS_VAL
Audio Input Control Service UUID value.

BT_UUID_AICS
Audio Input Control Service.

BT_UUID_VCS_VAL
Volume Control Service UUID value.

BT_UUID_VCS
Volume Control Service.

BT_UUID_VOCS_VAL
Volume Offset Control Service UUID value.

BT_UUID_VOCS
Volume Offset Control Service.

BT_UUID_CSIS_VAL
Coordinated Set Identification Service UUID value.

BT_UUID_CSIS
Coordinated Set Identification Service.

BT_UUID_DTS_VAL
Device Time Service UUID value.

BT_UUID_DTS
Device Time Service.

BT_UUID_MCS_VAL
Media Control Service UUID value.

BT_UUID_MCS
Media Control Service.
BT_UUID_GMCS_VAL
Generic Media Control Service UUID value.

BT_UUID_GMCS
Generic Media Control Service.

BT_UUID_CTES_VAL
Constant Tone Extension Service UUID value.

BT_UUID_CTES
Constant Tone Extension Service.

BT_UUID_TBS_VAL
Telephone Bearer Service UUID value.

BT_UUID_TBS
Telephone Bearer Service.

BT_UUID_GTBS_VAL
Generic Telephone Bearer Service UUID value.

BT_UUID_GTBS
Generic Telephone Bearer Service.

BT_UUID_MICS_VAL
Microphone Control Service UUID value.

BT_UUID_MICS
Microphone Control Service.

BT_UUID_ASCS_VAL
Audio Stream Control Service UUID value.

BT_UUID_ASCS
Audio Stream Control Service.

BT_UUID_BASS_VAL
Broadcast Audio Scan Service UUID value.

BT_UUID_BASS
Broadcast Audio Scan Service.

BT_UUID_PACS_VAL
Published Audio Capabilities Service UUID value.

BT_UUID_PACS
Published Audio Capabilities Service.
BT_UUID_BASIC_AUDIO_VAL
Basic Audio Announcement Service UUID value.

BT_UUID_BASIC_AUDIO
Basic Audio Announcement Service.

BT_UUID_BROADCAST_AUDIO_VAL
Broadcast Audio Announcement Service UUID value.

BT_UUID_BROADCAST_AUDIO
Broadcast Audio Announcement Service.

BT_UUID_CAS_VAL
Common Audio Service UUID value.

BT_UUID_CAS
Common Audio Service.

BT_UUID_HAS_VAL
Hearing Access Service UUID value.

BT_UUID_HAS
Hearing Access Service.

BT_UUID_TMAS_VAL
Telephony and Media Audio Service UUID value.

BT_UUID_TMAS
Telephony and Media Audio Service.

BT_UUID_PBA_VAL
Public Broadcast Announcement Service UUID value.

BT_UUID_PBA
Public Broadcast Announcement Service.

BT_UUID_GATT_PRIMARY_VAL
GATT Primary Service UUID value.

BT_UUID_GATT_PRIMARY
GATT Primary Service.

BT_UUID_GATT_SECONDARY_VAL
GATT Secondary Service UUID value.

BT_UUID_GATT_SECONDARY
GATT Secondary Service.
BT_UUID_GATT_INCLUDE_VAL
GATT Include Service UUID value.

BT_UUID_GATT_INCLUDE
GATT Include Service.

BT_UUID_GATT_CHRC_VAL
GATT Characteristic UUID value.

BT_UUID_GATT_CHRC
GATT Characteristic.

BT_UUID_GATT_CEP_VAL
GATT Characteristic Extended Properties UUID value.

BT_UUID_GATT_CEP
GATT Characteristic Extended Properties.

BT_UUID_GATT_CUD_VAL
GATT Characteristic User Description UUID value.

BT_UUID_GATT_CUD
GATT Characteristic User Description.

BT_UUID_GATT_CCC_VAL
GATT Client Characteristic Configuration UUID value.

BT_UUID_GATT_CCC
GATT Client Characteristic Configuration.

BT_UUID_GATT_SCC_VAL
GATT Server Characteristic Configuration UUID value.

BT_UUID_GATT_SCC
GATT Server Characteristic Configuration.

BT_UUID_GATTCPF_VAL
GATT Characteristic Presentation Format UUID value.

BT_UUID_GATTCPF
GATT Characteristic Presentation Format.

BT_UUID_GATT_CAF_VAL
GATT Characteristic Aggregated Format UUID value.

BT_UUID_GATT_CAF
GATT Characteristic Aggregated Format.
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**BT_UUID_VALID_RANGE_VAL**
Valid Range Descriptor UUID value.

**BT_UUID_VALID_RANGE**
Valid Range Descriptor.

**BT_UUID_HIDS_EXT_REPORT_VAL**
HID External Report Descriptor UUID value.

**BT_UUID_HIDS_EXT_REPORT**
HID External Report Descriptor.

**BT_UUID_HIDS_REPORT_REF_VAL**
HID Report Reference Descriptor UUID value.

**BT_UUID_HIDS_REPORT_REF**
HID Report Reference Descriptor.

**BT_UUID_VAL_TRIGGER_SETTING_VAL**
Value Trigger Setting Descriptor UUID value.

**BT_UUID_VAL_TRIGGER_SETTING**
Value Trigger Setting Descriptor.

**BT_UUID_ES_CONFIGURATION_VAL**
Environmental Sensing Configuration Descriptor UUID value.

**BT_UUID_ES_CONFIGURATION**
Environmental Sensing Configuration Descriptor.

**BT_UUID_ES_MEASUREMENT_VAL**
Environmental Sensing Measurement Descriptor UUID value.

**BT_UUID_ES_MEASUREMENT**
Environmental Sensing Measurement Descriptor.

**BT_UUID_ES_TRIGGER_SETTING_VAL**
Environmental Sensing Trigger Setting Descriptor UUID value.

**BT_UUID_ES_TRIGGER_SETTING**
Environmental Sensing Trigger Setting Descriptor.

**BT_UUID_TM_TRIGGER_SETTING_VAL**
Time Trigger Setting Descriptor UUID value.

**BT_UUID_TM_TRIGGER_SETTING**
Time Trigger Setting Descriptor.
BT_UUID_GAP_DEVICE_NAME_VAL
  GAP Characteristic Device Name UUID value.

BT_UUID_GAP_DEVICE_NAME
  GAP Characteristic Device Name.

BT_UUID_GAP_APPEARANCE_VAL
  GAP Characteristic Appearance UUID value.

BT_UUID_GAP_APPEARANCE
  GAP Characteristic Appearance.

BT_UUID_GAP_PPF_VAL
  GAP Characteristic Peripheal Privacy Flag UUID value.

BT_UUID_GAP_PPF
  GAP Characteristic Peripheal Privacy Flag.

BT_UUID_GAP_RA_VAL
  GAP Characteristic Reconnection Address UUID value.

BT_UUID_GAP_RA
  GAP Characteristic Reconnection Address.

BT_UUID_GAP_PPCP_VAL
  GAP Characteristic Peripheral Preferred Connection Parameters UUID value.

BT_UUID_GAP_PPCP
  GAP Characteristic Peripheral Preferred Connection Parameters.

BT_UUID_GATT_SC_VAL
  GATT Characteristic Service Changed UUID value.

BT_UUID_GATT_SC
  GATT Characteristic Service Changed.

BT_UUID_ALERT_LEVEL_VAL
  GATT Characteristic Alert Level UUID value.

BT_UUID_ALERT_LEVEL
  GATT Characteristic Alert Level.

BT_UUID_TPS_TX_POWER_LEVEL_VAL
  TPS Characteristic Tx Power Level UUID value.

BT_UUID_TPS_TX_POWER_LEVEL
  TPS Characteristic Tx Power Level.
**BT_UUID_GATT_DT_VAL**  
GATT Characteristic Date Time UUID value.

**BT_UUID_GATT_DT**  
GATT Characteristic Date Time.

**BT_UUID_GATT_DW_VAL**  
GATT Characteristic Day of Week UUID value.

**BT_UUID_GATT_DW**  
GATT Characteristic Day of Week.

**BT_UUID_GATT_DDT_VAL**  
GATT Characteristic Day Date Time UUID value.

**BT_UUID_GATT_DDT**  
GATT Characteristic Day Date Time.

**BT_UUID_GATT_ET256_VAL**  
GATT Characteristic Exact Time 256 UUID value.

**BT_UUID_GATT_ET256**  
GATT Characteristic Exact Time 256.

**BT_UUID_GATT_DST_VAL**  
GATT Characteristic DST Offset UUID value.

**BT_UUID_GATT_DST**  
GATT Characteristic DST Offset.

**BT_UUID_GATT_TZ_VAL**  
GATT Characteristic Time Zone UUID value.

**BT_UUID_GATT_TZ**  
GATT Characteristic Time Zone.

**BT_UUID_GATT_LTI_VAL**  
GATT Characteristic Local Time Information UUID value.

**BT_UUID_GATT_LTI**  
GATT Characteristic Local Time Information.

**BT_UUID_GATT_TDST_VAL**  
GATT Characteristic Time with DST UUID value.

**BT_UUID_GATT_TDST**  
GATT Characteristic Time with DST.
BT_UUID_GATT_TA_VAL
GATT Characteristic Time Accuracy UUID value.

BT_UUID_GATT_TA
GATT Characteristic Time Accuracy.

BT_UUID_GATT_TS_VAL
GATT Characteristic Time Source UUID value.

BT_UUID_GATT_TS
GATT Characteristic Time Source.

BT_UUID_GATT_RTI_VAL
GATT Characteristic Reference Time Information UUID value.

BT_UUID_GATT_RTI
GATT Characteristic Reference Time Information.

BT_UUID_GATT_TUCP_VAL
GATT Characteristic Time Update Control Point UUID value.

BT_UUID_GATT_TUCP
GATT Characteristic Time Update Control Point.

BT_UUID_GATT_TUS_VAL
GATT Characteristic Time Update State UUID value.

BT_UUID_GATT_TUS
GATT Characteristic Time Update State.

BT_UUID_GATT_GM_VAL
GATT Characteristic Glucose Measurement UUID value.

BT_UUID_GATT_GM
GATT Characteristic Glucose Measurement.

BT_UUID_BAS_BATTERY_LEVEL_VAL
BAS Characteristic Battery Level UUID value.

BT_UUID_BAS_BATTERY_LEVEL
BAS Characteristic Battery Level.

BT_UUID_BAS_BATTERY_POWER_STATE_VAL
BAS Characteristic Battery Power State UUID value.

BT_UUID_BAS_BATTERY_POWER_STATE
BAS Characteristic Battery Power State.
BT_UUID_BAS_BATTERY_LEVEL_STATE_VAL
  BAS Characteristic Battery Level State UUID value.

BT_UUID_BAS_BATTERY_LEVEL_STATE
  BAS Characteristic Battery Level State.

BT_UUID_HTS_MEASUREMENT_VAL
  HTS Characteristic Temperature Measurement UUID value.

BT_UUID_HTS_MEASUREMENT
  HTS Characteristic Temperature Measurement Value.

BT_UUID_HTS_TEMP_TYP_VAL
  HTS Characteristic Temperature Type UUID value.

BT_UUID_HTS_TEMP_TYP
  HTS Characteristic Temperature Type.

BT_UUID_HTS_TEMP_INT_VAL
  HTS Characteristic Intermediate Temperature UUID value.

BT_UUID_HTS_TEMP_INT
  HTS Characteristic Intermediate Temperature.

BT_UUID_HTS_TEMP_C_VAL
  HTS Characteristic Temperature Celsius UUID value.

BT_UUID_HTS_TEMP_C
  HTS Characteristic Temperature Celsius.

BT_UUID_HTS_TEMP_F_VAL
  HTS Characteristic Temperature Fahrenheit UUID value.

BT_UUID_HTS_TEMP_F
  HTS Characteristic Temperature Fahrenheit.

BT_UUID_HIDS_BOOT_KB_IN_REPORT_VAL
  HID Characteristic Boot Keyboard Input Report UUID value.

BT_UUID_HIDS_BOOT_KB_IN_REPORT
  HID Characteristic Boot Keyboard Input Report.
BT_UUID_DIS_SYSTEM_ID
DIS Characteristic System ID UUID value.

BT_UUID_DIS_SYSTEM_ID
DIS Characteristic System ID.

BT_UUID_DIS_MODEL_NUMBER
DIS Characteristic Model Number String UUID value.

BT_UUID_DIS_MODEL_NUMBER
DIS Characteristic Model Number String.

BT_UUID_DIS_SERIAL_NUMBER
DIS Characteristic Serial Number String UUID value.

BT_UUID_DIS_SERIAL_NUMBER
DIS Characteristic Serial Number String.

BT_UUID_DIS_FIRMWARE_REVISION
DIS Characteristic Firmware Revision String UUID value.

BT_UUID_DIS_FIRMWARE_REVISION
DIS Characteristic Firmware Revision String.

BT_UUID_DIS_HARDWARE_REVISION
DIS Characteristic Hardware Revision String UUID value.

BT_UUID_DIS_HARDWARE_REVISION
DIS Characteristic Hardware Revision String.

BT_UUID_DIS_SOFTWARE_REVISION
DIS Characteristic Software Revision String UUID value.

BT_UUID_DIS_SOFTWARE_REVISION
DIS Characteristic Software Revision String.

BT_UUID_DIS_MANUFACTURER_NAME
DIS Characteristic Manufacturer Name String UUID Value.

BT_UUID_DIS_MANUFACTURER_NAME
DIS Characteristic Manufacturer Name String.

BT_UUID_GATT_IEEE_RCDL
GATT Characteristic IEEE Regulatory Certification Data List UUID Value.

BT_UUID_GATT_IEEE_RCDL
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BT_UUID_HIDS_BOOT_MOUSE_IN_REPORT
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BT_UUID_GATT_GMC_VAL
GATT Characteristic Glucose Measurement Context UUID Value.

BT_UUID_GATT_GMC
GATT Characteristic Glucose Measurement Context.

BT_UUID_GATT_BPM_VAL
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BT_UUID_GATT_BPM
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BT_UUID_GATT_ICP_VAL
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BT_UUID_GATT_ICP
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BT_UUID_HRS_MEASUREMENT_VAL
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BT_UUID_HRS_BODYSENSOR_VAL
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BT_UUID_HRS_CONTROL_POINT_VAL
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BT_UUID_HRS_CONTROL_POINT
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BT_UUID_GATT_REM_VAL
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BT_UUID_GATT_REM
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BT_UUID_GATT_SRVREQ_VAL
GATT Characteristic Service Required UUID Value.

BT_UUID_GATT_SRVREQ
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BT_UUID_GATT_SC_TEMP_C_VAL
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BT_UUID_GATT_STRING_VAL
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BT_UUID_GATT_NETA_VAL
GATT Characteristic Network Availability UUID Value.

BT_UUID_GATT_NETA
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BT_UUID_GATT_ALRTS_VAL
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BT_UUID_GATT_RCP_VAL
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BT_UUID_GATT_RCP
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BT_UUID_GATT_RS_VAL
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BT_UUID_GATT_RS
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BT_UUID_GATT_ALRTCID_MASK_VAL
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BT_UUID_GATT_ALRTCID_MASK
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BT_UUID_GATT_ALRTCID_VAL
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BT_UUID_GATT_ALRTNCP_VAL
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BT_UUID_GATT_ALRTNCP
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BT_UUID_GATT_UALRTS_VAL
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BT_UUID_GATT_NALRT_VAL
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BT_UUID_GATT_NALRT
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BT_UUID_GATT_SNALRTC_VAL
   GATT Characteristic Supported New Alert Category UUID Value.

BT_UUID_GATT_SNALRTC
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BT_UUID_GATT_SUALRTC_VAL
   GATT Characteristic Supported Unread Alert Category UUID Value.

BT_UUID_GATT_SUALRTC
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BT_UUID_GATT_BPF_VAL
   GATT Characteristic Blood Pressure Feature UUID Value.

BT_UUID_GATT_BPF
   GATT Characteristic Blood Pressure Feature.

BT_UUID_HIDS_INFO_VAL
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BT_UUID_HIDS_INFO
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**BT_UUID_HIDS_REPORT_MAP_VAL**
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**BT_UUID_HIDS_REPORT_MAP**
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**BT_UUID_HIDS_CTRL_POINT_VAL**
HID Control Point Characteristic UUID value.

**BT_UUID_HIDS_CTRL_POINT**
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**BT_UUID_HIDS_REPORT_VAL**
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**BT_UUID_HIDS_PROTOCOL_MODE_VAL**
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**BT_UUID_HIDS_PROTOCOL_MODE**
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**BT_UUID_GATT_SIW_VAL**
GATT Characteristic Scan Interval Windows UUID Value.

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**BT_UUID_DIS_PNP_ID_VAL**
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**BT_UUID_GATT_GF_VAL**
GATT Characteristic Glucose Feature UUID Value.

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**BT_UUID_RECORD_ACCESS_CONTROL_POINT_VAL**
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BT_UUID_RSC_MEASUREMENT
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BT_UUID_RSC_FEATURE_VAL
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BT_UUID_SC_CONTROL_POINT_VAL
    SC Control Point Characteristic UUID value.

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BT_UUID_GATT_DI_VAL
    GATT Characteristic Digital Input UUID Value.

BT_UUID_GATT_DI
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BT_UUID_GATT_DO
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BT_UUID_GATT_AI
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BT_UUID_GATT_AO_VAL
    GATT Characteristic Analog Output UUID Value.

BT_UUID_GATT_AO
    GATT Characteristic Analog Output.

BT_UUID_GATT_AGGR_VAL
    GATT Characteristic Aggregate UUID Value.

BT_UUID_GATT_AGGR
    GATT Characteristic Aggregate.
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- **BT_UUID_CSC_MEASUREMENT_VAL**
  CSC Measurement Characteristic UUID value.

- **BT_UUID_CSC_MEASUREMENT**
  CSC Measurement Characteristic.

- **BT_UUID_CSC_FEATURE_VAL**
  CSC Feature Characteristic UUID value.

- **BT_UUID_CSC_FEATURE**
  CSC Feature Characteristic.

- **BT_UUID_SENSOR_LOCATION_VAL**
  Sensor Location Characteristic UUID value.

- **BT_UUID_SENSOR_LOCATION**
  Sensor Location Characteristic.

- **BT_UUID_GATT_PLX_SCM_VAL**
  GATT Characteristic PLX Spot-Check Measurement UUID Value.

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- **BT_UUID_GATT_PLX_CM_VAL**
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- **BT_UUID_GATT_PLX_F**
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- **BT_UUID_GATT_POPE_VAL**
  GATT Characteristic Pulse Oximetry Pulastile Event UUID Value.

- **BT_UUID_GATT_POPE**
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BT_UUID_GATT_CPS_CPM_VAL
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BT_UUID_GATT_CPS_CPV
  GATT Characteristic Cycling Power Vector.

BT_UUID_GATT_CPS_CPV_VAL
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BT_UUID_GATT_CPS_CPF_VAL
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BT_UUID_GATT_CPS_CPCP
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BT_UUID_GATT_CPS_CPCP_VAL
  GATT Characteristic Cycling Power Control Point UUID Value.

BT_UUID_GATT_LOC_SPD
  GATT Characteristic Location and Speed.

BT_UUID_GATT_LOC_SPD_VAL
  GATT Characteristic Location and Speed UUID Value.

BT_UUID_GATT_NAV
  GATT Characteristic Navigation.

BT_UUID_GATT_NAV_VAL
  GATT Characteristic Navigation UUID Value.

BT_UUID_GATT_PQ
  GATT Characteristic Position Quality.

BT_UUID_GATT_PQ_VAL
  GATT Characteristic Position Quality UUID Value.

BT_UUID_GATT_LNF
  GATT Characteristic LN Feature.

BT_UUID_GATT_LNF_VAL
  GATT Characteristic LN Feature UUID Value.
BT_UUID_GATT_LNCP_VAL
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BT_UUID_ELEVATION
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BT_UUID_PRESSURE_VAL
   Pressure Characteristic UUID value.

BT_UUID_PRESSURE
   Pressure Characteristic.

BT_UUID_TEMPERATURE_VAL
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BT_UUID_TEMPERATURE
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BT_UUID_HUMIDITY_VAL
   Humidity Characteristic UUID value.

BT_UUID_HUMIDITY
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BT_UUID_TRUE_WIND_SPEED_VAL
   True Wind Speed Characteristic UUID value.

BT_UUID_TRUE_WIND_SPEED
   True Wind Speed Characteristic.

BT_UUID_TRUE_WIND_DIR_VAL
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BT_UUID_APPARENT_WIND_SPEED_VAL
   Apparent Wind Speed Characteristic UUID value.

BT_UUID_APPARENT_WIND_SPEED
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BT_UUID_APPARENT_WIND_DIR_VAL
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BT_UUID_APPARENT_WIND_DIR
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BT_UUID_GUST_FACTOR_VAL
Gust Factor Characteristic UUID value.

BT_UUID_GUST_FACTOR
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BT_UUID_POLLEN_CONCENTRATION_VAL
Pollen Concentration Characteristic UUID value.

BT_UUID_POLLEN_CONCENTRATION
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BT_UUID_UV_INDEX_VAL
UV Index Characteristic UUID value.

BT_UUID_UV_INDEX
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BT_UUID_IRRADIANCE_VAL
Irradiance Characteristic UUID value.

BT_UUID_IRRADIANCE
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BT_UUID_RAINFALL_VAL
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BT_UUID_RAINFALL
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BT_UUID_WIND_CHILL_VAL
Wind Chill Characteristic UUID value.

BT_UUID_WIND_CHILL
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BT_UUID_HEAT_INDEX_VAL
Heat Index Characteristic UUID value.

BT_UUID_HEAT_INDEX
Heat Index Characteristic.
BT_UUID_DEW_POINT_VAL
Dew Point Characteristic UUID value.

BT_UUID_DEW_POINT
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BT_UUID_GATT_TREND_VAL
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BT_UUID_GATT_TREND
GATT Characteristic Trend.

BT_UUID_DESC_VALUE_CHANGED_VAL
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BT_UUID_DESC_VALUE_CHANGED
Descriptor Value Changed Characteristic.

BT_UUID_GATT_AEHRLL_VAL
GATT Characteristic Aerobic Heart Rate Low Limit UUID Value.

BT_UUID_GATT_AEHRLL
GATT Characteristic Aerobic Heart Rate Lower Limit.

BT_UUID_GATT_AETHR_VAL
GATT Characteristic Aerobic Threshold UUID Value.

BT_UUID_GATT_AETHR
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BT_UUID_GATT_AGE_VAL
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BT_UUID_GATT_ANHRLL_VAL
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BT_UUID_GATT_ANHRLL
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BT_UUID_GATT_ANHRUL_VAL
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BT_UUID_GATT_ANHRUL
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BT_UUID_GATT_ANTHR_VAL
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BT_UUID_GATT_AEHRUL_VAL
GATT Characteristic Aerobic Heart Rate Upper Limit UUID Value.

BT_UUID_GATT_AEHRUL
GATT Characteristic Aerobic Heart Rate Upper Limit.

BT_UUID_GATT_DATE_BIRTH_VAL
GATT Characteristic Date of Birth UUID Value.

BT_UUID_GATT_DATE_BIRTH
GATT Characteristic Date of Birth.

BT_UUID_GATT_DATE_THRASS_VAL
GATT Characteristic Date of Threshold Assessment UUID Value.

BT_UUID_GATT_DATE_THRASS
GATT Characteristic Date of Threshold Assessment.

BT_UUID_GATT_EMAIL_VAL
GATT Characteristic Email Address UUID Value.

BT_UUID_GATT_EMAIL
GATT Characteristic Email Address.

BT_UUID_GATT_FBHRLL_VAL
GATT Characteristic Fat Burn Heart Rate Lower Limit UUID Value.

BT_UUID_GATT_FBHRLL
GATT Characteristic Fat Burn Heart Rate Lower Limit.

BT_UUID_GATT_FBHRUL_VAL
GATT Characteristic Fat Burn Heart Rate Upper Limit UUID Value.

BT_UUID_GATT_FBHRUL
GATT Characteristic Fat Burn Heart Rate Upper Limit.

BT_UUID_GATT_FIRST_NAME_VAL
GATT Characteristic First Name UUID Value.

BT_UUID_GATT_FIRST_NAME
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BT_UUID_GATT_5ZHRL_VAL
GATT Characteristic Five Zone Heart Rate Limits UUID Value.

BT_UUID_GATT_5ZHRL
GATT Characteristic Five Zone Heart Rate Limits.

BT_UUID_GATT_GENDER_VAL
GATT Characteristic Gender UUID Value.

BT_UUID_GATT_GENDER
GATT Characteristic Gender.

BT_UUID_GATT_HR_MAX_VAL
GATT Characteristic Heart Rate Max UUID Value.

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GATT Characteristic Heart Rate Max.

BT_UUID_GATT_HEIGHT_VAL
GATT Characteristic Height UUID Value.

BT_UUID_GATT_HEIGHT
GATT Characteristic Height.

BT_UUID_GATT_HC_VAL
GATT Characteristic Hip Circumference UUID Value.

BT_UUID_GATT_HC
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BT_UUID_GATT_LAST_NAME_VAL
GATT Characteristic Last Name UUID Value.

BT_UUID_GATT_LAST_NAME
GATT Characteristic Last Name.

BT_UUID_GATT_MRHR_VAL
GATT Characteristic Maximum Recommended Heart Rate> UUID Value.

BT_UUID_GATT_MRHR
GATT Characteristic Maximum Recommended Heart Rate.

BT_UUID_GATT_RHR_VAL
GATT Characteristic Resting Heart Rate UUID Value.

BT_UUID_GATT_RHR
GATT Characteristic Resting Heart Rate.
BT_UUID_GATT_AEANTHR_VAL
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BT_UUID_GATT_AEANTHR
GATT Characteristic Sport Type for Aerobic and Anaerobic Threshold.

BT_UUID_GATT_3ZHRL_VAL
GATT Characteristic Three Zone Heart Rate Limits UUID Value.

BT_UUID_GATT_3ZHRL
GATT Characteristic Three Zone Heart Rate Limits.

BT_UUID_GATT_2ZHRL_VAL
GATT Characteristic Two Zone Heart Rate Limits UUID Value.

BT_UUID_GATT_2ZHRL
GATT Characteristic Two Zone Heart Rate Limits.

BT_UUID_GATT_VO2_MAX_VAL
GATT Characteristic VO2 Max UUID Value.

BT_UUID_GATT_VO2_MAX
GATT Characteristic VO2 Max.

BT_UUID_GATT_WC_VAL
GATT Characteristic Waist Circumference UUID Value.

BT_UUID_GATT_WC
GATT Characteristic Waist Circumference.

BT_UUID_GATT_WEIGHT_VAL
GATT Characteristic Weight UUID Value.

BT_UUID_GATT_WEIGHT
GATT Characteristic Weight.

BT_UUID_GATT_DBCHINC_VAL
GATT Characteristic Database Change Increment UUID Value.

BT_UUID_GATT_DBCHINC
GATT Characteristic Database Change Increment.

BT_UUID_GATT_USRIDX_VAL
GATT Characteristic User Index UUID Value.

BT_UUID_GATT_USRIDX
GATT Characteristic User Index.
BT_UUID_GATT_BCF_VAL
GATT Characteristic Body Composition Feature UUID Value.

BT_UUID_GATT_BCF
GATT Characteristic Body Composition Feature.

BT_UUID_GATT_BCM_VAL
GATT Characteristic Body Composition Measurement UUID Value.

BT_UUID_GATT_BCM
GATT Characteristic Body Composition Measurement.

BT_UUID_GATT_WM_VAL
GATT Characteristic Weight Measurement UUID Value.

BT_UUID_GATT_WM
GATT Characteristic Weight Measurement.

BT_UUID_GATT_WSF_VAL
GATT Characteristic Weight Scale Feature UUID Value.

BT_UUID_GATT_WSF
GATT Characteristic Weight Scale Feature.

BT_UUID_GATT_USRCP_VAL
GATT Characteristic User Control Point UUID Value.

BT_UUID_GATT_USRCP
GATT Characteristic User Control Point.

BT_UUID_MAGN_FLUX_DENSITY_2D_VAL
Magnetic Flux Density - 2D Characteristic UUID value.

BT_UUID_MAGN_FLUX_DENSITY_2D
Magnetic Flux Density - 2D Characteristic.

BT_UUID_MAGN_FLUX_DENSITY_3D_VAL
Magnetic Flux Density - 3D Characteristic UUID value.

BT_UUID_MAGN_FLUX_DENSITY_3D
Magnetic Flux Density - 3D Characteristic.

BT_UUID_GATT_LANG_VAL
GATT Characteristic Language UUID Value.

BT_UUID_GATT_LANG
GATT Characteristic Language.
BT_UUID_BAR_PRESSURE_TREND_VAL
Barometric Pressure Trend Characteristic UUID value.

BT_UUID_BAR_PRESSURE_TREND
Barometric Pressure Trend Characteristic.

BT_UUID_BMS_CONTROL_POINT_VAL
Bond Management Control Point UUID value.

BT_UUID_BMS_CONTROL_POINT
Bond Management Control Point.

BT_UUID_BMS_FEATURE_VAL
Bond Management Feature UUID value.

BT_UUID_BMS_FEATURE
Bond Management Feature.

BT_UUID_CENTRAL_ADDR_RES_VAL
Central Address Resolution Characteristic UUID value.

BT_UUID_CENTRAL_ADDR_RES
Central Address Resolution Characteristic.

BT_UUID_CGM_MEASUREMENT_VAL
CGM Measurement Characteristic value.

BT_UUID_CGM_MEASUREMENT
CGM Measurement Characteristic.

BT_UUID_CGM_FEATURE_VAL
CGM Feature Characteristic value.

BT_UUID_CGM_FEATURE
CGM Feature Characteristic.

BT_UUID_CGM_STATUS_VAL
CGM Status Characteristic value.

BT_UUID_CGM_STATUS
CGM Status Characteristic.

BT_UUID_CGM_SESSION_START_TIME_VAL
CGM Session Start Time Characteristic value.

BT_UUID_CGM_SESSION_START_TIME
CGM Session Start Time.
BT_UUID_CGM_SESSION_RUN_TIME_VAL
CGM Session Run Time Characteristic value.

BT_UUID_CGM_SESSION_RUN_TIME
CGM Session Run Time.

BT_UUID_CGM_SPECIFIC_OPS_CONTROL_POINT_VAL
CGM Specific Ops Control Point Characteristic value.

BT_UUID_CGM_SPECIFIC_OPS_CONTROL_POINT
CGM Specific Ops Control Point.

BT_UUID_GATT_IPC_VAL
GATT Characteristic Indoor Positioning Configuration UUID Value.

BT_UUID_GATT_IPC
GATT Characteristic Indoor Positioning Configuration.

BT_UUID_GATT_LAT_VAL
GATT Characteristic Latitude UUID Value.

BT_UUID_GATT_LAT
GATT Characteristic Latitude.

BT_UUID_GATT_LON_VAL
GATT Characteristic Longitude UUID Value.

BT_UUID_GATT_LON
GATT Characteristic Longitude.

BT_UUID_GATT_LNCOORD_VAL
GATT Characteristic Local North Coordinate UUID Value.

BT_UUID_GATT_LNCOORD
GATT Characteristic Local North Coordinate.

BT_UUID_GATT_LECOORD_VAL
GATT Characteristic Local East Coordinate UUID Value.

BT_UUID_GATT_LECOORD
GATT Characteristic Local East Coordinate.

BT_UUID_GATT_FN_VAL
GATT Characteristic Floor Number UUID Value.

BT_UUID_GATT_FN
GATT Characteristic Floor Number.
BT_UUID_GATT_ALT_VAL
GATT Characteristic Altitude UUID Value.

BT_UUID_GATT_ALT
GATT Characteristic Altitude.

BT_UUID_GATT_UNCERTAINTY_VAL
GATT Characteristic Uncertainty UUID Value.

BT_UUID_GATT_UNCERTAINTY
GATT Characteristic Uncertainty.

BT_UUID_GATT_LOC_NAME_VAL
GATT Characteristic Location Name UUID Value.

BT_UUID_GATT_LOC_NAME
GATT Characteristic Location Name.

BT_UUID_URI_VAL
URI UUID value.

BT_UUID_URI
URI.

BT_UUID_HTTP_HEADERS_VAL
HTTP Headers UUID value.

BT_UUID_HTTP_HEADERS
HTTP Headers.

BT_UUID_HTTP_STATUS_CODE_VAL
HTTP Status Code UUID value.

BT_UUID_HTTP_STATUS_CODE
HTTP Status Code.

BT_UUID_HTTP_ENTITY_BODY_VAL
HTTP Entity Body UUID value.

BT_UUID_HTTP_ENTITY_BODY
HTTP Entity Body.

BT_UUID_HTTP_CONTROL_POINT_VAL
HTTP Control Point UUID value.

BT_UUID_HTTP_CONTROL_POINT
HTTP Control Point.
BT_UUID_HTTPS_SECURITY_VAL
HTTPS Security UUID value.

BT_UUID_HTTPS_SECURITY
HTTPS Security.

BT_UUID_GATT_TDS_CP_VAL
GATT Characteristic TDS Control Point UUID Value.

BT_UUID_GATT_TDS_CP
GATT Characteristic TDS Control Point.

BT_UUID_OTS_FEATURE_VAL
OTS Feature Characteristic UUID value.

BT_UUID_OTS_FEATURE
OTS Feature Characteristic.

BT_UUID_OTS_NAME_VAL
OTS Object Name Characteristic UUID value.

BT_UUID_OTS_NAME
OTS Object Name Characteristic.

BT_UUID_OTS_TYPE_VAL
OTS Object Type Characteristic UUID value.

BT_UUID_OTS_TYPE
OTS Object Type Characteristic.

BT_UUID_OTS_SIZE_VAL
OTS Object Size Characteristic UUID value.

BT_UUID_OTS_SIZE
OTS Object Size Characteristic.

BT_UUID_OTS_FIRST_CREATED_VAL
OTS Object First-Created Characteristic UUID value.

BT_UUID_OTS_FIRST_CREATED
OTS Object First-Created Characteristic.

BT_UUID_OTS_LAST_MODIFIED_VAL
OTS Object Last-Modified Characteristic UUID value.

BT_UUID_OTS_LAST_MODIFIED
OTS Object Last-Modified Characteristic.
**BT_UUID_OTS_ID_VAL**
OTS Object ID Characteristic UUID value.

**BT_UUID_OTS_ID**
OTS Object ID Characteristic.

**BT_UUID_OTS_PROPERTIES_VAL**
OTS Object Properties Characteristic UUID value.

**BT_UUID_OTS_PROPERTIES**
OTS Object Properties Characteristic.

**BT_UUID_OTS_ACTION_CP_VAL**
OTS Object Action Control Point Characteristic UUID value.

**BT_UUID_OTS_ACTION_CP**
OTS Object Action Control Point Characteristic.

**BT_UUID_OTS_LIST_CP_VAL**
OTS Object List Control Point Characteristic UUID value.

**BT_UUID_OTS_LIST_CP**
OTS Object List Control Point Characteristic.

**BT_UUID_OTS_LIST_FILTER_VAL**
OTS Object List Filter Characteristic UUID value.

**BT_UUID_OTS_LIST_FILTER**
OTS Object List Filter Characteristic.

**BT_UUID_OTS_CHANGED_VAL**
OTS Object Changed Characteristic UUID value.

**BT_UUID_OTS_CHANGED**
OTS Object Changed Characteristic.

**BT_UUID_GATT_RPAO_VAL**
GATT Characteristic Resolvable Private Address Only UUID Value.

**BT_UUID_GATT_RPAO**
GATT Characteristic Resolvable Private Address Only.

**BT_UUID_OTS_TYPE_UNSPECIFIED_VAL**
OTS Unspecified Object Type UUID value.

**BT_UUID_OTS_TYPE_UNSPECIFIED**
OTS Unspecified Object Type.
**6.1. Bluetooth**

- **BT_UUID_OTS_DIRECTORY_LISTING_VAL**
  OTS Directory Listing UUID value.

- **BT_UUID_OTS_DIRECTORY_LISTING**
  OTS Directory Listing.

- **BT_UUID_GATT_FMF_VAL**
  GATT Characteristic Fitness Machine Feature UUID Value.

- **BT_UUID_GATT_FMF**
  GATT Characteristic Fitness Machine Feature.

- **BT_UUID_GATT_TD_VAL**
  GATT Characteristic Treadmill Data UUID Value.

- **BT_UUID_GATT_TD**
  GATT Characteristic Treadmill Data.

- **BT_UUID_GATT_CTD_VAL**
  GATT Characteristic Cross Trainer Data UUID Value.

- **BT_UUID_GATT_CTD**
  GATT Characteristic Cross Trainer Data.

- **BT_UUID_GATT_STPCD_VAL**
  GATT Characteristic Step Climber Data UUID Value.

- **BT_UUID_GATT_STPCD**
  GATT Characteristic Step Climber Data.

- **BT_UUID_GATT_STRCD_VAL**
  GATT Characteristic Stair Climber Data UUID Value.

- **BT_UUID_GATT_STRCD**
  GATT Characteristic Stair Climber Data.

- **BT_UUID_GATT_RD_VAL**
  GATT Characteristic Rower Data UUID Value.

- **BT_UUID_GATT_RD**
  GATT Characteristic Rower Data.

- **BT_UUID_GATT_IBD_VAL**
  GATT Characteristic Indoor Bike Data UUID Value.

- **BT_UUID_GATT_IBD**
  GATT Characteristic Indoor Bike Data.
BT_UUID_GATT_TRSTAT_VAL
GATT Characteristic Training Status UUID Value.

BT_UUID_GATT_TRSTAT
GATT Characteristic Training Status.

BT_UUID_GATT_SSR_VAL
GATT Characteristic Supported Speed Range UUID Value.

BT_UUID_GATT_SSR
GATT Characteristic Supported Speed Range.

BT_UUID_GATT_SIR_VAL
GATT Characteristic Supported Inclination Range UUID Value.

BT_UUID_GATT_SIR
GATT Characteristic Supported Inclination Range.

BT_UUID_GATT_SRLR_VAL
GATT Characteristic Supported Resistance Level Range UUID Value.

BT_UUID_GATT_SRLR
GATT Characteristic Supported Resistance Level Range.

BT_UUID_GATT_SHRR_VAL
GATT Characteristic Supported Heart Rate Range UUID Value.

BT_UUID_GATT_SHRR
GATT Characteristic Supported Heart Rate Range.

BT_UUID_GATT_SPR_VAL
GATT Characteristic Supported Power Range UUID Value.

BT_UUID_GATT_SPR
GATT Characteristic Supported Power Range.

BT_UUID_GATT_FMCP_VAL
GATT Characteristic Fitness Machine Control Point UUID Value.

BT_UUID_GATT_FMCP
GATT Characteristic Fitness Machine Control Point.

BT_UUID_GATT_FMS_VAL
GATT Characteristic Fitness Machine Status UUID Value.

BT_UUID_GATT_FMS
GATT Characteristic Fitness Machine Status.
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BT_UUID_MESH_PROV_DATA_IN_VAL
Mesh Provisioning Data In UUID value.

BT_UUID_MESH_PROV_DATA_IN
Mesh Provisioning Data In.

BT_UUID_MESH_PROV_DATA_OUT_VAL
Mesh Provisioning Data Out UUID value.

BT_UUID_MESH_PROV_DATA_OUT
Mesh Provisioning Data Out.

BT_UUID_MESH_PROXY_DATA_IN_VAL
Mesh Proxy Data In UUID value.

BT_UUID_MESH_PROXY_DATA_IN
Mesh Proxy Data In.

BT_UUID_MESH_PROXY_DATA_OUT_VAL
Mesh Proxy Data Out UUID value.

BT_UUID_MESH_PROXY_DATA_OUT
Mesh Proxy Data Out.

BT_UUID_GATT_NNN_VAL
GATT Characteristic New Number Needed UUID Value.

BT_UUID_GATT_NNN
GATT Characteristic New Number Needed.

BT_UUID_GATT_AC_VAL
GATT Characteristic Average Current UUID Value.

BT_UUID_GATT_AC
GATT Characteristic Average Current.

BT_UUID_GATT_AV_VAL
GATT Characteristic Average Voltage UUID Value.

BT_UUID_GATT_AV
GATT Characteristic Average Voltage.

BT_UUID_GATTBOOLEAN_VAL
GATT Characteristic Boolean UUID Value.

BT_UUID_GATTBOOLEAN
GATT Characteristic Boolean.
BT_UUID_GATT_CRFDP_VAL
GATT Characteristic Chromatic Distance From Planckian UUID Value.

BT_UUID_GATT_CRFDP
GATT Characteristic Chromatic Distance From Planckian.

BT_UUID_GATT_CRCOORDS_VAL
GATT Characteristic Chromaticity Coordinates UUID Value.

BT_UUID_GATT_CRCOORDS
GATT Characteristic Chromaticity Coordinates.

BT_UUID_GATT_CRCCT_VAL
GATT Characteristic Chromaticity In CCT And Duv Values UUID Value.

BT_UUID_GATT_CRCCT
GATT Characteristic Chromaticity In CCT And Duv Values.

BT_UUID_GATT_CRT_VAL
GATT Characteristic Chromaticity Tolerance UUID Value.

BT_UUID_GATT_CRT
GATT Characteristic Chromaticity Tolerance.

BT_UUID_GATT_CIEIDX_VAL
GATT Characteristic CIE 13.3-1995 Color Rendering Index UUID Value.

BT_UUID_GATT_CIEIDX
GATT Characteristic CIE 13.3-1995 Color Rendering Index.

BT_UUID_GATT_COEFFICIENT_VAL
GATT Characteristic Coefficient UUID Value.

BT_UUID_GATT_COEFFICIENT
GATT Characteristic Coefficient.

BT_UUID_GATT_CCTEMP_VAL
GATT Characteristic Correlated Color Temperature UUID Value.

BT_UUID_GATT_CCTEMP
GATT Characteristic Correlated Color Temperature.

BT_UUID_GATT_COUNT16_VAL
GATT Characteristic Count 16 UUID Value.

BT_UUID_GATT_COUNT16
GATT Characteristic Count 16.
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- **BT_UUID_GATT_COUNT24_VAL**
  - GATT Characteristic Count 24 UUID Value.

- **BT_UUID_GATT_COUNT24**
  - GATT Characteristic Count 24.

- **BT_UUID_GATT_CNTRCODE_VAL**
  - GATT Characteristic Country Code UUID Value.

- **BT_UUID_GATT_CNTRCODE**
  - GATT Characteristic Country Code.

- **BT_UUID_GATT_DATEUTC_VAL**
  - GATT Characteristic Date UTC UUID Value.

- **BT_UUID_GATT_DATEUTC**
  - GATT Characteristic Date UTC.

- **BT_UUID_GATT_EC_VAL**
  - GATT Characteristic Electric Current UUID Value.

- **BT_UUID_GATT_EC**
  - GATT Characteristic Electric Current.

- **BT_UUID_GATT_ECR_VAL**
  - GATT Characteristic Electric Current Range UUID Value.

- **BT_UUID_GATT_ECR**
  - GATT Characteristic Electric Current Range.

- **BT_UUID_GATT_ECSPEC_VAL**

- **BT_UUID_GATT_ECSPEC**

- **BT_UUID_GATT_ECSTAT_VAL**

- **BT_UUID_GATT_ECSTAT**
  - GATT Characteristic Electric Current Statistics.

- **BT_UUID_GATT_ENERGY_VAL**
  - GATT Characteristic Energy UUID Value.

- **BT_UUID_GATT_ENERGY**
  - GATT Characteristic Energy.
BT_UUID_GATT_EPOD_VAL
GATT Characteristic Energy In A Period Of Day UUID Value.

BT_UUID_GATT_EPOD
GATT Characteristic Energy In A Period Of Day.

BT_UUID_GATT_EVTSTAT_VAL
GATT Characteristic Event Statistics UUID Value.

BT_UUID_GATT_EVTSTAT
GATT Characteristic Event Statistics.

BT_UUID_GATT_FSTR16_VAL
GATT Characteristic Fixed String 16 UUID Value.

BT_UUID_GATT_FSTR16
GATT Characteristic Fixed String 16.

BT_UUID_GATT_FSTR24_VAL
GATT Characteristic Fixed String 24 UUID Value.

BT_UUID_GATT_FSTR24
GATT Characteristic Fixed String 24.

BT_UUID_GATT_FSTR36_VAL
GATT Characteristic Fixed String 36 UUID Value.

BT_UUID_GATT_FSTR36
GATT Characteristic Fixed String 36.

BT_UUID_GATT_FSTR8_VAL
GATT Characteristic Fixed String 8 UUID Value.

BT_UUID_GATT_FSTR8
GATT Characteristic Fixed String 8.

BT_UUID_GATT_GENLVL_VAL
GATT Characteristic Generic Level UUID Value.

BT_UUID_GATT_GENLVL
GATT Characteristic Generic Level.

BT_UUID_GATT_GTIN_VAL
GATT Characteristic Global Trade Item Number UUID Value.

BT_UUID_GATT_GTIN
GATT Characteristic Global Trade Item Number.
BT_UUID_GATT_ILLUM_VAL
GATT Characteristic Illuminance UUID Value.

BT_UUID_GATT_ILLUM
GATT Characteristic Illuminance.

BT_UUID_GATT_LUMEFF_VAL
GATT Characteristic Luminous Efficacy UUID Value.

BT_UUID_GATT_LUMEFF
GATT Characteristic Luminous Efficacy.

BT_UUID_GATT_LUMNRG_VAL
GATT Characteristic Luminous Energy UUID Value.

BT_UUID_GATT_LUMNRG
GATT Characteristic Luminous Energy.

BT_UUID_GATT_LUMEXP_VAL
GATT Characteristic Luminous Exposure UUID Value.

BT_UUID_GATT_LUMEXP
GATT Characteristic Luminous Exposure.

BT_UUID_GATT_LUMFLX_VAL
GATT Characteristic Luminous Flux UUID Value.

BT_UUID_GATT_LUMFLX
GATT Characteristic Luminous Flux.

BT_UUID_GATT_LUMFLXR_VAL
GATT Characteristic Luminous Flux Range UUID Value.

BT_UUID_GATT_LUMFLXR
GATT Characteristic Luminous Flux Range.

BT_UUID_GATT_LUMINT_VAL
GATT Characteristic Luminous Intensity UUID Value.

BT_UUID_GATT_LUMINT
GATT Characteristic Luminous Intensity.

BT_UUID_GATT_MASSFLOW_VAL
GATT Characteristic Mass Flow UUID Value.

BT_UUID_GATT_MASSFLOW
GATT Characteristic Mass Flow.
BT_UUID_GATT_PERLGHT_VAL
GATT Characteristic Perceived Lightness UUID Value.

BT_UUID_GATT_PERLGHT
GATT Characteristic Perceived Lightness.

BT_UUID_GATT_PER8_VAL
GATT Characteristic Percentage 8 UUID Value.

BT_UUID_GATT_PER8
GATT Characteristic Percentage 8.

BT_UUID_GATT_PWR_VAL
GATT Characteristic Power UUID Value.

BT_UUID_GATT_PWR
GATT Characteristic Power.

BT_UUID_GATT_PWRSPEC_VAL
GATT Characteristic Power Specification UUID Value.

BT_UUID_GATT_PWRSPEC
GATT Characteristic Power Specification.

BT_UUID_GATT_RRICR_VAL
GATT Characteristic Relative Runtime In A Current Range UUID Value.

BT_UUID_GATT_RRICR
GATT Characteristic Relative Runtime In A Current Range.

BT_UUID_GATT_RRIGLR_VAL
GATT Characteristic Relative Runtime In A Generic Level Range UUID Value.

BT_UUID_GATT_RRIGLR
GATT Characteristic Relative Runtime In A Generic Level Range.

BT_UUID_GATT_RVIVR_VAL
GATT Characteristic Relative Value In A Voltage Range UUID Value.

BT_UUID_GATT_RVIVR
GATT Characteristic Relative Value In A Voltage Range.

BT_UUID_GATT_RVIIR_VAL
GATT Characteristic Relative Value In A Illuminance Range UUID Value.

BT_UUID_GATT_RVIIR
GATT Characteristic Relative Value In A Illuminance Range.
BT_UUID_GATT_RVIPOD_VAL
GATT Characteristic Relative Value In A Period Of Day UUID Value.

BT_UUID_GATT_RVIPOD
GATT Characteristic Relative Value In A Period Of Day.

BT_UUID_GATT_RVITR_VAL
GATT Characteristic Relative Value In A Temperature Range UUID Value.

BT_UUID_GATT_RVITR
GATT Characteristic Relative Value In A Temperature Range.

BT_UUID_GATT_TEMP8_VAL
GATT Characteristic Temperature 8 UUID Value.

BT_UUID_GATT_TEMP8
GATT Characteristic Temperature 8.

BT_UUID_GATT_TEMP8_IPOD_VAL
GATT Characteristic Temperature 8 In A Period Of Day UUID Value.

BT_UUID_GATT_TEMP8_IPOD
GATT Characteristic Temperature 8 In A Period Of Day.

BT_UUID_GATT_TEMP8_STAT_VAL
GATT Characteristic Temperature 8 Statistics UUID Value.

BT_UUID_GATT_TEMP8_STAT
GATT Characteristic Temperature 8 Statistics.

BT_UUID_GATT_TEMP_RNG_VAL
GATT Characteristic Temperature Range UUID Value.

BT_UUID_GATT_TEMP_RNG
GATT Characteristic Temperature Range.

BT_UUID_GATT_TEMP_STAT_VAL
GATT Characteristic Temperature Statistics UUID Value.

BT_UUID_GATT_TEMP_STAT
GATT Characteristic Temperature Statistics.

BT_UUID_GATT_TIM_DC8_VAL
GATT Characteristic Time Decihour 8 UUID Value.

BT_UUID_GATT_TIM_DC8
GATT Characteristic Time Decihour 8.
BT_UUID_GATT_TIM_EXP8_VAL
GATT Characteristic Time Exponential 8 UUID Value.

BT_UUID_GATT_TIM_EXP8
GATT Characteristic Time Exponential 8.

BT_UUID_GATT_TIM_H24_VAL
GATT Characteristic Time Hour 24 UUID Value.

BT_UUID_GATT_TIM_H24
GATT Characteristic Time Hour 24.

BT_UUID_GATT_TIM_MS24_VAL
GATT Characteristic Time Millisecond 24 UUID Value.

BT_UUID_GATT_TIM_MS24
GATT Characteristic Time Millisecond 24.

BT_UUID_GATT_TIM_S16_VAL
GATT Characteristic Time Second 16 UUID Value.

BT_UUID_GATT_TIM_S16
GATT Characteristic Time Second 16.

BT_UUID_GATT_TIM_S8_VAL
GATT Characteristic Time Second 8 UUID Value.

BT_UUID_GATT_TIM_S8
GATT Characteristic Time Second 8.

BT_UUID_GATT_V_VAL
GATT Characteristic Voltage UUID Value.

BT_UUID_GATT_V
GATT Characteristic Voltage.

BT_UUID_GATT_V_SPEC_VAL
GATT Characteristic Voltage Specification UUID Value.

BT_UUID_GATT_V_SPEC
GATT Characteristic Voltage Specification.

BT_UUID_GATT_V_STAT_VAL
GATT Characteristic Voltage Statistics UUID Value.

BT_UUID_GATT_V_STAT
GATT Characteristic Voltage Statistics.
BT_UUID_GATT_VOLF_VAL
GATT Characteristic Volume Flow UUID Value.

BT_UUID_GATT_VOLF
GATT Characteristic Volume Flow.

BT_UUID_GATT_CRCORD_VAL
GATT Characteristic Chromaticity Coordinate (not Coordinates) UUID Value.

BT_UUID_GATT_CRCORD
GATT Characteristic Chromaticity Coordinate (not Coordinates)

BT_UUID_GATT_RCF_VAL
GATT Characteristic RC Feature UUID Value.

BT_UUID_GATT_RCF
GATT Characteristic RC Feature.

BT_UUID_GATT_RCSET_VAL
GATT Characteristic RC Settings UUID Value.

BT_UUID_GATT_RCSET
GATT Characteristic RC Settings.

BT_UUID_GATT_RCCP_VAL
GATT Characteristic Reconnection Configuration Control Point UUID Value.

BT_UUID_GATT_RCCP
GATT Characteristic Reconnection Configuration Control Point.

BT_UUID_GATT_IDD_SC_VAL
GATT Characteristic IDD Status Changed UUID Value.

BT_UUID_GATT_IDD_SC
GATT Characteristic IDD Status Changed.

BT_UUID_GATT_IDD_S_VAL
GATT Characteristic IDD Status UUID Value.

BT_UUID_GATT_IDD_S
GATT Characteristic IDD Status.

BT_UUID_GATT_IDD_AS_VAL
GATT Characteristic IDD Announciation Status UUID Value.

BT_UUID_GATT_IDD_AS
GATT Characteristic IDD Announciation Status.
BT_UUID_GATT_IDD_F_VAL
GATT Characteristic IDD Features UUID Value.

BT_UUID_GATT_IDD_F
GATT Characteristic IDD Features.

BT_UUID_GATT_IDD_SRCP_VAL
GATT Characteristic IDD Status Reader Control Point UUID Value.

BT_UUID_GATT_IDD_SRCP
GATT Characteristic IDD Status Reader Control Point.

BT_UUID_GATT_IDD_CCP_VAL
GATT Characteristic IDD Command Control Point UUID Value.

BT_UUID_GATT_IDD_CCP
GATT Characteristic IDD Command Control Point.

BT_UUID_GATT_IDD_CD_VAL
GATT Characteristic IDD Command Data UUID Value.

BT_UUID_GATT_IDD_CD
GATT Characteristic IDD Command Data.

BT_UUID_GATT_IDD_RACP_VAL
GATT Characteristic IDD Record Access Control Point UUID Value.

BT_UUID_GATT_IDD_RACP
GATT Characteristic IDD Record Access Control Point.

BT_UUID_GATT_IDD_HD_VAL
GATT Characteristic IDD History Data UUID Value.

BT_UUID_GATT_IDD_HD
GATT Characteristic IDD History Data.

BT_UUID_GATT_CLIENT_FEATURES_VAL
GATT Characteristic Client Supported Features UUID value.

BT_UUID_GATT_CLIENT_FEATURES
GATT Characteristic Client Supported Features.

BT_UUID_GATT_DB_HASH_VAL
GATT Characteristic Database Hash UUID value.

BT_UUID_GATT_DB_HASH
GATT Characteristic Database Hash.
BT_UUID_GATT_BSS_CP_VAL
GATT Characteristic BSS Control Point UUID Value.

BT_UUID_GATT_BSS_CP
GATT Characteristic BSS Control Point.

BT_UUID_GATT_BSS_R_VAL
GATT Characteristic BSS Response UUID Value.

BT_UUID_GATT_BSS_R
GATT Characteristic BSS Response.

BT_UUID_GATT_EMG_ID_VAL
GATT Characteristic Emergency ID UUID Value.

BT_UUID_GATT_EMG_ID
GATT Characteristic Emergency ID.

BT_UUID_GATT_EMG_TXT_VAL
GATT Characteristic Emergency Text UUID Value.

BT_UUID_GATT_EMG_TXT
GATT Characteristic Emergency Text.

BT_UUID_GATT_ACS_S_VAL
GATT Characteristic ACS Status UUID Value.

BT_UUID_GATT_ACS_S
GATT Characteristic ACS Status.

BT_UUID_GATT_ACS_DI_VAL
GATT Characteristic ACS Data In UUID Value.

BT_UUID_GATT_ACS_DI
GATT Characteristic ACS Data In.

BT_UUID_GATT_ACS_DON_VAL
GATT Characteristic ACS Data Out Notify UUID Value.

BT_UUID_GATT_ACS_DON
GATT Characteristic ACS Data Out Notify.

BT_UUID_GATT_ACS_DOI_VAL
GATT Characteristic ACS Data Out Indicate UUID Value.

BT_UUID_GATT_ACS_DOI
GATT Characteristic ACS Data Out Indicate.
BT_UUID_GATT_ACS_CP_VAL
GATT Characteristic ACS Control Point UUID Value.

BT_UUID_GATT_ACS_CP
GATT Characteristic ACS Control Point.

BT_UUID_GATT_EBPM_Val
GATT Characteristic Enhanced Blood Pressure Measurement UUID Value.

BT_UUID_GATT_EBPM
GATT Characteristic Enhanced Blood Pressure Measurement.

BT_UUID_GATT_EICP_Val
GATT Characteristic Enhanced Intermediate Cuff Pressure UUID Value.

BT_UUID_GATT_EICP
GATT Characteristic Enhanced Intermediate Cuff Pressure.

BT_UUID_GATT_BPR_Val
GATT Characteristic Blood Pressure Record UUID Value.

BT_UUID_GATT_BPR
GATT Characteristic Blood Pressure Record.

BT_UUID_GATT_RU_Val
GATT Characteristic Registered User UUID Value.

BT_UUID_GATT_RU
GATT Characteristic Registered User.

BT_UUID_GATT_BR_EDR_HD_Val
GATT Characteristic BR-EDR Handover Data UUID Value.

BT_UUID_GATT_BR_EDR_HD
GATT Characteristic BR-EDR Handover Data.

BT_UUID_GATT_BT_SIG_D_Val
GATT Characteristic Bluetooth SIG Data UUID Value.

BT_UUID_GATT_BT_SIG_D
GATT Characteristic Bluetooth SIG Data.

BT_UUID_GATT_SERVER_FEATURES_Val
GATT Characteristic Server Supported Features UUID value.

BT_UUID_GATT_SERVER_FEATURES
GATT Characteristic Server Supported Features.
BT_UUID_GATT_PHY_AMF_VAL
GATT Characteristic Physical Activity Monitor Features UUID Value.

BT_UUID_GATT_PHY_AMF
GATT Characteristic Physical Activity Monitor Features.

BT_UUID_GATT_GEN_AID_VAL
GATT Characteristic General Activity Instantaneous Data UUID Value.

BT_UUID_GATT_GEN_AID
GATT Characteristic General Activity Instantaneous Data.

BT_UUID_GATT_GEN_ASD_VAL
GATT Characteristic General Activity Summary Data UUID Value.

BT_UUID_GATT_GEN_ASD
GATT Characteristic General Activity Summary Data.

BT_UUID_GATT_CR_AID_VAL
GATT Characteristic CardioRespiratory Activity Instantaneous Data UUID Value.

BT_UUID_GATT_CR_AID
GATT Characteristic CardioRespiratory Activity Instantaneous Data.

BT_UUID_GATT_CR_ASD_VAL
GATT Characteristic CardioRespiratory Activity Summary Data UUID Value.

BT_UUID_GATT_CR_ASD
GATT Characteristic CardioRespiratory Activity Summary Data.

BT_UUID_GATT_SC_ASD_VAL
GATT Characteristic Step Counter Activity Summary Data UUID Value.

BT_UUID_GATT_SC_ASD
GATT Characteristic Step Counter Activity Summary Data.

BT_UUID_GATT_SLP_AID_VAL
GATT Characteristic Sleep Activity Instantaneous Data UUID Value.

BT_UUID_GATT_SLP_AID
GATT Characteristic Sleep Activity Instantaneous Data.

BT_UUID_GATT_SLP_ASD_VAL
GATT Characteristic Sleep Activity Summary Data UUID Value.

BT_UUID_GATT_SLP_ASD
GATT Characteristic Sleep Activity Summary Data.
BT_UUID_GATT_PHY_AMCP_VAL
GATT Characteristic Physical Activity Monitor Control Point UUID Value.

BT_UUID_GATT_PHY_AMCP
GATT Characteristic Physical Activity Monitor Control Point.

BT_UUID_GATT_ACS_VAL
GATT Characteristic Activity Current Session UUID Value.

BT_UUID_GATT_ACS
GATT Characteristic Activity Current Session.

BT_UUID_GATT_PHY_ASDESC_VAL
GATT Characteristic Physical Activity Session Descriptor UUID Value.

BT_UUID_GATT_PHY_ASDESC
GATT Characteristic Physical Activity Session Descriptor.

BT_UUID_GATT_PREF_U_VAL
GATT Characteristic Preffered Units UUID Value.

BT_UUID_GATT_PREF_U
GATT Characteristic Preffered Units.

BT_UUID_GATT_HRES_H_VAL
GATT Characteristic High Resolution Height UUID Value.

BT_UUID_GATT_HRES_H
GATT Characteristic High Resolution Height.

BT_UUID_GATT_MID_NAME_VAL
GATT Characteristic Middle Name UUID Value.

BT_UUID_GATT_MID_NAME
GATT Characteristic Middle Name.

BT_UUID_GATT_STRDLEN_VAL
GATT Characteristic Stride Length UUID Value.

BT_UUID_GATT_STRDLEN
GATT Characteristic Stride Length.

BT_UUID_GATT_HANDEDNESS_VAL
GATT Characteristic Handedness UUID Value.

BT_UUID_GATT_HANDEDNESS
GATT Characteristic Handedness.
BT_UUID_GATT_DEVICE_WP_VAL
GATT Characteristic Device Wearing Position UUID Value.

BT_UUID_GATT_DEVICE_WP
GATT Characteristic Device Wearing Position.

BT_UUID_GATT_4ZHRL_VAL
GATT Characteristic Four Zone Heart Rate Limit UUID Value.

BT_UUID_GATT_4ZHRL
GATT Characteristic Four Zone Heart Rate Limit.

BT_UUID_GATT_HIET_VAL
GATT Characteristic High Intensity Exercise Threshold UUID Value.

BT_UUID_GATT_HIET
GATT Characteristic High Intensity Exercise Threshold.

BT_UUID_GATT_AG_VAL
GATT Characteristic Activity Goal UUID Value.

BT_UUID_GATT_AG
GATT Characteristic Activity Goal.

BT_UUID_GATT_SIN_VAL
GATT Characteristic Sedentary Interval Notification UUID Value.

BT_UUID_GATT_SIN
GATT Characteristic Sedentary Interval Notification.

BT_UUID_GATT_CI_VAL
GATT Characteristic Caloric Intake UUID Value.

BT_UUID_GATT_CI
GATT Characteristic Caloric Intake.

BT_UUID_GATT_TMAPR_VAL
GATT Characteristic TMAP Role UUID Value.

BT_UUID_GATT_TMAPR
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BT_UUID_AICS_STATE_VAL
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BT_UUID_AICS_STATE
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BT_UUID_AICS_GAIN_SETTINGS_VAL
Audio Input Control Service Gain Settings Properties value.

BT_UUID_AICS_GAIN_SETTINGS
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BT_UUID_AICS_INPUT_TYPE_VAL
Audio Input Control Service Input Type value.

BT_UUID_AICS_INPUT_TYPE
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BT_UUID_AICS_INPUT_STATUS_VAL
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BT_UUID_AICS_CONTROL_VAL
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BT_UUID_AICS_DESCRIPTION
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BT_UUID_VCS_STATE_VAL
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BT_UUID_VCS_STATE
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BT_UUID_VCS_CONTROL
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BT_UUID_VCS_FLAGS_VAL
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BT_UUID_VCS_FLAGS
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BT_UUID_VOCS_STATE_VAL
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BT_UUID_VOCS_STATE
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BT_UUID_VOCS_LOCATION_VAL
   Audio Location value.

BT_UUID_VOCS_LOCATION
   Audio Location.

BT_UUID_VOCS_CONTROL_VAL
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BT_UUID_VOCS_CONTROL
   Volume Offset Control Point.

BT_UUID_VOCS_DESCRIPTION_VAL
   Volume Offset Audio Output Description value.

BT_UUID_VOCS_DESCRIPTION
   Volume Offset Audio Output Description.

BT_UUID_CSIS_SET_SIRK_VAL
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BT_UUID_CSIS_SET_SIRK
   Set Identity Resolving Key.

BT_UUID_CSIS_SET_SIZE_VAL
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BT_UUID_CSIS_SET_SIZE
   Set size.

BT_UUID_CSIS_SET_LOCK_VAL
   Set lock value.

BT_UUID_CSIS_SET_LOCK
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BT_UUID_CSIS_RANK_VAL
   Rank value.

BT_UUID_CSIS_RANK
   Rank.

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GATT Characteristic Encrypted Data Key Material.

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GATT Characteristic Apparent Energy 32 UUID Value.

BT_UUID_GATT_AE32
GATT Characteristic Apparent Energy 32.

BT_UUID_GATT_AP_VAL
GATT Characteristic Apparent Power UUID Value.

BT_UUID_GATT_AP
GATT Characteristic Apparent Power.

BT_UUID_GATT_CO2CONC_VAL
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BT_UUID_GATT_CO2CONC
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BT_UUID_GATT_COS_VAL
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BT_UUID_GATT_COS
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BT_UUID_GATT_DEVTF_VAL
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BT_UUID_GATT_DEVTF
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BT_UUID_GATT_DEVTP
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BT_UUID_GATT_DEVTCP_VAL
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BT_UUID_GATT_DEVTCP
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BT_UUID_GATT_TCLD_VAL
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BT_UUID_MCS_PLAYER_NAME_VAL
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BT_UUID_MCS_ICON_OBJ_ID
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BT_UUID_MCS_TRACK_DURATION
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BT_UUID_MCS_PLAYBACK_SPEED_VAL
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BT_UUID_MCS_PLAYBACK_SPEED
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BT_UUID_MCS_TRACK_SEGMENTS_OBJ_ID_VAL
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BT_UUID_MCS_SEARCH_RESULTS_OBJ_ID
Search result object ID.

BT_UUID_MCS_SEARCH_CONTROL_POINT_VAL
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BT_UUID_GATT_E32
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BT_UUID_OTS_TYPE_MPL_ICON
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BT_UUID_OTS_TYPE_TRACK_SEGMENT_VAL
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BT_UUID_OTS_TYPE_TRACK_SEGMENT
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BT_UUID_OTS_TYPE_TRACK_VAL
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BT_UUID_OTS_TYPE_GROUP_VAL
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BT_UUID_GATT_ACTETD_VAL
GATT Characteristic Advertising Constant Tone Extension Transmit Duration UUID Value.
BT_UUID_GATT_ACTETD
GATT Characteristic Advertising Constant Tone Extension Transmit Duration.

BT_UUID_GATT_ACTEI_VAL
GATT Characteristic Advertising Constant Tone Extension Interval UUID Value.

BT_UUID_GATT_ACTEI
GATT Characteristic Advertising Constant Tone Extension Interval.

BT_UUID_GATT_ACTEP_VAL
GATT Characteristic Advertising Constant Tone Extension PHY UUID Value.

BT_UUID_GATT_ACTEP
GATT Characteristic Advertising Constant Tone Extension PHY.

BT_UUID_TBS_PROVIDER_NAME_VAL
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BT_UUID_TBS_PROVIDER_NAME
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BT_UUID_TBS_UCI_VAL
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BT_UUID_TBS_UCI
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BT_UUID_TBS_TECHNOLOGY_VAL
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Bearer Signal Strength value.

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BT_UUID_TBS_LIST_CURRENT_CALLS
Bearer List Current Calls.

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BT_UUID_CCID
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BT_UUID_TBS_INCOMING_URI
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BT_UUID_TBS_CALL_STATE_VAL
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BT_UUID_TBS_OPTIONAL_OPCODES
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BT_UUID_TBS_INCOMING_CALL
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BT_UUID_TBS_FRIENDLY_NAME_VAL
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BT_UUID_TBS_FRIENDLY_NAME
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BT_UUID_MICS_MUTE_VAL
    Microphone Control Service Mute value.

BT_UUID_MICS_MUTE
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BT_UUID_ASCS_ASE_SNK_VAL
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BT_UUID_ASCS_ASE_SNK
    Audio Stream Endpoint Sink Characteristic.

BT_UUID_ASCS_ASE_SRC_VAL
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BT_UUID_ASCS_ASE_SRC
    Audio Stream Endpoint Source Characteristic.

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    Audio Stream Endpoint Control Point Characteristic value.

BT_UUID_ASCS_ASE_CP
    Audio Stream Endpoint Control Point Characteristic.

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    Broadcast Audio Scan Service Scan State value.

BT_UUID_BASS_CONTROL_POINT
    Broadcast Audio Scan Service Scan State.

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**BT_UUID_GATT_NONCH4CONC**
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**BT_UUID_GATT_O3CONC**
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**BT_UUID_GATT_PM10CONC_VAL**
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BT_UUID_GATT_FSTR64
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GATT Characteristic High Temperature.

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BT_UUID_GMAP_UGG_FEAT_VAL
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6.1. Bluetooth
Enums

Bluetooth UUID types.

**Values:**

- `BT_UUID_TYPE_16` - UUID type 16-bit.
- `BT_UUID_TYPE_32` - UUID type 32-bit.
- `BT_UUID_TYPE_128` - UUID type 128-bit.

Functions

**int bt_uuid_cmp(const struct bt_uuid *u1, const struct bt_uuid *u2)**

Compare Bluetooth UUIDs.

Compares 2 Bluetooth UUIDs, if the types are different both UUIDs are first converted to 128 bits format before comparing.

**Parameters**

- `u1` – First Bluetooth UUID to compare
- `u2` – Second Bluetooth UUID to compare

**Returns**

- negative value if `u1 < u2`, 0 if `u1 == u2`, else positive

**bool bt_uuid_create(struct bt_uuid *uuid, const uint8_t *data, uint8_t data_len)**

Create a `bt_uuid` from a little-endian data buffer.

Create a `bt_uuid` from a little-endian data buffer. The `data_len` parameter is used to determine whether the UUID is in 16, 32 or 128 bit format (length 2, 4 or 16). Note: 32 bit format is not allowed over the air.

**Parameters**

- `uuid` – Pointer to the `bt_uuid` variable
- `data` – pointer to UUID stored in little-endian data buffer
- `data_len` – length of the UUID in the data buffer

**Returns**

- true if the data was valid and the UUID was successfully created.

**void bt_uuid_to_str(const struct bt_uuid *uuid, char *str, size_t len)**

Convert Bluetooth UUID to string.

Converts Bluetooth UUID to string. UUID can be in any format, 16-bit, 32-bit or 128-bit.

**Parameters**

- `uuid` – Bluetooth UUID
- `str` – pointer where to put converted string
- `len` – length of str
struct bt_uuid
#include <uuid.h> This is a ‘tentative’ type and should be used as a pointer only.

struct bt_uuid_16
#include <uuid.h>

Public Members

struct bt_uuid uuid
UUID generic type.

uint16_t val
UUID value, 16-bit in host endianness.

struct bt_uuid_32
#include <uuid.h>

Public Members

struct bt_uuid uuid
UUID generic type.

uint32_t val
UUID value, 32-bit in host endianness.

struct bt_uuid_128
#include <uuid.h>

Public Members

struct bt_uuid uuid
UUID generic type.

uint8_t val[16]
UUID value, 128-bit in little-endian format.

Bluetooth: Basic Audio Profile

This document describes how to run Basic Audio Profile functionality which includes:
- Capabilities and Endpoint discovery
- Audio Stream Endpoint procedures

Commands

6.1. Bluetooth
bap --help
Subcommands:
  init
  select_broadcast :<stream>
  create_broadcast :[preset <preset_name>] [enc <broadcast_code>]
  start_broadcast :
  stop_broadcast :
  delete_broadcast :
  broadcast_scan :<on, off>
  create_broadcast_sink :0x<broadcast_id>
  sync_broadcast :0x<bis_index> [[0x<bis_index> 0x<bis_index>] ...]
  stop_broadcast_sink :
  term_broadcast_sink :
  discover :[dir: sink, source] <index> [loc <loc_bits>] [preset
  ...<preset_name>]
  stream_qos :interval [framing] [latency] [pd] [sdu] [phy] [rtn]
  qos :Send QoS configure for Unicast Group
  enable :[context]
  stop
  print_ase_info :Print ASE info for default connection
  metadata :[context]
  start
  disable
  release
  list
  select_unicast :<stream>
  preset :<sink, source, broadcast> [preset]
  send :Send to Audio Stream [data]
  start_sine :Start sending a LC3 encoded sine wave
  stop_sine :Stop sending a LC3 encoded sine wave
  set_location :<direction: sink, source> <location bitmask>
  set_context :<direction: sink, source><context bitmask> <type: supported, available>

Table 8: State Machine Transitions

<table>
<thead>
<tr>
<th>Command</th>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>init</td>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
<tr>
<td>discover</td>
<td>init</td>
<td>any</td>
<td>any</td>
</tr>
<tr>
<td>config</td>
<td>discover</td>
<td>idle/codec-configured/qos-configured</td>
<td>codec-configured</td>
</tr>
<tr>
<td>qos</td>
<td>config</td>
<td>codec-configured/qos-configured</td>
<td>qos-configured</td>
</tr>
<tr>
<td>enable</td>
<td>qos</td>
<td>qos-configured</td>
<td>enabling</td>
</tr>
<tr>
<td>[start]</td>
<td>enable</td>
<td>enabling</td>
<td>streaming</td>
</tr>
<tr>
<td>disable</td>
<td>enable</td>
<td>enabling/streaming</td>
<td>disabling</td>
</tr>
<tr>
<td>[stop]</td>
<td>disable</td>
<td>disabling</td>
<td>qos-configure/idle</td>
</tr>
<tr>
<td>release</td>
<td>config</td>
<td>any</td>
<td>releasing/configure/idle</td>
</tr>
<tr>
<td>list</td>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
<tr>
<td>select_unicast</td>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
<tr>
<td>connect</td>
<td>discover</td>
<td>idle/codec-configured/qos-configured</td>
<td>codec-configured</td>
</tr>
<tr>
<td>send</td>
<td>enable</td>
<td>streaming</td>
<td>none</td>
</tr>
</tbody>
</table>

Example Central  
Connect and establish a stream:
Or using connect command:

```
uart:~$ bt init
uart:~$ bap init
uart:~$ bt connect <address>
uart:~$ gatt exchange-mtu
uart:~$ bap discover sink
uart:~$ bap config sink 0
uart:~$ bap qos
uart:~$ bap enable
```

Disconnect and release:

```
uart:~$ bap disable
uart:~$ bap release
```

**Example Peripheral**  Listen:

```
uart:~$ bt init
uart:~$ bap init
uart:~$ bt advertise on
```

Server initiated disable and release:

```
uart:~$ bap disable
uart:~$ bap release
```

**Example Broadcast Source**  Create and establish a broadcast source stream:

```
uart:~$ bap init
uart:~$ bap create_broadcast
uart:~$ bap start_broadcast
```

Stop and release a broadcast source stream:

```
uart:~$ bap stop_broadcast
uart:~$ bap delete_broadcast
```

**Example Broadcast Sink**  Scan for and establish a broadcast sink stream. The command `bap create_broadcast_sink 0xEF6716` will either use existing periodic advertising sync (if exist) or start scanning and sync to the periodic advertising before syncing to the BIG.

```
uart:~$ bap init
uart:~$ bap broadcast_scan on
Found broadcaster with ID 0xEF6716 and addr 3D:A5:F9:35:0B:19 (random) and sid 0x00
uart:~$ bap create_broadcast_sink 0xEF6716
Attempting to PA sync to the broadcaster
PA synced to broadcast with broadcast ID 0xEF6716
Attempting to sync to the BIG
Received BASE from sink 0x20031fac:
```

(continues on next page)
Zephyr Project Documentation, Release 3.6.0-rc3

Presentation delay: 40000
Subgroup count: 2
Subgroup[0]:
codec cfg id 0x06 cid 0x0000 vid 0x0000
data_count 4
data #0: type 0x01 len 1
00000000: 03 |.
data #1: type 0x02 len 1
00000000: 01 |.
data #2: type 0x03 len 4
00000000: 01 00 00 00 |.... .
data #3: type 0x04 len 2
00000000: 28 00 |(. .
meta_count 4
meta #0: type 0x02 len 2
00000000: 01 00 |.. .
   BIS[0] index 0x01
Subgroup[1]:
codec cfg id 0x06 cid 0x0000 vid 0x0000
data_count 4
data #0: type 0x01 len 1
00000000: 03 |.
data #1: type 0x02 len 1
00000000: 01 |.
data #2: type 0x03 len 4
00000000: 01 00 00 00 |.... .
data #3: type 0x04 len 2
00000000: 28 00 |(. .
meta_count 4
meta #0: type 0x02 len 2
00000000: 01 00 |.. .
   BIS[1] index 0x01
[0]: 0x01
[1]: 0x01
Possible indexes: 0x01 0x01
uart:~$ bap_sync_broadcast 0x01

Stop and release a broadcast sink stream:

uart:~$ bap stop_broadcast_sink
uart:~$ bap term_broadcast_sink

Init  The init command register local PAC records which are necessary to be able to configure stream and properly manage capabilities in use.

Table 9: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
</tbody>
</table>

uart:~$ bap init

Discover PAC(s) and ASE(s)  Once connected the discover command discover PAC records and ASE characteristics representing remote endpoints.
Table 10: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>init</td>
<td>any</td>
<td>any</td>
</tr>
</tbody>
</table>

**Note:** Use command `gatt exchange-mtu` to make sure the MTU is configured properly.

```bash
uart:~$ gatt exchange-mtu
Exchange pending
uart:~$ bap discover [type: sink, source]
uart:~$ bap discover sink
cap 0x8175940 type 0x01
codec 0x06 cid 0x0000 vid 0x0000 count 4
data #0: type 0x01 len 1
  00000000: 3f |? | |
data #1: type 0x02 len 1
  00000000: 03 |. | |
data #2: type 0x03 len 1
  00000000: 03 |. | |
data #3: type 0x04 len 4
  00000000: 1e 00 f0 00 |... | |
meta #0: type 0x01 len 2
  00000000: 06 00 |. | |
meta #1: type 0x02 len 2
  00000000: ff 03 |. | |
ep 0x81754e0
ep 0x81755d4
Discover complete: err 0
```

**Select preset** The preset command can be used to either print the default preset configuration or set a different one, it is worth noting that it doesn’t change any stream previously configured.

```bash
uart:~$ bap preset <sink, source, broadcast> [preset]
uart:~$ bap preset sink 16_2_1
codec 0x06 cid 0x0000 vid 0x0000 count 4
data #0: type 0x01 len 1
data #1: type 0x02 len 1
data #2: type 0x03 len 4
  00000000: 01 00 00 |... | |
data #3: type 0x04 len 2
  00000000: 28 |( | |
meta #0: type 0x02 len 2
  00000000: 06 |. | |
QoS: interval 10000 framing 0x00 phy 0x02 sdu 40 rtn 2 latency 10 pd 40000
uart:~$ bap preset sink 32_2_1 32_2_1
codec 0x06 cid 0x0000 vid 0x0000 count 4
data #0: type 0x01 len 1
data #1: type 0x02 len 1
data #2: type 0x03 len 4
  00000000: 01 00 00 |... | |
data #3: type 0x04 len 2
  00000000: 50 |P | |
meta #0: type 0x02 len 2
```

(continues on next page)
Configure Codec  The `config` command attempts to configure a stream for the given direction using a preset codec configuration which can either be passed directly or in case it is omitted the default preset is used.

Table 11: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>discover</td>
<td>idle/codec-configured/qos-configured</td>
<td>codec-configured</td>
</tr>
</tbody>
</table>

```sh
uart:~$ bap config <direction: sink, source> <index> [loc <loc_bits>] [preset <preset_name>]
```

ASE Codec Config: conn 0x8173800 ep 0x81754e0 cap 0x816a360
codec 0x06 cid 0x0000 vid 0x0000 count 3
data #0: type 0x01 len 1
00000000: 02 |.
|.
|.
data #1: type 0x02 len 1
00000000: 01 |.
|.
data #2: type 0x04 len 2
00000000: 28 00 |(.|
|.
meta #0: type 0x02 len 2
00000000: 02 00 |..|
|.
ASE Codec Config stream 0x8179e60
Default as: 1
ASE config: preset 16_2_1

Configure Stream QoS  The `stream_qos` Sets a new stream QoS.

```sh
uart:~$ bap stream_qos <interval> [framing] [latency] [pd] [sdu] [phy] [rtn]
uart:~$ bap stream_qos 10
```

Configure QoS  The `qos` command attempts to configure the stream QoS using the preset configuration, each individual QoS parameter can be set with use optional parameters.

Table 12: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>config</td>
<td>qos-configured/codec-configured</td>
<td>qos-configured</td>
</tr>
</tbody>
</table>

```sh
uart:~$ bap qos
```

Enable  The `enable` command attempts to enable the stream previously configured, if the remote peer accepts then the ISO connection procedure is also initiated.

Table 13: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>qos</td>
<td>qos-configured</td>
<td>enabling</td>
</tr>
</tbody>
</table>
The start command is only necessary when acting as a sink as it indicates to the source the stack is ready to start receiving data.

Table 14: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>enable</td>
<td>enabling</td>
<td>streaming</td>
</tr>
</tbody>
</table>

The disable command attempts to disable the stream previously enabled, if the remote peer accepts then the ISO disconnection procedure is also initiated.

Table 15: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>enable</td>
<td>enabling/streaming</td>
<td>disabling</td>
</tr>
</tbody>
</table>

The stop command is only necessary when acting as a sink as it indicates to the source the stack is ready to stop receiving data.

Table 16: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>disable</td>
<td>disabling</td>
<td>qos-configure/idle</td>
</tr>
</tbody>
</table>

The release command releases the current stream and its configuration.

Table 17: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>config</td>
<td>any</td>
<td>releasing/codec-configure/idle</td>
</tr>
</tbody>
</table>

The list command list the available streams.

Table 18: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
</tbody>
</table>

6.1. Bluetooth
Select Unicast  The select_unicast command set a unicast stream as default.

Table 19: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
</tbody>
</table>

To select a broadcast stream:

```
uart:~$ bap select <ase>
uart:~$ bap select 0x01
Default stream: 1
```

Send  The send command sends data over BAP Stream.

Table 20: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>enable</td>
<td>streaming</td>
<td>none</td>
</tr>
</tbody>
</table>

```
uart:~$ bap send [count]
uart:~$ bap send
Audio sending...
```

Bluetooth: Broadcast Audio Profile Broadcast Assistant

This document describes how to run the BAP Broadcast Assistant functionality. Note that in the examples below, some lines of debug have been removed to make this shorter and provide a better overview.

The Broadcast Assistant is responsible for offloading scan for a resource restricted device, such that scanning does not drain the battery. The Broadcast Assistant shall support scanning for periodic advertisements and may optionally support the periodic advertisements synchronization transfer (PAST) protocol.

The Broadcast Assistant will typically be phones or laptops. The Broadcast Assistant scans for periodic advertisements and transfer information to the server.

It is necessary to have BT_DEBUG_BAP_BROADCAST_ASSISTANT enabled for using the Broadcast Assistant interactively.

When the Bluetooth stack has been initialized (`bt init`), and a device has been connected, the Broadcast Assistant can discover BASS on the connected device calling `bap_broadcast_assistant discover`, which will start a discovery for the BASS UUIDs and store the handles, and subscribe to all notifications.
Example usage

**Setup**

```
uart:~$ bt init
uart:~$ bap init
```

**When connected**

**Start scanning for periodic advertisements for a server:**

```
uart:~$ bap_broadcast_assistant discover
BASS discover done with 1 recv states
```

**Note:** The Broadcast Assistant will not actually start scanning for periodic advertisements, as that feature is still, at the time of writing, not implemented.

```
uart:~$ bap_broadcast_assistant scan_start true
BASS scan start successful
Found broadcaster with ID 0x05BD38 and addr 1E:4D:0A:AA:6E:49 (random) and sid 0x00
```

**Adding a source to the receive state with add_src:**

```
uart:~$ bap_broadcast_assistant add_src 11:22:33:44:55:66 public 5 1 1
[0]: BIS sync 0, metadata_len 0
```

**Adding a source to the receive state with add_broadcast_id (recommended):**

```
uart:~$ bap_broadcast_assistant add_broadcast_id 0x05BD38 true
[DEVICE]: 1E:4D:0A:AA:6E:49 (random), AD evt type 5, RSSI -28 Broadcast Audio Source C:0 S:0 D:0 SR E:1 Prim: LE 1M, Secn: LE 2M, Interval: 0x03c0 (1200000 us), SID: 0x0
Found BAP broadcast source with address 1E:4D:0A:AA:6E:49 (random) and ID 0x05BD38
```

(continues on next page)
BASS recv state: src_id 0, addr 1E:4D:0A:AA:6E:49 (random), sid 0, sync_state 0, encrypt_state 0

[0]: BIS sync 0x0000, metadata_len 0
BASS add source successful

BASS recv state: src_id 0, addr 1E:4D:0A:AA:6E:49 (random), sid 0, sync_state 2, encrypt_state 0

[0]: BIS sync 0x0000, metadata_len 0

BASS recv state: src_id 0, addr 1E:4D:0A:AA:6E:49 (random), sid 0, sync_state 2, encrypt_state 0

[0]: BIS sync 0x0001, metadata_len 4
Metadata length 2, type 2, data: 0100

Modifying a receive state:

```
uart:~$ bap_broadcast_assistant mod_src 0 true 0x03c0 0x02
```
BASS modify source successful

BASS recv state: src_id 0, addr 1E:4D:0A:AA:6E:49 (random), sid 0, sync_state 2, encrypt_state 0

[0]: BIS sync 0x0001, metadata_len 4
Metadata length 2, type 2, data: 0100

Bluetooth: Broadcast Audio Profile Scan Delegator

This document describes how to run the Scan Delegator functionality. Note that in the examples below, some lines of debug have been removed to make this shorter and provide a better overview.

The Scan Delegator may optionally support the periodic advertisements synchronization transfer (PAST) protocol.

The Scan Delegator server typically resides on devices that have inputs or outputs.

It is necessary to have `BT_DEBUG_BAP_SCAN_DELEGATOR` enabled for using the Scan Delegator interactively.

The Scan Delegator can currently only set the sync state of a receive state, but does not actually support syncing with periodic advertisements yet.

```
bap_scan_delegator --help
bap_scan_delegator - Bluetooth BAP Scan Delegator shell commands
Subcommands:
   init :Initialize the service and register callbacks
   synced :Set server scan state <src_id> <pa_synced> <bis_syncs> <enc_state>
```

Example Usage

**Setup**

```
uart:~$ bt init
uart:~$ bt advertise on
Advertising started
```

When connected Set sync state for a source:

```
uart:~$ bap_scan_delegator synced 0 1 3 0
```
Bluetooth: Common Audio Profile Shell

This document describes how to run the Common Audio Profile functionality.

**CAP Acceptor**  The Acceptor will typically be a resource-constrained device, such as a headset, earbud or hearing aid. The Acceptor can initialize a Coordinated Set Identification Service instance, if it is in a pair with one or more other CAP Acceptors.

**Using the CAP Acceptor**  When the Bluetooth stack has been initialized (`bt init`), the Acceptor can be registered by calling `cap_acceptor init`, which will register the CAS and CSIS services, as well as register callbacks.

```
cap_acceptor --help
```

```
cap_acceptor - Bluetooth CAP acceptor shell commands
Subcommands:

init :Initialize the service and register callbacks [size <int>]
[rank <int>] [not-lockable] [sirk <data>]
lock :Lock the set
release :Release the set [force]
print_sirk :Print the currently used SIRK
set_sirk_rsp :Set the response used in SIRK requests <accept, accept_enc,
reject, oob>
```

Besides initializing the CAS and the CSIS, there are also commands to lock and release the CSIS instance, as well as printing and modifying access to the SIRK of the CSIS.

**CAP Initiator**  The Initiator will typically be a resource-rich device, such as a phone or PC. The Initiator can discover CAP Acceptors’s CAS and optional CSIS services. The CSIS service can be read to provide information about other CAP Acceptors in the same Coordinated Set. The Initiator can execute stream control procedures on sets of devices, either ad-hoc or Coordinated, and thus provides an easy way to set up multiple streams on multiple devices at once.

**Using the CAP Initiator**  When the Bluetooth stack has been initialized (`bt init`), the Initiator can discover CAS and the optionally included CSIS instance by calling (`cap_initiator discover`).

```
cap_initiator --help
```

```
cap_initiator - Bluetooth CAP initiator shell commands
Subcommands:

discover :Discover CAS
unicast_start :Unicast Start [csip] [sinks <cnt> (default 1)] [sources <cnt>
(default 1)] [conns <cnt> | all] (default 1)]
unicast_list :Unicast list streams
unicast_update :Unicast Update <all | stream [stream...]]>
unicast_stop :Unicast stop streams <all | stream [stream...]]>
unicast_cancel :Unicast cancel current procedure
```

Before being able to perform any stream operation, the device must also perform the `bap discover` operation to discover the ASEs and PAC records. The `bap init` command also needs to be called.

**When connected**  Discovering CAS and CSIS on a device:

```
uart:~$ cap_initiator discover
discovery completed with CSIS
```

Discovering ASEs and PAC records on a device:
Both of the above commands should be done for each device that you want to use in the set. To use multiple devices, simply connect to more and then use `bt select` the device to execute the commands on.

Once all devices have been connected and the respective discovery commands have been called, the `cap_initiator unicast_start` command can be used to put one or more streams into the streaming state.

To stop all the streams that has been started, the `cap_initiator unicast_stop` command can be used.

**CAP Commander** The Commander will typically be a either co-located with a CAP Initiator or be on a separate resource-rich mobile device, such as a phone or smartwatch. The Commander can discover CAP Acceptors's CAS and optional CSIS services. The CSIS service can be read to provide information about other CAP Acceptors in the same Coordinated Set. The Commander can provide information about broadcast sources to CAP Acceptors or coordinate capture and rendering information such as mute or volume states.
Using the CAP Commander  When the Bluetooth stack has been initialized (bt init), the Commander can discover CAS and the optionally included CSIS instance by calling (cap_commander discover).

<table>
<thead>
<tr>
<th>Subcommands:</th>
</tr>
</thead>
<tbody>
<tr>
<td>discover</td>
</tr>
<tr>
<td>change_volume</td>
</tr>
<tr>
<td>change_volume_offset</td>
</tr>
</tbody>
</table>

Before being able to perform any stream operation, the device must also perform the bap discover operation to discover the ASEs and PAC records. The bap init command also needs to be called.

When connected  Discovering CAS and CSIS on a device:

```
uart:~$ cap_commander discover
discovery completed with CSIS
```

Setting the volume on all connected devices:

```
uart:~$ vcp_vol_ctlr discover
VCP discover done with 1 VOCS and 1 AICS
uart:~$ cap_commander change_volume 15
uart:~$ cap_commander change_volume 15
Setting volume to 15 on 2 connections
VCP volume 15, mute 0
VCP vo1_set done
VCP volume 15, mute 0
VCP flags 0x01
VCP vo1_set done
Volume change completed
```

Setting the volume offset on one or more connected devices. The offsets are set by connection index, so connection index 0 gets the first offset, and index 1 gets the second offset, etc.:

```
uart:~$ bt connect <device A>
Connected: <device A>
uart:~$ cap_commander discover
discovery completed with CSIS
uart:~$ vcp_vol_ctlr discover
VCP discover done with 1 VOCS and 1 AICS
uart:~$
uart:~$ bt connect <device B>
Connected: <device B>
uart:~$ cap_commander discover
discovery completed with CSIS
uart:~$ vcp_vol_ctlr discover
VCP discover done with 1 VOCS and 1 AICS
uart:~$
uart:~$ cap_commander change_volume_offset 10
Setting volume offset on 1 connections
VOCS inst 0x200140a4 offset 10
Offset set for inst 0x200140a4
Volume offset change completed
uart:~$
uart:~$ cap_commander change_volume_offset 10 15
Setting volume offset on 2 connections
Offset set for inst 0x200140a4
```

(continues on next page)
Bluetooth: Call Control Profile

This document describes how to run the call control functionality, both as a client and as a (telephone bearer service (TBS)) server. Note that in the examples below, some lines of debug have been removed to make this shorter and provide a better overview.

**Telephone Bearer Service Client** The telephone bearer service client will typically exist on a resource restricted device, such as headphones, but may also exist on e.g. phones or laptops. The call control client will also thus typically be the advertiser. The client can control the states of calls on a server using the call control point.

It is necessary to have `BT_DEBUG_TBS_CLIENT` enabled for using the client interactively.

**Using the telephone bearer service client** When the Bluetooth stack has been initialized (`bt init`), and a device has been connected, the telephone bearer service client can discover TBS on the connected device calling `tbs_client discover`, which will start a discovery for the TBS UUIDs and store the handles, and optionally subscribe to all notifications (default is to subscribe to all).

Since a server may have multiple TBS instances, most of the `tbs_client` commands will take an index (starting from 0) as input. Joining calls require at least 2 call IDs, and all call indexes shall be on the same TBS instance.

A server may also have a GTBS instance, which is an abstraction layer for all the telephone bearers on the server. If the server has both GTBS and TBS, the client may subscribe and use either when sending requests if `BT_TBS_CLIENT_GTBS` is enabled.
read_current_calls :Read the current calls [{instance_index, gtbs}]
read_ccid :Read the CCID [{instance_index, gtbs}]
read_status_flags :Read the in feature and status value [{instance_index, gtbs}]
read_uri :Read the incoming call target URI [{instance_index, gtbs}]
read_call_state :Read the call state [{instance_index, gtbs}]
read_remote_uri :Read the incoming remote URI [{instance_index, gtbs}]
read_friendly_name :Read the friendly name of an incoming call [{instance_index, gtbs}]
read_optional_opcodes :Read the optional opcodes [{instance_index, gtbs}]

In the following examples, notifications from GTBS is ignored, unless otherwise specified.

Example usage

Setup

uart:~$ bt init
uart:~$ bt advertise on
Advertising started

When connected  Placing a call:

uart:~$ tbs_client discover
<dbg> bt_tbs_client.primary_discover_func: Discover complete, found 1 instances (GTBS found)
<dbg> bt_tbs_client.discover_func: Setup complete for 1 / 1 TBS
<dbg> bt_tbs_client.discover_func: Setup complete GTBS
uart:~$ tbs_client originate 0 tel:123
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the dialing state with URI tel:123
<dbg> bt_tbs_client.call_cp_notify_handler: Status: success for the originate opcode for call 0x00
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the alerting state with URI tel:123
<call answered by peer device, and status notified by TBS server>
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the active state with URI tel:123

Placing a call on GTBS:

uart:~$ tbs_client originate 0 tel:123
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the dialing state with URI tel:123
<dbg> bt_tbs_client.call_cp_notify_handler: Status: success for the originate opcode for call 0x00
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the alerting state with URI tel:123
<call answered by peer device, and status notified by TBS server>
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the active state with URI tel:123

(continues on next page)
It is necessary to set an outgoing caller ID before placing a call.

Accepting incoming call from peer device:

Terminating call:

**Telephone Bearer Service (TBS)** The telephone bearer service is a service that typically resides on devices that can make calls, including calls from apps such as Skype, e.g. (smart)phones and PCs.

It is necessary to have `BT_DEBUG_TBS` enabled for using the TBS server interactively.

**Using the telephone bearer service** TBS can be controlled locally, or by a remote device (when in a call). For example a remote device may initiate a call to the device with the TBS server, or the TBS server may initiate a call to remote device, without a TBS_CLIENT client. The TBS implementation is capable of fully controlling any call.
### Example Usage

#### Setup

```
uart:~$ bt init
```

#### When connected  Answering a call for a peer device originated by a client:

```
<dbg> bt_tbs.write_call_cp: Index 0: Processing the originate opcode
<dbg> bt_tbs.originate_call: New call with call index 1
<dbg> bt_tbs.write_call_cp: Index 0: Processed the originate opcode with status success for...
uart:~$ tbs remote_answer 1
TBS succeeded for call_id: 1
```

#### Incoming call from a peer device, accepted by client:

```
uart:~$ tbs incoming 0 tel:123 tel:456 Peter
TBS succeeded for call_id: 4
<dbg> bt_tbs.bt_tbs_remote_incoming: New call with call index 4
<dbg> bt_tbs.write_call_cp: Index 0: Processed the accept opcode with status success for...
```

### Bluetooth: Coordinated Set Identification Profile

This document describes how to run the coordinated set identification functionality, both as a client and as a server. Note that in the examples below, some lines of debug have been removed to make this shorter and provide a better overview.

#### Set Coordinator (Client)  The client will typically be a resource-rich device, such as a smartphone or a laptop. The client is able to lock and release members of a coordinated set. While the coordinated set is locked, no other clients may lock the set.

To lock a set, the client must connect to each of the set members it wants to lock. This implementation will always try to connect to all the members of the set, and at the same time. Thus if the set size is 3, then BT_MAX_CONN shall be at least 3.

If the locks on set members shall persists through disconnects, it is necessary to bond with the set members. If you need to bond with multiple set members, make sure that BT_MAX_PAIRED is correctly configured.

#### Using the Set Coordinator  When the Bluetooth stack has been initialized (bt init), and a set member device has been connected, the call control client can be initialized by calling csip_set_coordinator init, which will start a discovery for the TBS uuids and store the handles, and optionally subscribe to all notifications (default is to subscribe to all).
Once the client has connected and discovered the handles, then it can read the set information, which is needed to identify other set members. The client can then scan for and connect to the remaining set members, and once all the members have been connected to, it can lock and release the set.

It is necessary to enable `BT_DEBUG_CSIP_SET_COORDINATOR` to properly use the set coordinator.

```
csip_set_coordinator --help
```

### Subcommands:

- `init`: Initialize CSIP_SET_COORDINATOR
- `discover`: Run discover for CSIS on peer device [member_index]
- `discover_members`: Scan for set members <set_pointer>
- `lock_set`: Lock set
- `release_set`: Release set
- `lock`: Lock specific member [member_index]
- `release`: Release specific member [member_index]
- `lock_get`: Get the lock value of the specific member and instance [member_index [inst_idx]]

### Example usage

#### Setup

```
uart:~$ init
```
```
```

#### When connected  Discovering sets on a device:

```
uart:~$ csip_set_coordinator init
```
```
<dbg> bt_csip_set_coordinator.primary_discover_func: [ATTRIBUTE] handle 0x0048
<dbg> bt_csip_set_coordinator.primary_discover_func: Discover complete, found 1 instances
<dbg> bt_csip_set_coordinator.discover_func: Setup complete for 1 / 1
Found 1 sets on device
```
```
uart:~$ csip_set_coordinator discover_sets
```
```
<dbg> bt_csip_set_coordinator.Set SIRK
36 04 9a dc 66 3a a1 01 73 3e 01 |6...f:..
1d 9a 2f 41 01 73 3e 01 |..A.s>
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_set_size_cb: 2
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_set_lock_cb: 1
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_rank_cb: 1
Set size 2 (pointer: 0x566fdfe8)
```

Discover set members, based on the set pointer above:

```
uart:~$ csip_set_coordinator discover_members 0x566fdfe8
```
```
<dbg> bt_csip_set_coordinator.csip_found: Found CSIS advertiser with address...
<dbg> bt_csip_set_coordinator.is_set_member: hash: 0x33ccb1, prand 0x5bfe6a
<dbg> bt_csip_set_coordinator.is_discovered: 34:02:86:03:86:c0 (public)
<dbg> bt_csip_set_coordinator.is_discovered: 34:13:e8:b3:7f:9e (public)
<dbg> bt_csip_set_coordinator.csip_found: Found member (2 / 2)
Discovered 2/2 set members
```

Lock set members:

```
uart:~$ csip_set_coordinator lock_set
```
```
<dbg> bt_csip_set_coordinator.bt_csip_set_coordinator_lock_set: Connecting to...
```
(continues on next page)
Release set members:

```
>>> csip_set_coordinator release_set
<dbg> bt_csip_set_coordinator.csip_set_coordinator_release_highest_rank: Releasing member
<dbg> bt_csip_set_coordinator.notify_func: Instance 0 lock was released
<dbg> bt_csip_set_coordinator.csip_set_coordinator_release_highest_rank: Releasing member
<dbg> bt_csip_set_coordinator.notify_func: Instance 0 lock was released
Set released
```

**Coordinated Set Member (Server)** The server on devices that are part of a set, consisting of at least two devices, e.g. a pair of earbuds.

**Using the Set Member**

```
csip_set_member --help
```

*register*: Initialize the service and register callbacks [size <int>]

*update_psri*: Update the advertised PSRI

*lock*: Lock the set

*release*: Release the set [force]

*print_sirk*: Print the currently used SIRK

*set_sirk_rsp*: Set the response used in SIRK requests <accept, accept_enc, reject, oob>

**Example Usage**

**Setup**

```
uart:~$ bt init
uart:~$ csip_set_member register
```
Bluetooth: Gaming Audio Profile Shell

This document describes how to run the Gaming Audio Profile shell functionality. Unlike most other low-layer profiles, GMAP is a profile that exists and has a service (GMAS) on all devices. Thus both the initiator and acceptor (or central and peripheral) should do a discovery of the remote device’s GMAS to see what GMAP roles and features they support.

Using the GMAP Shell  When the Bluetooth stack has been initialized (bt init), the GMAS can be registered by by calling gmap init. It is also strongly suggested to enable BAP via bap init.

```
gmap --help
```

gmap - Bluetooth GMAP shell commands

Subcommands:
  init    :[none]
  set_role :[ugt | ugg | bgr | bgs]
  discover :[none]
  ac_1    :<sink preset>
  ac_2    :<source preset>
  ac_3    :<sink preset> <source preset>
  ac_4    :<sink preset>
  ac_5    :<sink preset> <source preset>
  ac_6_i  :<sink preset>
  ac_6_ii :<sink preset>
  ac_7_ii :<sink preset> <source preset>
  ac_8_i  :<sink preset> <source preset>
  ac_8_ii :<sink preset> <source preset>
  ac_11_i :<sink preset> <source preset>
  ac_11_ii :<sink preset> <source preset>
  ac_12   :<preset>
  ac_13   :<preset>
  ac_14   :<preset>

The set_role command can be used to change the role at runtime, assuming that the device supports the role (the GMAP roles depend on some BAP configurations).

Example Central with GMAP UGT role  Connect and establish Gaming Audio streams using Audio Configuration (AC) 3 (some logging has been omitted for clarity):

```
uart:~$ bt init
uart:~$ bap init
uart:~$ gmap init
uart:~$ bt connect <address>
uart:~$ gatt exchange-mtu
uart:~$ bap discover
Discover complete: err 0
uart:~$ cap_initiator discover
discovery completed with CSIS
uart:~$ gmap discover
```

gmap discovered for conn 0x2001c7d8:
role 0xf
  ugg_feat 0x07
  ugt_feat 0x0f
  bgs_feat 0x81
  bgr_feat 0x03
uart:~$ gmap ac_3 32_2_gr 32_2_gs
Starting 2 streams for AC_3
stream 0x20020060 config operation rsp_code 0 reason 0
stream 0x200204d0 config operation rsp_code 0 reason 0
stream 0x200204d0 qos operation rsp_code 0 reason 0
```

(continues on next page)
stream 0x20020060 qos operation rsp_code 0 reason 0
Stream 0x20020060 enabled
stream 0x200204d0 enable operation rsp_code 0 reason 0
Stream 0x200204d0 enabled
stream 0x20020060 enable operation rsp_code 0 reason 0
Stream 0x20020060 started
stream 0x200204d0 start operation rsp_code 0 reason 0
Stream 0x200204d0 started
Unicast start completed
uart:~$ bap start_sine
Started transmitting on default_stream 0x20020060
[0]: stream 0x20020060 : TX LC3: 80 (seq_num 24800)

Bluetooth: Isochronous Channels

Commands

iso --help
iso - Bluetooth ISO shell commands
Subcommands:
  cig_create :[dir=tx,rx,txrx] [interval] [packing] [framing] [latency] [sdu]
               [phy] [rtn]
  cig_term :Terminate the CIG
  connect :Connect ISO Channel
  listen :<dir=tx,rx,txrx> [security level]
  send :Send to ISO Channel [count]
  disconnect :Disconnect ISO Channel
  create-big :Create a BIG as a broadcaster [enc <broadcast code>]
  broadcast :Broadcast on ISO channels
  sync-big :Synchronize to a BIG as a receiver <BIS bitfield> [mse] [timeout]
             [enc <broadcast code>]
  term-big :Terminate a BIG

1. [Central] Create CIG:

Requires to be connected:

uart:~$ iso cig_create
CIG created

2. [Peripheral] Listen to ISO connections

uart:~$ iso listen txrx

3. [Central] Connect ISO channel:

uart:~$ iso connect
ISO Connect pending...
ISO Channel 0x20000f88 connected

4. Send data:

uart:~$ iso send
send: 40 bytes of data
ISO sending...

5. Disconnect ISO channel:

uart:~$ iso disconnect
ISO Disconnect pending...
ISO Channel 0x20000f88 disconnected with reason 0x16

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Media control for Generic Audio Content Control

This document describes how to run the media control functionality, using the shell, both as a client and as a server.

The media control server consists of two parts. There is a media player (mpl) that contains the logic to handle media, and there is a media control service (mcs) that serves as a GATT-based interface to the player. The media control client consists of one part, the GATT-based client (mcc).

The media control server may include an object transfer service (ots) and the media control client may include an object transfer client (otc). When these are included, a richer set of functionality is available.

The media control server and client both implement the Generic Media Control Service (only), and do not use any underlying Media Control Services.

Note that in the examples below, in many cases the debug output has been removed and long outputs may have been shortened to make the examples shorter and clearer.

Also note that this documentation does not list all shell commands, it just shows examples of some of them. The set of commands is exploratory from the mcc shell and the mpl shell, by typing mcc or mpl and pressing TAB. A help text for each command can be found by doing mcc <command> help or mpl <command> help.

Overview

A media player has a name and an icon that allows identification of the player for the user.

The content of the media player is structured into tracks and groups. A media player has a number of groups. A group contains tracks and other groups. (In this implementation, a group only contains tracks, not other groups.) Tracks can be divided into segments.

An active player will have a current track. This is the track that is playing now (if the player is playing). The current track has a title, a duration (given in hundredths of a second) and a position - the current position of the player within the track.

There is also a current group (the group of the current track), a parent group (the parent group of the current group) and a next track.

The media player is in a state, which will be one of playing, paused, seeking or inactive. When playing, playback happens at a given playback speed, and the tracks are played according to the playing order, which is one of the playing orders supported. Track changes are signalled as notifications of the track changed characteristic. When seeking (fast forward or fast rewind), the track position is moved according to the seeking speed.

The opcodes supported tells which operations are supported by the player by writing to the media control point. There is also a search control point that allows to search for groups and tracks according to various criteria, with the result returned in the search results.

Finally, the content control ID is used to associate the media player with an audio stream.

Media Control Client (MCP) The media control client is used to control, and to get information from, a media control server. Control is done by writing to one of the two control points, or by writing to other writable characteristics. Getting information is done by reading characteristics, or by configuring the server to send notifications.

Using the media control client Before use, the media control client must be initialized by the command mcc init.

To achieve a connection to the peer, the bt commands must be used - bt init followed by bt advertise on (or bt connect if the server is advertising).
When the media control client is connected to a media control server, the client can discover the server's Generic Media Control Service, by giving the command `mcc discover_mcs`. This will store the handles of the service, and (optionally, but default) subscribe to all notifications.

After discovery, the media control client can read and write characteristics, including the media control point and the search control point.

**Example usage**

**Setup**

```
uart:~$ bt init
Bluetooth initialized

uart:~$ mcc init
MCC init complete

uart:~$ bt advertise on
Advertising started
```

**When connected  Service discovery (GMCS and included OTS):**

```
uart:~$ mcc discover_mcs
<dbg> bt_mcc.bt_mcc_discover_mcs: start discovery of MCS primary service
<dbg> bt_mcc.discover_primary_func: [ATTRIBUTE] handle 0x00ae
<dbg> bt_mcc.discover_primary_func: Primary discovery complete
<dbg> bt_mcc.discover_primary_func: UUID: 2800
<dbg> bt_mcc.discover_primary_func: UUID: 8fd7
<dbg> bt_mcc.discover_primary_func: Start discovery of MCS characteristics
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00b0
<dbg> bt_mcc.discover_mcs_char_func: Player name, UUID: 8fa0
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00b2
<dbg> bt_mcc.discover_mcs_char_func: Icon Object, UUID: 8fa1
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00b4
<dbg> bt_mcc.discover_mcs_char_func: Icon URI, UUID: 8fa2
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00b6
<dbg> bt_mcc.discover_mcs_char_func: Track Changed, UUID: 8fa3
<dbg> bt_mcc.discover_mcs_char_func: Subscribing - handle: 0x00b6 
[...]
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00ea
<dbg> bt_mcc.discover_mcs_char_func: Content Control ID, UUID: 8fb5
<dbg> bt_mcc.discover_mcs_char_func: Setup complete for MCS
<dbg> bt_mcc.discover_mcs_char_func: Start discovery of included services
<dbg> bt_mcc.discover_include_func: [ATTRIBUTE] handle 0x00af
<dbg> bt_mcc.discover_include_func: Include UUID 1825
<dbg> bt_mcc.discover_include_func: Discover include complete for MCS: OTS
<dbg> bt_mcc.discover_include_func: Start discovery of OTS characteristics
<dbg> bt_mcc.discover_otc_char_func: [ATTRIBUTE] handle 0x009c
<dbg> bt_mcc.discover_otc_char_func: OTS Features 
[...]
<dbg> bt_mcc.discover_otc_char_func: [ATTRIBUTE] handle 0x00ac
<dbg> bt_mcc.discover_otc_char_func: Object Size
Discovery complete
<dbg> bt.otc.bt.otc_register: 0
<dbg> bt.otc.bt.otc_register: L2CAP psm 0x 25 sec_level 1 registered
<dbg> bt.mcc.discover_otc_char_func: Setup complete for OTS 1 / 1
```

Reading characteristics - the player name and the track duration as examples:
uart:~$ mcc read_player_name
Player name: My media player
4d 79 20 6d 65 64 69 61 20 70 6c 61 79 65 72 |My media player

uart:~$ mcc read_track_duration
Track duration: 6300

Note that the value of some characteristics may be truncated due to being too long to fit in the ATT packet. Increasing the ATT MTU may help:

uart:~$ mcc read_track_title
Track title: Interlude #1 (Song for
uart:~$ gatt exchange-mtu
Exchange pending
Exchange successful
uart:~$ mcc read_track_title
Track title: Interlude #1 (Song for Alison)

Writing characteristics - track position as an example:

The track position is where the player “is” in the current track. Read the track position, change it by writing to it, confirm by reading it again.

uart:~$ mcc read_track_position
Track Position: 0

uart:~$ mcc set_track_position 500
Track Position: 500

uart:~$ mcc read_track_position
Track Position: 500

Controlling the player via the control point:

Writing to the control point allows the client to request the server to do operations like play, pause, fast forward, change track, change group and so on. Some operations (e.g. goto track) take an argument. Currently, raw opcode values are used as input to the control point shell command. These opcode values can be found in the mpl.h header file.

Send the play command (opcode “1”), the command to go to track (opcode “52”) number three, and the pause command (opcode “2”):

uart:~$ mcc set_cp 1
Media State: 1
Operation: 1, result: 1
Operation: 1, param: 0

uart:~$ mcc set_cp 52 3
Track changed
Track title: Interlude #3 (Levanto Seventy)
Track duration: 7800
Track Position: 0
Current Track Object ID: 0x000000000104
Next Track Object ID: 0x000000000105
Operation: 52, result: 1
Operation: 52, param: 3

uart:~$ mcc set_cp 2
Media State: 2
Operation: 2, result: 1
Operation: 2, param: 0
Using the included object transfer client  When object transfer is supported by both the client and the server, a larger set of characteristics is available. These include object IDs for the various track and group objects. These IDs can be used to select and download the corresponding objects from the server's object transfer service.

Read the object ID of the current group object:

```
uart:$ mcc read_current_group_obj_id
Current Group Object ID: 0x000000000107
```

Select the object with that ID:

```
uart:$ mcc ots_select 0x107
Selecting object succeeded
```

Read the object's metadata:

```
uart:$ mcc ots_read_metadata
Reading object metadata succeeded
<inf> bt_mcc: Object's meta data:
<inf> bt_mcc: Current size :35
<inf> bt_ots: Displaying 1 metadata records ---
<inf> bt_ots: Object ID: 0x000000000107
<inf> bt_ots: Object name: Joe Pass - Guitar Inte
<inf> bt_ots: Object Current Size: 35
<inf> bt_ots: Object Allocate Size: 35
<inf> bt_ots: Type: Group Obj Type
<inf> bt_ots: Properties:0x4
<inf> bt_ots: - read permitted
```

Read the object itself:

The object received is a group object. It consists of a series of records consisting of a type (track or group) and an object ID.

```
uart:$ mcc ots_read_current_group_object
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x000000000102
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x000000000103
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x000000000104
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x000000000105
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x000000000106
```

Search  The search control point takes as its input a sequence of search control items, each consisting of length, type (e.g. track name or artist name) and parameter (the track name or artist name to search for). If the result is successful, the search results are stored in an object in the object transfer service. The ID of the search results ID object can be read from the search results object ID characteristic. The search result object can then be downloaded as for the current group object above. (Note that the search results object ID is empty until a search has been done.)

This implementation has a working implementation of the search functionality interface and the server-side search control point parameter parsing. But the actual searching is faked, the same results are returned no matter what is searched for.

There are two commands for search, one (mcc set_scp_raw) allows to input the search control point parameter (the sequence of search control items) as a string. The other (mcc set_scp_ioptest) does preset IOP test searches and takes the round number of the IOP search control point test as a parameter.

Before the search, the search results object ID is empty

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Run the search corresponding to the fourth round of the IOP test:

The search control point parameter generated by this command and parameter has one search control item. The length field (first octet) is 16 (0x10). (The length of the length field itself is not included.) The type field (second octet) is 0x04 (search for a group name). The parameter (the group name to search for) is “TSPX_Group_Name”.

After the successful search, the search results object ID has a value:

Media Control Service (MCS)  The media control service (mcs) and the associated media player (mpl) typically reside on devices that can provide access to, and serve, media content, like PCs and smartphones.

As mentioned above, the media player (mpl) has the player logic, while the media control service (mcs) has the GATT-based interface. This separation is done so that the media player can also be used without the GATT-based interface.

Using the media control service and the media player  The media control service and the media player are in general controlled remotely, from the media control client.

Before use, the media control client must be initialized by the command mpl init.

As for the client, the bt commands are used for connecting - bt init followed by bt connect <address> <address type> (or bt advertise on if the server is advertising).

Example Usage

Setup

When connected  Control is done from the client.

The server will give debug output related to the various operations performed by the client.
Example: Debug output by the server when the client gives the “next track” command:

```
[00:13:29.932,373] <dbg> bt_mcs.control_point_write: Opcode: 49
[00:13:29.932,403] <dbg> bt_mpl.paused_state_operation_handler: Operation opcode: 49
[00:13:29.932,495] <dbg> bt_mpl.do_next_track: Track ID before: 0x000000000104
[00:13:29.932,586] <dbg> bt_mpl.do_next_track: Track ID after: 0x000000000105
[00:13:29.932,617] <dbg> bt_mpl.paused_state_operation_handler: Operation opcode: 49
[00:13:29.932,708] <dbg> bt_mpl.do_next_track: Track ID after: 0x000000000105
[00:13:29.932,800] <dbg> bt_mpl.mpl_track_changed_cb: Notifying track change
[00:13:29.932,861] <dbg> bt_mpl.mpl_track_position_cb: Notifying track position: 0
[00:13:29.933,044] <dbg> bt_mpl.mpl_current_track_id_cb: Notifying current track ID:
[00:13:29.933,258] <dbg> bt_mpl.mpl_next_track_id_cb: Notifying next track ID:
```

Some server commands are available. These commands force notifications of the various characteristics, for testing that the client receives notifications. The values sent in the notifications caused by these testing commands are independent of the media player, so they do not correspond the actual values of the characteristics nor to the actual state of the media player.

Example: Force (fake value) notification of the track duration:

```
uart:~$ mpl duration_changed_cb
[00:15:17.491,058] <dbg> bt_mcs.mpl_track_duration_cb: Notifying track duration: 12000
```

### Bluetooth: Telephone and Media Audio Profile Shell

This document describes how to run the Telephone and Media Audio Profile functionality. Unlike most other low-layer profiles, TMAP is a profile that exists and has a service (TMAS) on all devices. Thus both the initiator and acceptor (or central and peripheral) should do a discovery of the remote device’s TMAS to see what TMAP roles they support.

**Using the TMAP Shell**  When the Bluetooth stack has been initialized (`bt init`), the TMAS can be registered by calling `tmap init`.

```
tmap --help
mmap - Bluetooth TMAP shell commands
Subcommands:
  init :Initialize and register the TMAS
  discover :Discover TMAS on remote device
```

### Bluetooth: Public Broadcast Profile Shell

This document describes how to run the Public Broadcast Profile functionality. PBP does not have an associated service. Its purpose is to enable a faster, more efficient discovery of Broadcast Sources that are transmitting audio with commonly used codec configurations.

**Using the PBP Shell**  When the Bluetooth stack has been initialized (`bt init`), the Public Broadcast Profile is ready to run. To set the Public Broadcast Announcement features call `pbp set_features`.

6.1. Bluetooth
pbp --help
pbp - Bluetooth PBP shell commands
Subcommands:
  set_features : Set the Public Broadcast Announcement features

6.1.11 Bluetooth Shell

The Bluetooth Shell is an application based on the Shell module. It offer a collection of commands made to easily interact with the Bluetooth stack.

Bluetooth Shell Setup and Usage

First you need to build and flash your board with the Bluetooth shell. For how to do that, see the Getting Started Guide. The Bluetooth shell itself is located in tests/bluetooth/shell/.

When it’s done, connect to the CLI using your favorite serial terminal application. You should see the following prompt:

uart:~$

For more details on general usage of the shell, see Shell.

The first step is enabling Bluetooth. To do so, use the bt init command. The following message is printed to confirm Bluetooth has been initialized.

uart:~$ bt init
Bluetooth initialized
Settings Loaded
[00:02:26.771,148] <inf> fs_nvs: nvs_mount: 8 Sectors of 4096 bytes
[00:02:26.771,148] <inf> fs_nvs: nvs_mount: alloc wra: 0, fe8
[00:02:26.771,179] <inf> fs_nvs: nvs_mount: data wra: 0, 0
[00:02:26.777,984] <inf> bt_hci_core: hci_vs_init: HW Platform: Nordic Semiconductor → (0x0002)
[00:02:26.778,015] <inf> bt_hci_core: hci_vs_init: HW Variant: nRF52x (0x0002)
[00:02:26.778,045] <inf> bt_hci_core: hci_vs_init: Firmware: Standard Bluetooth controller → (0x00) Version 3.2 Build 99
[00:02:26.778,656] <inf> bt_hci_core: bt_init: No ID address. App must call settings_load()
[00:02:26.794,769] <inf> bt_hci_core: bt_dev_show_info: HCI: version 5.3 (0x0c) revision → 0x0000, manufacturer 0x05f1
[00:02:26.794,799] <inf> bt_hci_core: bt_dev_show_info: LMP: version 5.3 (0x0c) subver → 0xffff

Identities

Identities are a Zephyr host concept, allowing a single physical device to behave like multiple logical Bluetooth devices.

The shell allows the creation of multiple identities, to a maximum that is set by the Kconfig symbol CONFIG_BT_ID_MAX. To create a new identity, use bt id-create command. You can then use it by selecting it with its ID bt id-select <id>. Finally, you can list all the available identities with id-show.
Scan for devices

Start scanning by using the `bt scan` command. Depending on the environment you’re in, you may see a lot of lines printed on the shell. To stop the scan, run `bt scan off`, the scrolling should stop.

Here is an example of what you can expect:

```
uart:~$ bt scan on
Bluetooth active scan enabled
[DEVICE]: CB:01:1A:2D:6E:AE (random), AD evt type 0, RSSI -78 C:1 S:1 D:0 SR:0 E:0 Prim:
  → LE 1M, Secn: No packets, Interval: 0x0000 (0 us), SID: 0xff
[DEVICE]: 28:C2:EE:59:85:5B (random), AD evt type 3, RSSI -62 C:0 S:0 D:0 SR:0 E:0 Prim:
  → LE 1M, Secn: No packets, Interval: 0x0000 (0 us), SID: 0xff
[DEVICE]: E3:72:76:87:2F:E8 (random), AD evt type 3, RSSI -74 C:0 S:0 D:0 SR:0 E:0 Prim:
  → LE 1M, Secn: No packets, Interval: 0x0000 (0 us), SID: 0xff
[DEVICE]: 1E:19:25:8A:CB:84 (random), AD evt type 3, RSSI -67 C:0 S:0 D:0 SR:0 E:0 Prim:
  → LE 1M, Secn: No packets, Interval: 0x0000 (0 us), SID: 0xff
[DEVICE]: 26:42:F3:D5:A0:86 (random), AD evt type 3, RSSI -73 C:0 S:0 D:0 SR:0 E:0 Prim:
  → LE 1M, Secn: No packets, Interval: 0x0000 (0 us), SID: 0xff
[DEVICE]: 0C:61:D1:B9:5D:9E (random), AD evt type 3, RSSI -87 C:0 S:0 D:0 SR:0 E:0 Prim:
  → LE 1M, Secn: No packets, Interval: 0x0000 (0 us), SID: 0xff
uart:~$ bt scan off
Scan successfully stopped
```

As you can see, this can lead to a high number of results. To reduce that number and easily find a specific device, you can enable scan filters. There are four types of filters: by name, by RSSI, by address and by periodic advertising interval. To apply a filter, use the `bt scan-set-filter` command followed by the type of filters. You can add multiple filters by using the commands again.

For example, if you want to look only for devices with the name `test shell`:

```
uart:~$ bt scan-filter-set name "test shell"
```

Or if you want to look for devices at a very close range:

```
uart:~$ bt scan-filter-set rssi -40
RSSI cutoff set at -40 dB
```

Finally, if you want to remove all filters:

```
uart:~$ bt scan-filter-clear all
```

You can use the command `bt scan on` to create an active scanner, meaning that the scanner will ask the advertisers for more information by sending a scan request packet. Alternatively, you can create a passive scanner by using the `bt scan passive` command, so the scanner will not ask the advertiser for more information.

Connecting to a device

To connect to a device, you need to know its address and type of address and use the `bt connect` command with the address and the type as arguments.

Here is an example:
You can list the active connections of the shell using the `bt connections` command. The shell maximum number of connections is defined by `CONFIG_BT_MAX_CONN`. You can disconnect from a connection with the `bt disconnect <address: XX:XX:XX:XX:XX:XX> <type: (public|random)>` command.

**Note:** If you were scanning just before, you can connect to the last scanned device by simply running the `bt connect` command.

Alternatively, you can use the `bt connect-name <name>` command to automatically enable scanning with a name filter and connect to the first match.

### Advertising

Begin advertising by using the `bt advertise on` command. This will use the default parameters and advertise a resolvable private address with the name of the device. You can choose to use the identity address instead by running the `bt advertise on identity` command. To stop advertising use the `bt advertise off` command.

To enable more advanced features of advertising, you should create an advertiser using the `bt adv-create` command. Parameters for the advertiser can be passed either at the creation of it or by using the `bt adv-param` command. To begin advertising with this newly created advertiser, use the `bt adv-start` command, and then the `bt adv-stop` command to stop advertising.

When using the custom advertisers, you can choose if it will be connectable or scannable. This leads to four options: `conn-scan`, `conn-nscan`, `nconn-scan` and `nconn-nscan`. Those parameters are mandatory when creating an advertiser or updating its parameters.

For example, if you want to create a connectable and scannable advertiser and start it:

```
uart:~$ bt adv-create conn-scan
Created adv id: 0, adv: 0x200022f0
uart:~$ bt adv-start
Advertiser[0] 0x200022f0 set started
```

You may notice that with this, the custom advertiser does not advertise the device name; you need to enable it. Continuing from the previous example:

```
uart:~$ bt adv-stop
Advertiser set stopped
uart:~$ bt adv-param conn-scan name
uart:~$ bt adv-start
Advertiser[0] 0x200022f0 set started
```

You should now see the name of the device in the advertising data. You can also set the advertising data manually by using the `bt adv-data` command. The following example shows how to set the advertiser name with it:

```
uart:~$ bt adv-create conn-scan
Created adv id: 0, adv: 0x20002348
uart:~$ bt adv-data 1009426C7565746F6F74682D5368656C6C
```

(continues on next page)
The data must be formatted according to the Bluetooth Core Specification (see version 5.3, vol. 3, part C, 11). In this example, the first octet is the size of the data (the data and one octet for the data type), the second one is the type of data, 0x09 is the Complete Local Name and the remaining data are the name in ASCII. So, on the other device you should see the name Bluetooth-Shell.

When advertising, if others devices use an active scanner, you may receive scan request packets. To visualize those packets, you can add scan-reports to the parameters of your advertiser.

**Directed Advertising**  It is possible to use directed advertising on the shell if you want to reconnect to a device. The following example demonstrates how to create a directed advertiser with the address specified right after the parameter directed. The low parameter indicates that we want to use the low duty cycle mode, and the dir-rpa parameter is required if the remote device is privacy-enabled and supports address resolution of the target address in directed advertisement.

```
uart:~$ bt adv-create conn-scan directed D7:54:03:CE:F3:B4 random low dir-rpa
Created adv id: 0, adv: 0x20002348
```

After that, you can start the advertiser and then the target device will be able to reconnect.

**Extended Advertising**  Let's now have a look at some extended advertising features. To enable extended advertising, use the ext-adv parameter.

```
uart:~$ bt adv-create conn-nscan ext-adv name-ad
Created adv id: 0, adv: 0x200022f0
```

This will create an extended advertiser, that is connectable and non-scannable.

**Filter Accept List**

It's possible to create a list of allowed addresses that can be used to connect to those addresses automatically. Here is how to do it:

```
uart:~$ bt fal-add 66:C8:B0:2A:05:73 random
uart:~$ bt fal-connect on
```

The shell will then connect to the first available device. In the example, if both devices are advertising at the same time, we will connect to the first address added to the list.

The Filter Accept List can also be used for scanning or advertising by using the option fal. For example, if we want to scan for a bunch of selected addresses, we can set up a Filter Accept List:

```
uart:~$ bt fal-add 65:4B:9E:83:AF:73 random
uart:~$ bt fal-add 5D:85:50:1C:72:64 random
uart:~$ bt scan on fal
```

You should see only those three addresses reported by the scanner.
Enabling security

When connected to a device, you can enable multiple levels of security, here is the list for Bluetooth LE:

- 1 No encryption and no authentication;
- 2 Encryption and no authentication;
- 3 Encryption and authentication;
- 4 Bluetooth LE Secure Connection.

To enable security, use the `bt security <level>` command. For levels requiring authentication (level 3 and above), you must first set the authentication method. To do it, you can use the `bt auth all` command. After that, when you will set the security level, you will be asked to confirm the passkey on both devices. On the shell side, do it with the command `bt auth-passkey-confirm`.

Pairing

Enabling authentication requires the devices to be bondable. By default the shell is bondable. You can make the shell not bondable using `bt bondable off`. You can list all the devices you are paired with using the command `bt bonds`.

The maximum number of paired devices is set using `CONFIG_BT_MAX_PAIRED`. You can remove a paired device using `bt clear <address: XX:XX:XX:XX:XX:XX> <type: (public|random)>` or remove all paired devices with the command `bt clear all`.

GATT

The following examples assume that you have two devices already connected.

To perform service discovery on the client side, use the `gatt discover` command. This should print all the services that are available on the GATT server.

On the server side, you can register pre-defined test services using the `gatt register` command. When done, you should see the newly added services on the client side when running the discovery command.

You can now subscribe to those new services on the client side. Here is an example on how to subscribe to the test service:

```
uart:~$ gatt subscribe 26 25
Subscribed
```

The server can now notify the client with the command `gatt notify`.

Another option available through the GATT command is initiating the MTU exchange. To do it, use the `gatt exchange-mtu` command. To update the shell maximum MTU, you need to update Kconfig symbols in the configuration file of the shell. For more details, see `bluetooth_mtu_update_sample`.

L2CAP

The `l2cap` command exposes parts of the L2CAP API. The following example shows how to register a LE PSM, connect to it from another device and send 3 packets of 14 octets each.

The example assumes that the two devices are already connected.

On device A, register the LE PSM:

```
uart:~$ l2cap register 29
L2CAP psm 41 sec_level 1 registered
```
On device B, connect to the registered LE PSM and send data:

```
uart:~$ l2cap connect 29
Chan sec: 1
L2CAP connection pending
Channel 0x20000210 connected
Channel 0x20000210 status 1
uart:~$ l2cap send 3 14
Rem 2
Rem 1
Rem 0
Outgoing data channel 0x20000210 transmitted
Outgoing data channel 0x20000210 transmitted
Outgoing data channel 0x20000210 transmitted
```

On device A, you should have received the data:

```
Incoming conn 0x20002398
Channel 0x20000210 status 1
Channel 0x20000210 connected
Channel 0x20000210 requires buffer
Incoming data channel 0x20000210 len 14
00000000: ff ff ff ff ff ff ff ff ff ff ff ff ff ff |........ ...... |
Channel 0x20000210 requires buffer
Incoming data channel 0x20000210 len 14
00000000: ff ff ff ff ff ff ff ff ff ff ff ff ff ff |........ ...... |
Channel 0x20000210 requires buffer
Incoming data channel 0x20000210 len 14
00000000: ff ff ff ff ff ff ff ff ff ff ff ff ff ff |........ ...... |
```

**Logging**

You can configure the logging level per module at runtime. This depends on the maximum logging level that is compiled in. To configure, use the `log` command. Here are some examples:

- List the available modules and their current logging level

```
uart:~$ log status
```

- Disable logging for `bt_hci_core`

```
uart:~$ log disable bt_hci_core
```

- Enable error logs for `bt_att` and `bt_smp`

```
uart:~$ log enable err bt_att bt_smp
```

- Disable logging for all modules

```
uart:~$ log disable
```

- Enable warning logs for all modules

```
uart:~$ log enable wrn
```

## 6.2 Controller Area Network (CAN) Bus Protocols
6.2.1 ISO-TP Transport Protocol

Overview

ISO-TP is a transport protocol defined in the ISO-Standard ISO15765-2 Road vehicles - Diagnostic communication over Controller Area Network (DoCAN). Part2: Transport protocol and network layer services. As its name already implies, it is originally designed, and still used in road vehicle diagnostic over Controller Area Networks. Nevertheless, it's not limited to applications in road vehicles or the automotive domain.

This transport protocol extends the limited payload data size for classical CAN (8 bytes) and CAN FD (64 bytes) to theoretically four gigabytes. Additionally, it adds a flow control mechanism to influence the sender's behavior. ISO-TP segments packets into small fragments depending on the payload size of the CAN frame. The header of those segments is called Protocol Control Information (PCI).

Packets smaller or equal to seven bytes on Classical CAN are called single-frames (SF). They don't need to fragment and do not have any flow-control.

Packets larger than that are segmented into a first-frame (FF) and as many consecutive-frames (CF) as required. The FF contains information about the length of the entire payload data and additionally, the first few bytes of payload data. The receiving peer sends back a flow-control-frame (FC) to either deny, postpone, or accept the following consecutive frames. The FC also defines the conditions of sending, namely the block-size (BS) and the minimum separation time between frames (STmin). The block size defines how many CF the sender is allowed to send, before he has to wait for another FC.

API Reference

Related code samples

ISO-TP library
Use ISO-TP library to exchange messages between two boards.

group can_isotp
CAN ISO-TP Protocol.

ISO-TP message ID flags
**ISOTP_MSG_EXT_ADDR**
Message uses ISO-TP extended addressing (first payload byte of CAN frame)

**ISOTP_MSG_FIXED_ADDR**
Message uses ISO-TP fixed addressing (according to SAE J1939).
Only valid in combination with **ISOTP_MSG_IDE**.

**ISOTP_MSG_IDE**
Message uses extended (29-bit) CAN ID.

**ISOTP_MSG_FDF**
Message uses CAN FD format (FDF)

**ISOTP_MSG_BRS**
Message uses CAN FD Baud Rate Switch (BRS).
Only valid in combination with **ISOTP_MSG_FDF**.

**Defines**

**ISOTP_N_OK**
Completed successfully.

**ISOTP_N_TIMEOUT_A**
Ar/As has timed out.

**ISOTP_N_TIMEOUT_BS**
Reception of next FC has timed out.

**ISOTP_N_TIMEOUT_CR**
Cr has timed out.

**ISOTP_N_WRONG_SN**
Unexpected sequence number.

**ISOTP_N_INVALID_FS**
Invalid flow status received.

**ISOTP_N_UNEXP_PDU**
Unexpected PDU received.

**ISOTP_N_WFT_OVRN**
Maximum number of WAIT flowStatus PDUs exceeded.

**ISOTP_N_BUFFER_OVFLW**
FlowStatus OVFLW PDU was received.

6.2. Controller Area Network (CAN) Bus Protocols
ISOTP_N_ERROR
   General error.

ISOTP_NO_FREE_FILTER
   Implementation specific errors.
   Can't bind or send because the CAN device has no filter left

ISOTP_NO_NET_BUF_LEFT
   No net buffer left to allocate.

ISOTP_NO_BUF_DATA_LEFT
   Not sufficient space in the buffer left for the data.

ISOTP_NO_CTX_LEFT
   No context buffer left to allocate.

ISOTP_RECV_TIMEOUT
   Timeout for recv.

ISOTP_FIXED_ADDR_SA_POS
   Position of fixed source address (SA)

ISOTP_FIXED_ADDR_SA_MASK
   Mask to obtain fixed source address (SA)

ISOTP_FIXED_ADDR_TA_POS
   Position of fixed target address (TA)

ISOTP_FIXED_ADDR_TA_MASK
   Mask to obtain fixed target address (TA)

ISOTP_FIXED_ADDR_PRIO_POS
   Position of priority in fixed addressing mode.

ISOTP_FIXED_ADDR_PRIO_MASK
   Mask for priority in fixed addressing mode.

ISOTP_FIXED_ADDR_RX_MASK
   CAN filter RX mask to match any priority and source address (SA)

**Typedefs**

typedef void (*isotp_tx_callback_t)(int error_nr, void *arg)
   Transmission callback.
   This callback is called when a transmission is completed.

   **Param error_nr**
      ISOTP_N_OK on success, ISOTP_N_* on error
**Param arg**

Callback argument passed to the send function

**Functions**

```c
int isotp_bind(struct isotp_recv_ctx *rctx, const struct device *can_dev, const struct isotp_msg_id *rx_addr, const struct isotp_msg_id *tx_addr, const struct isotp_fc_opts *opts, k_timeout_t timeout)
```

Bind an address to a receiving context.

This function binds an RX and TX address combination to an RX context. When data arrives from the specified address, it is buffered and can be read by calling isotp_recv. When calling this routine, a filter is applied in the CAN device, and the context is initialized. The context must be valid until calling unbind.

**Parameters**

- `rctx` – Context to store the internal states.
- `can_dev` – The CAN device to be used for sending and receiving.
- `rx_addr` – Identifier for incoming data.
- `tx_addr` – Identifier for FC frames.
- `opts` – Flow control options.
- `timeout` – Timeout for FF SF buffer allocation.

**Return values**

- `ISOTP_N_OK` – on success
- `ISOTP_NO_FREE_FILTER` – if CAN device has no filters left.

```c
void isotp_unbind(struct isotp_recv_ctx *rctx)
```

Unbind a context from the interface.

This function removes the binding from isotp_bind. The filter is detached from the CAN device, and if a transmission is ongoing, buffers are freed. The context can be discarded safely after calling this function.

**Parameters**

- `rctx` – Context that should be unbound.

```c
int isotp_recv(struct isotp_recv_ctx *rctx, uint8_t *data, size_t len, k_timeout_t timeout)
```

Read out received data from fifo.

This function reads the data from the receive FIFO of the context. It blocks if the FIFO is empty. If an error occurs, the function returns a negative number and leaves the data buffer unchanged.

**Parameters**

- `rctx` – Context that is already bound.
- `data` – Pointer to a buffer where the data is copied to.
- `len` – Size of the buffer.
- `timeout` – Timeout for incoming data.

**Return values**

- `Number` – of bytes copied on success
- `ISOTP_RECV_TIMEOUT` – when “timeout” timed out
Get the net buffer on data reception.
This function reads incoming data into net-buffers. It blocks until the entire packet is received, BS is reached, or an error occurred. If BS was zero, the data is in a single `net_buf`. Otherwise, the data is fragmented in chunks of BS size. The net-buffers are referenced and must be freed with `net_buf_unref` after the data is processed.

**Parameters**
- `rctx` – Context that is already bound.
- `buffer` – Pointer where the `net_buf` pointer is written to.
- `timeout` – Timeout for incoming data.

**Return values**
- Remaining – data length for this transfer if BS > 0, 0 for BS = 0
- ISOTP_RECV_TIMEOUT – when “timeout” timed out
- ISOTP_N_* – on error

Send data.
This function is used to send data to a peer that listens to the tx_addr. An internal workqueue is used to transfer the segmented data. Data and context must be valid until the transmission has finished. If a complete_cb is given, this function is non-blocking, and the callback is called on completion with the return value as a parameter.

**Parameters**
- `sctx` – Context to store the internal states.
- `can_dev` – The CAN device to be used for sending and receiving.
- `data` – Data to be sent.
- `len` – Length of the data to be sent.
- `rx_addr` – Identifier for FC frames.
- `tx_addr` – Identifier for outgoing frames the receiver listens on.
- `complete_cb` – Function called on completion or NULL.
- `cb_arg` – Argument passed to the complete callback.

**Return values**
- ISOTP_N_OK – on success
- ISOTP_N_* – on error

```c
#include <isotp.h>
ISO-TP message id struct.
Used to pass addresses to the bind and send functions.
```
Public Members

union isotp_msg_id
  CAN identifier.
  
  If ISO-TP fixed addressing is used, isotp_bind ignores SA and priority sections and modifies TA section in flow control frames.

uint8_t ext_addr
  ISO-TP extended address (if used)

uint8_t dl
  ISO-TP frame data length (TX_DL for TX address or RX_DL for RX address).
  Valid values are 8 for classical CAN or 8, 12, 16, 20, 24, 32, 48 and 64 for CAN FD.
  0 will be interpreted as 8 or 64 (if ISOTP_MSG_FDF is set).
  The value for incoming transmissions (RX_DL) is determined automatically based on the received first frame and does not need to be set during initialization.

uint8_t flags
  Flags.

See also:

  ISOTP_MSG_FLAGS.

struct isotp_fc_opts
  #include <isotp.h> ISO-TP frame control options struct.
  Used to pass the options to the bind and send functions.

Public Members

uint8_t bs
  Block size.
  Number of CF PDUs before next CF is sent

uint8_t stmin
  Minimum separation time.
  Min time between frames

6.3 Networking

The networking section contains information regarding the network stack of the Zephyr kernel. Use the information to understand the principles behind the operation of the stacks and how they were implemented.
6.3.1 Overview

- **Supported Features**
- **Source Tree Layout**

**Supported Features**

The networking IP stack is modular and highly configurable via build-time configuration options. You can minimize system memory consumption by enabling only those network features required by your application. Almost all features can be disabled if not needed.

- **IPv6** The support for IPv6 is enabled by default. Various IPv6 sub-options can be enabled or disabled depending on networking needs.
  - Developer can set the number of unicast and multicast IPv6 addresses that are active at the same time.
  - The IPv6 address for the device can be set either statically or dynamically using SLAAC (Stateless Address Auto Configuration) (RFC 4862).
  - The system also supports multiple IPv6 prefixes and the maximum IPv6 prefix count can be configured at build time.
  - The IPv6 neighbor cache can be disabled if not needed, and its size can be configured at build time.
  - The IPv6 neighbor discovery support (RFC 4861) is enabled by default.
  - Multicast Listener Discovery v2 support (RFC 3810) is enabled by default.
  - IPv6 header compression (6lo) is available for IPv6 connectivity for Bluetooth IPSP (RFC 7668) and IEEE 802.15.4 networks (RFC 4944).

- **IPv4** The legacy IPv4 is supported by the networking stack. It cannot be used by IEEE 802.15.4 or Bluetooth IPSP as those network technologies support only IPv6. IPv4 can be used in Ethernet based networks. By default IPv4 support is disabled.
  - DHCP (Dynamic Host Configuration Protocol) client is supported (RFC 2131).
  - The IPv4 address can also be configured manually. Static IPv4 addresses are supported by default.

- **Dual stack support.** The networking stack allows a developer to configure the system to use both IPv6 and IPv4 at the same time.

- **UDP** User Datagram Protocol (RFC 768) is supported. The developer can send UDP datagrams (client side support) or create a listener to receive UDP packets destined to certain port (server side support).

- **TCP** Transmission Control Protocol (RFC 793) is supported. Both server and client roles can be used the application. The amount of TCP sockets that are available to applications can be configured at build time.

- **BSD Sockets API** Support for a subset of a BSD sockets compatible API is implemented. Both blocking and non-blocking datagram (UDP) and stream (TCP) sockets are supported.

- **Secure Sockets API** Experimental support for TLS/DTLS secure protocols and configuration options for sockets API. Secure functions for the implementation are provided by mbedTLS library.

- **MQTT** Message Queue Telemetry Transport (ISO/IEC PRF 20922) is supported. A sample mqtt-publisher client application for MQTT v3.1.1 is implemented.
Zephyr Project Documentation, Release 3.6.0-rc3

- **CoAP** Constrained Application Protocol (RFC 7252) is supported. Both coap-client and coap-server sample applications are implemented.

- **LWM2M** OMA Lightweight Machine-to-Machine Protocol (LwM2M specification 1.0.2) is supported via the “Bootstrap”, “Client Registration”, “Device Management & Service Enablement” and “Information Reporting” interfaces. The required core LwM2M objects are implemented as well as several IPSO Smart Objects. (LwM2M specification 1.1.1) is supported in similar manner when enabled with a Kconfig option. lwm2m-client sample implements the library as an example.

- **DNS** Domain Name Service (RFC 1035) client functionality is supported. Applications can use the DNS API to query domain name information or IP addresses from the DNS server. Both IPv4 (A) and IPv6 (AAAA) records can be queried. Both multicast DNS (mDNS) (RFC 6762) and link-local multicast name resolution (LLMNR) (RFC 4795) are supported.

- **Network Management API.** Applications can use network management API to listen management events generated by core stack when for example IP address is added to the device, or network interface is coming up etc.

- **Wi-Fi Management API.** Applications can use Wi-Fi management API to manage the interface, in example to connect to Wi-Fi network and to scan available Wi-Fi networks.

- **Wi-Fi Network Manager API.** Wi-Fi Network Managers can now register themselves to the Wi-Fi stack. The Network Managers can then implement the Wi-Fi Management API and manage the Wi-Fi interface.

- **Multiple Network Technologies.** The Zephyr OS can be configured to support multiple network technologies at the same time simply by enabling them in Kconfig: for example, Ethernet, Wi-Fi and 802.15.4 support. Note that no automatic IP routing functionality is provided between these technologies. Applications can send data according to their needs to desired network interface.

- **Minimal Copy Network Buffer Management.** It is possible to have minimal copy network data path. This means that the system tries to avoid copying application data when it is sent to the network.

- **Virtual LAN support.** Virtual LANs (VLANs) allow partitioning of physical ethernet networks into logical networks. See VLAN support for more details.

- **Network traffic classification.** The sent and received network packets can be prioritized depending on application needs. See traffic classification for more details.

- **Time Sensitive Networking.** The gPTP (generalized Precision Time Protocol) is supported. See gPTP support for more details.

- **Network shell.** The network shell provides helpers for figuring out network status, enabling/disabling features, and issuing commands like ping or DNS resolving. The net-shell is useful when developing network software. See network shell for more details.

Additionally these network technologies (link layers) are supported in Zephyr OS v1.7 and later:

- IEEE 802.15.4
- Bluetooth
- Ethernet
- SLIP (IP over serial line). Used for testing with QEMU. It provides ethernet interface to host system (like Linux) and test applications can be run in Linux host and send network data to Zephyr OS device.

**Source Tree Layout**

The networking stack source code tree is organized as follows:
subsys/net/ip/
This is where the IP stack code is located.

subsys/net/12/
This is where the IP stack layer 2 code is located. This includes generic support for Bluetooth IPSP adaptation, Ethernet, IEEE 802.15.4 and Wi-Fi.

subsys/net/lib/
Application-level protocols (DNS, MQTT, etc.) and additional stack components (BSD Sockets, etc.).

include/net/
Public API header files. These are the header files applications need to include to use IP networking functionality.

samples/net/
Sample networking code. This is a good reference to get started with network application development.

tests/net/
Test applications. These applications are used to verify the functionality of the IP stack, but are not the best source for sample code (see samples/net instead).

6.3.2 Network Stack Architecture

Network Packet Processing Statistics

This page describes how to get information about network packet processing statistics inside network stack.

Network stack contains infrastructure to figure out how long the network packet processing takes either in sending or receiving path. There are two Kconfig options that control this. For transmit (TX) path the option is called CONFIG_NET_PKT_TXTIME_STATS and for receive (RX) path the options is called CONFIG_NET_PKT_RXTIME_STATS. Note that for TX, all kind of network packet statistics is collected. For RX, only UDP, TCP or raw packet type network packet statistics is collected.

After enabling these options, the net stats network shell command will show this information:

<table>
<thead>
<tr>
<th>Statistic</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>Avg TX net_pkt (11484)</td>
<td>time 67 us</td>
</tr>
<tr>
<td>Avg RX net_pkt (11474)</td>
<td>time 43 us</td>
</tr>
</tbody>
</table>

Note: The values above and below are from emulated qemu_x86 board and UDP traffic

The TX time tells how long it took for network packet from its creation to when it was sent to the network. The RX time tells the time from its creation to when it was passed to the application. The values are in microseconds. The statistics will be collected per traffic class if there are more than one transmit or receive queues defined in the system. These are controlled by CONFIG_NET_TC_TX_COUNT and CONFIG_NET_TC_RX_COUNT options.

If you enable CONFIG_NET_PKT_TXTIME_STATS_DETAIL or CONFIG_NET_PKT_RXTIME_STATS_DETAIL options, then additional information for TX or RX network packets are collected when the network packet traverses the IP stack.

After enabling these options, the net stats will show this information:

<table>
<thead>
<tr>
<th>Statistic</th>
<th>Value</th>
<th>Queue Times</th>
</tr>
</thead>
<tbody>
<tr>
<td>Avg TX net_pkt (18902)</td>
<td>time 63 us</td>
<td>[0-&gt;22-&gt;15-&gt;23=60 us]</td>
</tr>
<tr>
<td>Avg RX net_pkt (18892)</td>
<td>time 42 us</td>
<td>[0-&gt;9-&gt;6-&gt;11-&gt;13=39 us]</td>
</tr>
</tbody>
</table>
The numbers inside the brackets contain information how many microseconds it took for a network packet to go from previous state to next.

In the TX example above, the values are averages over 18902 packets and contain this information:

- Packet was created by application so the time is 0.
- Packet is about to be placed to transmit queue. The time it took from network packet creation to this state, is 22 microseconds in this example.
- The correct TX thread is invoked, and the packet is read from the transmit queue. It took 15 microseconds from previous state.
- The network packet was just sent and the network stack is about to free the network packet. It took 23 microseconds from previous state.
- In total it took on average 60 microseconds to get the network packet sent. The value 63 tells also the same information, but is calculated differently so there is slight difference because of rounding errors.

In the RX example above, the values are averages over 18892 packets and contain this information:

- Packet was created network device driver so the time is 0.
- Packet is about to be placed to receive queue. The time it took from network packet creation to this state, is 9 microseconds in this example.
- The correct RX thread is invoked, and the packet is read from the receive queue. It took 6 microseconds from previous state.
- The network packet is then processed and placed to correct socket queue. It took 11 microseconds from previous state.
- The last value tells how long it took from there to the application. Here the value is 13 microseconds.
- In total it took on average 39 microseconds to get the network packet sent. The value 42 tells also the same information, but is calculated differently so there is slight difference because of rounding errors.

The Zephyr network stack is a native network stack specifically designed for Zephyr OS. It consists of layers, each meant to provide certain services to other layers. Network stack functionality is highly configurable via Kconfig options.

---

### High level overview of the network stack

- **Network data flow**
  - Data receiving (RX)
  - Data sending (TX)
- Network packet processing statistics

### High level overview of the network stack

The network stack is layered and consists of the following parts:

- **Network Application.** The network application can either use the provided application-level protocol libraries or access the BSD socket API directly to create a network connection, send or receive data, and close a connection. The application can also use the network management API to configure the network and set related parameters such as network link options, starting a scan (when applicable), listen network configuration events, etc.
Fig. 12: Network stack overview
The network interface API can be used to set IP address to a network interface, taking the
network interface down, etc.

- **Network Protocols.** This provides implementations for various protocols such as
  - Application-level network protocols like CoAP, LWM2M, and MQTT. See application protocols chapter for information about them.
  - Core network protocols like IPv6, IPv4, UDP, TCP, ICMPv4, and ICMPv6. You access these protocols by using the BSD socket API.

- **Network Interface Abstraction.** This provides functionality that is common in all the network interfaces, such as setting network interface down, etc. There can be multiple network interfaces in the system. See network interface overview for more details.

- **L2 Network Technologies.** This provides a common API for sending and receiving data to and from an actual network device. See L2 overview for more details. These network technologies include Ethernet, IEEE 802.15.4, Bluetooth, CANBUS, etc. Some of these technologies support IPv6 header compression (6Lo), see RFC 6282 for details. For example ARP for IPv4 is done by the Ethernet component.

- **Network Device Drivers.** The actual low-level device drivers handle the physical sending or receiving of network packets.

**Network data flow**

An application typically consists of one or more threads that execute the application logic. When using the BSD socket API, the following things will happen.

**Data receiving (RX)**

1. A network data packet is received by a device driver.

2. The device driver allocates enough network buffers to store the received data. The network packet is placed in the proper RX queue (implemented by k_fifo). By default there is only one receive queue in the system, but it is possible to have up to 8 receive queues. These queues will process incoming packets with different priority. See Traffic Classification for more details. The receive queues also act as a way to separate the data processing pipeline (bottom-half) as the device driver is running in an interrupt context and it must do its processing as fast as possible.

3. The network packet is then passed to the correct L2 driver. The L2 driver can check if the packet is proper and modify it if needed, e.g. strip L2 header and frame check sequence, etc.

4. The packet is processed by a network interface. The network statistics are collected if enabled by CONFIG_NET_STATISTICS.

5. The packet is then passed to L3 processing. If the packet is IP based, then the L3 layer checks if the packet is a proper IPv6 or IPv4 packet.

6. A socket handler then finds an active socket to which the network packet belongs and puts it in a queue for that socket, in order to separate the networking code from the application. Typically the application is run in userspace context and the network stack is run in kernel context.

7. The application will then receive the data and can process it as needed. The application should have used the BSD socket API to create a socket that will receive the data.

**Data sending (TX)**

1. The application should use the BSD socket API when sending the data.

6.3. Networking
Receiving UDP packet

1. Packet received from the network
2. Allocate buffers and put packet to RX queue
3. Network packet passed to correct L2 driver, Ethernet headers stripped and packet checked
4. Passed to Network Interface for further processing
5. IPv4 headers parsed and stripped
6. UDP headers parsed and stripped. Packet added to socket queue
7. Packet retrieved from socket queue. Data copied into application buffers.
8.Recv returns

Network Application

Application Protocols
- CoAP
- LWM2M
- MQTT

Non-IP sockets
- IPv6
- ICMPv4
- IPv4
- ICMPv6
- UDP
- TCP

Network Management API

Application Protocols

User space

Kernel space

“Bottom Half” Core stack

Network Interface Abstraction

Network Interface Drivers

Ethernet drivers
- 802.15.4 drivers
- Other drivers

Network Protocols

IPv6
ICMPv4
IPv4
ICMPv6
UDP
TCP
Ethernet
802.15.4
Bluetooth
CAN

L2 Network Technologies

Packet Header Compression

802.15.4

Network Device Drivers

802.15.4

Fig. 13: Network RX data flow

Chapter 6. Connectivity
Sending UDP packet

1. Application calls send() from socket API.
2. Net_packet structure created, user data copied to it. Packet marshalled to kernel space.
3. UDP protocol header is added in front of the data.
4. IPv4 headers added in front.
5. The network stack checks if interface is set up and enabled and sends the data.
6. The network packet is classified and placed to proper transmit queue. Packet checked and L2 headers for the network packet are added.
7. Device driver retrieves packet from the FIFO and sends it to the network.
8. Data physically sent.

Fig. 14: Network TX data flow
2. The application data is prepared for sending to kernel space and then copied to internal net_buf structures.

3. Depending on the socket type, a protocol header is added in front of the data. For example, if the socket is a UDP socket, then a UDP header is constructed and placed in front of the data.

4. An IP header is added to the network packet for a UDP or TCP packet.

5. The network stack will check that the network interface is properly set for the network packet, and also will make sure that the network interface is enabled before the data is queued to be sent.

6. The network packet is then classified and placed to the proper transmit queue (implemented by kfifo). By default there is only one transmit queue in the system, but it is possible to have up to 8 transmit queues. These queues will process the sent packets with different priority. See Traffic Classification for more details. After the transmit packet classification, the packet is checked by the correct L2 layer module. The L2 module will do additional checks for the data and it will also create any L2 headers for the network packet. If everything is ok, the data is given to the network device driver to be sent out.

7. The device driver will send the packet to the network.

Note that in both the TX and RX data paths, the queues (kfifo’s) form separation points where data is passed from one thread to another. These threads might run in different contexts (kernel vs. userspace) and with different priorities.

Network packet processing statistics

See information about network processing statistics here.

6.3.3 Network Configuration Guide

- Network Buffer Configuration Options
- Connection Options
- Socket Options
- TLS Options
- IPv4/6 Options
- TCP Options
- Traffic Class Options
- Stack Size Options

This document describes how various network configuration options can be set according to available resources in the system.

Network Buffer Configuration Options

The network buffer configuration options control how much data we are able to either send or receive at the same time.

CONFIG_NET_PKT_RX_COUNT
Maximum amount of network packets we can receive at the same time.
CONFIG_NET_PKT_TX_COUNT
Maximum amount of network packet sends pending at the same time.

CONFIG_NET_BUF_RX_COUNT
How many network buffers are allocated for receiving data. Each net_buf contains a small header and either a fixed or variable length data buffer. The CONFIG_NET_BUF_DATA_SIZE is used when CONFIG_NET_BUF_FIXED_DATA_SIZE is set. This is the default setting. The default size of the buffer is 128 bytes.

The CONFIG_NET_BUF_VARIABLE_DATA_SIZE is an experimental setting. There each net_buf data portion is allocated from a memory pool and can be the amount of data we have received from the network. When data is received from the network, it is placed into net_buf data portion. Depending on device resources and desired network usage, user can tweak the size of the fixed buffer by setting CONFIG_NET_BUF_DATA_SIZE, and the size of the data pool size by setting CONFIG_NET_BUF_DATA_POOL_SIZE if variable size buffers are used.

When using the fixed size data buffers, the memory consumption of network buffers can be tweaked by selecting the size of the data part according to what kind of network data we are receiving. If one sets the data size to 256, but only receives packets that are 32 bytes long, then we are “wasting” 224 bytes for each packet because we cannot utilize the remaining data. One should not set the data size too low because there is some overhead involved for each net_buf. For these reasons the default network buffer size is set to 128 bytes.

The variable size data buffer feature is marked as experimental as it has not received as much testing as the fixed size buffers. Using variable size data buffers tries to improve memory utilization by allocating minimum amount of data we need for the network data. The extra cost here is the amount of time that is needed when dynamically allocating the buffer from the memory pool.

For example, in Ethernet the maximum transmission unit (MTU) size is 1500 bytes. If one wants to receive two full frames, then the net_pkt RX count should be set to 2, and net_buf RX count to (1500 / 128) * 2 which is 24. If TCP is being used, then these values need to be higher because we can queue the packets internally before delivering to the application.

CONFIG_NET_BUF_TX_COUNT
How many network buffers are allocated for sending data. This is similar setting as the receive buffer count but for sending.

Connection Options

CONFIG_NET_MAX_CONN
This option tells how many network connection endpoints are supported. For example each TCP connection requires one connection endpoint. Similarly each listening UDP connection requires one connection endpoint. Also various system services like DHCP and DNS need connection endpoints to work. The network shell command net conn can be used at runtime to see the network connection information.

CONFIG_NET_MAX_CONTEXTS
Number of network contexts to allocate. Each network context describes a network 5-tuple that is used when listening or sending network traffic. Each BSD socket in the system uses one network context.

Socket Options

CONFIG_NET_SOCKETS_POLL_MAX
Maximum number of supported poll() entries. One needs to select proper value here depending on how many BSD sockets are polled in the system.

CONFIG_POSIX_MAX_FDS
Maximum number of open file descriptors, this includes files, sockets, special devices, etc.
One needs to select proper value here depending on how many BSD sockets are created in the system.

**CONFIG_NET_SOCKETPAIR_BUFFER_SIZE**
This option is used by socketpair() function. It sets the size of the internal intermediate buffer, in bytes. This sets the limit how large messages can be passed between two socket-pair endpoints.

**TLS Options**

**CONFIG_NET_SOCKETS_TLS_MAX_CONTEXTS**
Maximum number of TLS/DTLS contexts. Each TLS/DTLS connection needs one context.

**CONFIG_NET_SOCKETS_TLS_MAX_CREDENTIALS**
This variable sets maximum number of TLS/DTLS credentials that can be used with a specific socket.

**CONFIG_NET_SOCKETS_TLS_MAX_CIPHERSUITES**
Maximum number of TLS/DTLS ciphersuites per socket. This variable sets maximum number of TLS/DTLS ciphersuites that can be used with a specific socket, if set explicitly by a socket option. By default, all ciphersuites that are available in the system are available to the socket.

**CONFIG_NET_SOCKETS_TLS_MAX_APP_PROTOCOLS**
Maximum number of supported application layer protocols. This variable sets maximum number of supported application layer protocols over TLS/DTLS that can be set explicitly by a socket option. By default, no supported application layer protocol is set.

**CONFIG_NET_SOCKETS_TLS_MAX_CLIENT_SESSION_COUNT**
This variable specifies maximum number of stored TLS/DTLS sessions, used for TLS/DTLS session resumption.

**CONFIG_TLS_MAX_CREDENTIALS_NUMBER**
Maximum number of TLS credentials that can be registered. Make sure that this value is high enough so that all the certificates can be loaded to the store.

**IPv4/6 Options**

**CONFIG_NET_IF_MAX_IPV4_COUNT**
Maximum number of IPv4 network interfaces in the system. This tells how many network interfaces there will be in the system that will have IPv4 enabled. For example if you have two network interfaces, but only one of them can use IPv4 addresses, then this value can be set to 1. If both network interface could use IPv4, then the setting should be set to 2.

**CONFIG_NET_IF_MAX_IPV6_COUNT**
Maximum number of IPv6 network interfaces in the system. This is similar setting as the IPv4 count option but for IPv6.

**TCP Options**

**CONFIG_NET_TCP_TIME_WAIT_DELAY**
How long to wait in TCP **TIME_WAIT** state (in milliseconds). To avoid a (low-probability) issue when delayed packets from previous connection get delivered to next connection reusing the same local/remote ports, RFC 793 (TCP) suggests to keep an old, closed connection in a special **TIME_WAIT** state for the duration of 2*MSL (Maximum Segment Lifetime). The RFC suggests to use MSL of 2 minutes, but notes

*This is an engineering choice, and may be changed if experience indicates it is desirable to do so.*
For low-resource systems, having large MSL may lead to quick resource exhaustion (and related DoS attacks). At the same time, the issue of packet misdelivery is largely alleviated in the modern TCP stacks by using random, non-repeating port numbers and initial sequence numbers. Due to this, Zephyr uses much lower value of 1500ms by default. Value of 0 disables TIME_WAIT state completely.

**CONFIG_NET_TCP_RETRY_COUNT**

Maximum number of TCP segment retransmissions. The following formula can be used to determine the time (in ms) that a segment will be be buffered awaiting retransmission:

\[ \sum_{n=0}^{\text{NET_TCP_RETRY_COUNT}} (1 \ll n) \times \text{NET_TCP_INIT_RETRANSMISSION_TIMEOUT} \]

With the default value of 9, the IP stack will try to retransmit for up to 1:42 minutes. This is as close as possible to the minimum value recommended by RFC 1122 (1:40 minutes). Only 5 bits are dedicated for the retransmission count, so accepted values are in the 0-31 range. It's highly recommended to not go below 9, though.

Should a retransmission timeout occur, the receive callback is called with -ETIMEDOUT error code and the context is dereferenced.

**CONFIG_NET_TCP_MAX_SEND_WINDOW_SIZE**

Maximum sending window size to use. This value affects how the TCP selects the maximum sending window size. The default value 0 lets the TCP stack select the value according to amount of network buffers configured in the system. Note that if there are multiple active TCP connections in the system, then this value might require finetuning (lowering), otherwise multiple TCP connections could easily exhaust net_buf pool for the queued TX data.

**CONFIG_NET_TCP_MAX_RECV_WINDOW_SIZE**

Maximum receive window size to use. This value defines the maximum TCP receive window size. Increasing this value can improve connection throughput, but requires more receive buffers available in the system for efficient operation. The default value 0 lets the TCP stack select the value according to amount of network buffers configured in the system.

**CONFIG_NET_TCP_RECV_QUEUE_TIMEOUT**

How long to queue received data (in ms). If we receive out-of-order TCP data, we queue it. This value tells how long the data is kept before it is discarded if we have not been able to pass the data to the application. If set to 0, then receive queueing is not enabled. The value is in milliseconds.

Note that we only queue data sequentially in current version i.e., there should be no holes in the queue. For example, if we receive SEQs 5,4,3,6 and are waiting SEQ 2, the data in segments 3,4,5,6 is queued (in this order), and then given to application when we receive SEQ 2. But if we receive SEQs 5,4,3,7 then the SEQ 7 is discarded because the list would not be sequential as number 6 is be missing.

**Traffic Class Options**

It is possible to configure multiple traffic classes (queues) when receiving or sending network data. Each traffic class queue is implemented as a thread with different priority. This means that higher priority network packet can be placed to a higher priority network queue in order to send or receive it faster or slower. Because of thread scheduling latencies, in practice the fastest way to send a packet out, is to directly send the packet without using a dedicated traffic class thread. This is why by default the `CONFIG_NET_TC_TX_COUNT` option is set to 0 if userspace is not enabled. If userspace is enabled, then the minimum TX traffic class count is 1. Reason for this is that the userspace application does not have enough permissions to deliver the message directly.

In receiving side, it is recommended to have at least one receiving traffic class queue. Reason is that typically the network device driver is running in IRQ context when it receives the packet,
in which case it should not try to deliver the network packet directly to the upper layers, but to place the packet to the traffic class queue. If the network device driver is not running in IRQ context when it gets the packet, then the RX traffic class option `CONFIG_NET_TC_RX_COUNT` could be set to 0.

**Stack Size Options**

There several network specific threads in a network enabled system. Some of the threads might depend on a configure option which can be used to enable or disable a feature. Each thread stack size is optimized to allow normal network operations.

The network management API is using a dedicated thread by default. The thread is responsible to deliver network management events to the event listeners that are setup in the system if the `CONFIG_NET_MGMT` and `CONFIG_NET_MGMT_EVENT` options are enabled. If the options are enabled, the user is able to register a callback function that the net_mgmt thread is calling for each network management event. By default the net_mgmt event thread stack size is rather small. The idea is that the callback function does minimal things so that new events can be delivered to listeners as fast as possible and they are not lost. The net_mgmt event thread stack size is controlled by `CONFIG_NET_MGMT_EVENT_QUEUE_SIZE` option. It is recommended to not do any blocking operations in the callback function.

The network thread stack utilization can be monitored from kernel shell by the `kernel threads` command.

### 6.3.4 Networking with the host system

**Networking with native_sim board**

<p>| <strong>Prerequisites</strong> |</p>
<table>
<thead>
<tr>
<th><strong>Basic Setup</strong></th>
</tr>
</thead>
<tbody>
<tr>
<td>Step 1 - Create Ethernet interface</td>
</tr>
<tr>
<td>Step 2 - Start app in native_sim board</td>
</tr>
<tr>
<td>Step 3 - Connect to console (optional)</td>
</tr>
</tbody>
</table>

This page describes how to set up a virtual network between a (Linux) host and a Zephyr application running in a native_sim board.

In this example, the sockets-echo-server sample application from the Zephyr source distribution is run in native_sim board. The Zephyr native_sim board instance is connected to a Linux host using a tuntap device which is modeled in Linux as an Ethernet network interface.

**Prerequisites** On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:

```
git clone https://github.com/zephyrproject-rtos/net-tools
```

**Basic Setup** For the steps below, you will need three terminal windows:

- Terminal #1 is terminal window with net-tools being the current directory (`cd net-tools`)
- Terminal #2 is your usual Zephyr development terminal, with the Zephyr environment initialized.
• Terminal #3 is the console to the running Zephyr native_sim instance (optional).

**Step 1 - Create Ethernet interface**  
Before starting native_sim with network emulation, a network interface should be created.

In terminal #1, type:

```
./net-setup.sh
```

You can tweak the behavior of the net-setup.sh script. See various options by running `net-setup.sh` like this:

```
./net-setup.sh --help
```

**Step 2 - Start app in native_sim board**  
Build and start the echo_server sample application.

In terminal #2, type:

```
w west build -b native_sim samples/net/sockets/echo_server
west build -t run
```

**Step 3 - Connect to console (optional)**  
The console window should be launched automatically when the Zephyr instance is started but if it does not show up, you can manually connect to the console. The native_sim board will print a string like this when it starts:

```
UART connected to pseudotty: /dev/pts/5
```

You can manually connect to it like this:

```
screen /dev/pts/5
```

**Networking with QEMU Ethernet**

- **Prerequisites**
- **Basic Setup**
  - Step 1 - Create Ethernet interface
  - Step 2 - Start app in QEMU board

This page describes how to set up a virtual network between a (Linux) host and a Zephyr application running in QEMU.

In this example, the sockets-echo-server sample application from the Zephyr source distribution is run in QEMU. The Zephyr instance is connected to a Linux host using a tuntap device which is modeled in Linux as an Ethernet network interface.

**Prerequisites**  
On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:

```
git clone https://github.com/zephyrproject-rtos/net-tools
```
Basic Setup  

For the steps below, you will need two terminal windows:

- Terminal #1 is terminal window with net-tools being the current directory (`cd net-tools`)
- Terminal #2 is your usual Zephyr development terminal, with the Zephyr environment initialized.

When configuring the Zephyr instance, you must select the correct Ethernet driver for QEMU connectivity:

- For `qemu_x86`, select Intel(R) PRO/1000 Gigabit Ethernet driver. Driver is called `e1000` in Zephyr source tree.
- For `qemu_cortex_m3`, select TI Stellaris MCU family ethernet driver Ethernet driver. Driver is called `stellaris` in Zephyr source tree.
- For `mps2_an385`, select SMSC911x/9220 Ethernet driver Ethernet driver. Driver is called `smsc911x` in Zephyr source tree.
- For `qemu_cortex_a53`, Intel(R) PRO/1000 Gigabit Ethernet driver Ethernet driver is selected by default.

Step 1 - Create Ethernet interface  

Before starting QEMU with network connectivity, a network interface should be created in the host system.

In terminal #1, type:

```
./net-setup.sh
```

You can tweak the behavior of the `net-setup.sh` script. See various options by running `net-setup.sh` like this:

```
./net-setup.sh --help
```

Step 2 - Start app in QEMU board  

Build and start the sockets-echo-server sample application. In this example, the qemu_x86 board is used.

In terminal #2, type:

```
west build -b qemu_x86 samples/net/sockets/echo_server -- -DEXTRA_CONF_FILE=overlay-e1000.conf
west build -t run
```

Exit QEMU by pressing CTRL+A x.

Networking with QEMU

- Prerequisites
- Basic Setup
  - Step 1 - Create helper socket
  - Step 2 - Start TAP device routing daemon
  - Step 3 - Start app in QEMU
  - Step 4 - Run apps on host
  - Step 5 - Stop supporting daemons
- Setting up Zephyr and NAT/masquerading on host to access Internet
Network connection between two QEMU VMs
- Terminal #1:
- Terminal #2:

Running multiple QEMU VMs of the same sample
- Terminal #1:
- Terminal #2:

This page describes how to set up a virtual network between a (Linux) host and a Zephyr application running in a QEMU virtual machine (built for Zephyr targets such as qemu_x86 and qemu_cortex_m3). Some virtual ARM boards (such as qemu_cortex_a53) only support a single UART, in this case QEMU Ethernet is preferred, see Networking with QEMU Ethernet for details.

In this example, the sockets-echo-server sample application from the Zephyr source distribution is run in QEMU. The QEMU instance is connected to a Linux host using a serial port, and SLIP is used to transfer data between the Zephyr application and Linux (over a chain of virtual connections).

Prerequisites On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:

```bash
git clone https://github.com/zephyrproject-rtos/net-tools
cd net-tools
make
```

Note: If you get an error about AX_CHECK_COMPILE_FLAG, install package autoconf-archive package on Debian/Ubuntu.

Basic Setup For the steps below, you will need at least 4 terminal windows:

- Terminal #1 is your usual Zephyr development terminal, with the Zephyr environment initialized.
- Terminals #2, #3, and #4 are terminal windows with net-tools being the current directory (cd net-tools)

Step 1 - Create helper socket Before starting QEMU with network emulation, a Unix socket for the emulation should be created.
In terminal #2, type:

```
./loop-socat.sh
```

Step 2 - Start TAP device routing daemon In terminal #3, type:

```
sudo ./loop-slip-tap.sh
```

For applications requiring DNS, you may need to restart the host's DNS server at this point, as described in Setting up Zephyr and NAT/masquerading on host to access Internet.

6.3. Networking
**Step 3 - Start app in QEMU**  Build and start the echo_server sample application.

In terminal #1, type:

```
west build -b qemu_x86 samples/net/sockets/echo_server
west build -t run
```

If you see an error from QEMU about unix:/tmp/slip.sock, it means you missed Step 1 above.

**Step 4 - Run apps on host**  Now in terminal #4, you can run various tools to communicate with the application running in QEMU.

You can start with pings:

```
ping 192.0.2.1
ping6 2001:db8::1
```

You can use the netcat ("nc") utility, connecting using UDP:

```
echo foobar | nc -6 -u 2001:db8::1 4242
```

```
echo foobar | nc -6 -u 192.0.2.1 4242
```

If echo_server is compiled with TCP support (now enabled by default for the echo_server sample, CONFIG_NET_TCP=y):

```
echo foobar | nc -6 -q2 2001:db8::1 4242
```

**Note:** Use Ctrl+C to exit.

You can also use the telnet command to achieve the above.

**Step 5 - Stop supporting daemons**  When you are finished with network testing using QEMU, you should stop any daemons or helpers started in the initial steps, to avoid possible networking or routing problems such as address conflicts in local network interfaces. For example, stop them if you switch from testing networking with QEMU to using real hardware, or to return your host laptop to normal Wi-Fi use.

To stop the daemons, press Ctrl+C in the corresponding terminal windows (you need to stop both loop-slip-tap.sh and loop-socat.sh).

Exit QEMU by pressing CTRL+A x.

**Setting up Zephyr and NAT/masquerading on host to access Internet**  To access the internet from a Zephyr application, some additional setup on the host may be required. This setup is common for both application running in QEMU and on real hardware, assuming that a development board is connected to the development host. If a board is connected to a dedicated router, it should not be needed.

To access the internet from a Zephyr application using IPv4, a gateway should be set via DHCP or configured manually. For applications using the "Settings" facility (with the config option CONFIG_NET_CONFIG_SETTINGS enabled), set the CONFIG_NET_CONFIG_MY_IPV4_GW option to the IP address of the gateway. For apps not using the "Settings" facility, set up the gateway by calling the net_if_ipv4_set_gw() at runtime.
To access the internet from a custom application running in QEMU, NAT (masquerading) should be set up for QEMU's source address. Assuming 192.0.2.1 is used, the following command should be run as root:

```
iptables -t nat -A POSTROUTING -j MASQUERADE -s 192.0.2.1
```

Additionally, IPv4 forwarding should be enabled on the host, and you may need to check that other firewall (iptables) rules don't interfere with masquerading. To enable IPv4 forwarding the following command should be run as root:

```
sysctl -w net.ipv4.ip_forward=1
```

Some applications may also require a DNS server. A number of Zephyr-provided samples assume by default that the DNS server is available on the host (IP 192.0.2.2), which, in modern Linux distributions, usually runs at least a DNS proxy. When running with QEMU, it may be required to restart the host's DNS, so it can serve requests on the newly created TAP interface. For example, on Debian-based systems:

```
service dnsmasq restart
```

An alternative to relying on the host's DNS server is to use one in the network. For example, 8.8.8.8 is a publicly available DNS server. You can configure it using `CONFIG_DNS_SERVER1` option.

### Network connection between two QEMU VMs

Unlike the VM-to-Host setup described above, VM-to-VM setup is automatic. For sample applications that support this mode (such as the `echo_server` and `echo_client` samples), you will need two terminal windows, set up for Zephyr development.

**Terminal #1:**

```
w west build -b qemu_x86 samples/net/sockets/echo_server
```

This will start QEMU, waiting for a connection from a client QEMU.

**Terminal #2:**

```
w west build -b qemu_x86 samples/net/sockets/echo_client
```

This will start a second QEMU instance, where you should see logging of data sent and received in both.

### Running multiple QEMU VMs of the same sample

If you find yourself wanting to run multiple instances of the same Zephyr sample application, which do not need to talk to each other, use the `QEMU_INSTANCE` argument.

Start `socat` and `tunslip6` manually (instead of using the `loop-xxx.sh` scripts) for as many instances as you want. Use the following as a guide, replacing MAIN or OTHER.

**Terminal #1:**

```
$ socat PTY,link=/tmp/slip.devMAIN UNIX-LISTEN:/tmp/slip.sockMAIN
$ $ZEPHYR_BASE/../net-tools/tunslip6 -t tapMAIN -T -s /tmp/slip.devMAIN \
    -d 2001:db8::1/64
# Now run Zephyr
make -Cbuild run QEMU_INSTANCE=MAIN
```
USB Device Networking

- **Basic Setup**
  - Choosing IP addresses
  - Setting IPv4 address and routing
  - Setting IPv6 address and routing
- Testing connection

This page describes how to set up networking between a Linux host and a Zephyr application running on USB supported devices.

The board is connected to Linux host using USB cable and provides an Ethernet interface to the host. The sockets-echo-server application from the Zephyr source distribution is run on supported board. The board is connected to a Linux host using a USB cable providing an Ethernet interface to the host.

**Basic Setup**  To communicate with the Zephyr application over a newly created Ethernet interface, we need to assign IP addresses and set up a routing table for the Linux host. After plugging a USB cable from the board to the Linux host, the cdc_ether driver registers a new Ethernet device with a provided MAC address.

You can check that network device is created and MAC address assigned by running dmesg from the Linux host.

```
cdc_ether 1-2.7:1.0 eth0: register 'cdc_ether' at usb-0000:00:01.2-2.7, CDC Ethernet Device, 00:00:5e:00:53:01
```

We need to set it up and assign IP addresses as explained in the following section.

**Choosing IP addresses**  To establish network connection to the board we need to choose IP address for the interface on the Linux host.

It make sense to choose addresses in the same subnet we have in Zephyr application. IP addresses usually set in the project configuration files and may be checked also from the shell with following commands. Connect a serial console program (such as puTTY) to the board, and enter this command to the Zephyr shell:

```
shell> net iface
```

```bash
Interface 0xa800e580 (Ethernet)
============================
Link addr : 00:00:5E:00:53:00
MTU : 1500
IPv6 unicast addresses (max 2):
  fe80::200:5eff:fe00:5300 autoconf preferred infinite
  2001:db8::2 manual preferred infinite
...```

(continues on next page)
This command shows that one IPv4 address and two IPv6 addresses have been assigned to the board. We can use either IPv4 or IPv6 for network connection depending on the board network configuration.

Next step is to assign IP addresses to the new Linux host interface, in the following steps:

**Setting IPv4 address and routing**

```bash
# ip address add dev enx00005e005301 192.0.2.2
# ip link set enx00005e005301 up
# ip route add 192.0.2.0/24 dev enx00005e005301
```

**Setting IPv6 address and routing**

```bash
# ip address add dev enx00005e005301 2001:db8::2
# ip link set enx00005e005301 up
# ip -6 route add 2001:db8::/64 dev enx00005e005301
```

**Testing connection** From the host we can test the connection by pinging Zephyr IP address of the board with:

```bash
$ ping 192.0.2.1
PING 192.0.2.1 (192.0.2.1) 56(84) bytes of data.
64 bytes from 192.0.2.1: icmp_seq=1 ttl=64 time=2.30 ms
64 bytes from 192.0.2.1: icmp_seq=2 ttl=64 time=1.43 ms
64 bytes from 192.0.2.1: icmp_seq=3 ttl=64 time=2.45 ms
...```

**Networking with QEMU User**

- **Introduction**
- **Using SLIRP with Zephyr**
- **Limitations**

This page is intended to serve as a starting point for anyone interested in using QEMU SLIRP with Zephyr.

**Introduction** SLIRP is a network backend which provides the complete TCP/IP stack within QEMU and uses that stack to implement a virtual NAT’d network. As there are no dependencies on the host, SLIRP is simple to setup.

By default, QEMU uses the 10.0.2.X/24 network and runs a gateway at 10.0.2.2. All traffic intended for the host network has to travel through this gateway, which will filter out packets based on the QEMU command line parameters. This gateway also functions as a DHCP server for all GOS, allowing them to be automatically assigned with an IP address starting from 10.0.2.15.

Using SLIRP with Zephyr  In order to use SLIRP with Zephyr, the user has to set the Kconfig option to enable User Networking.

```plaintext
CONFIG_NET_QEMU_USER=y
```

Once this configuration option is enabled, all QEMU launches will use SLIRP. In the default configuration, Zephyr only enables User Networking, and does not pass any arguments to it. This means that the Guest will only be able to communicate to the QEMU gateway, and any data intended for the host machine will be dropped by QEMU.

In general, QEMU User Networking can take in a lot of arguments including,

- Information about host/guest port forwarding. This must be provided to create a communication channel between the guest and host.
- Information about network to use. This may be valuable if the user does not want to use the default 10.0.2.X network.
- Tell QEMU to start DHCP server at user-defined IP address.
- ID and other information.

As this information varies with every use case, it is difficult to come up with good defaults that work for all. Therefore, Zephyr Implementation offloads this to the user, and expects that they will provide arguments based on requirements. For this, there is a Kconfig string which can be populated by the user.

```plaintext
CONFIG_NET_QEMU_USER_EXTRA_ARGS="net=192.168.0.0/24,hostfwd=tcp::8080-:8080"
```

This option is appended as-is to the QEMU command line. Therefore, any problems with this command line will be reported by QEMU only. Here's what this particular example will do,

- Make QEMU use the 192.168.0.0/24 network instead of the default.
- Enable forwarding of any TCP data received from port 8080 of host to port 8080 of guest, and vice versa.

Limitations  If the user does not have any specific networking requirements other than the ability to access a web page from the guest, user networking (slirp) is a good choice. However, it has several limitations

- There is a lot of overhead so the performance is poor.
- The guest is not directly accessible from the host or the external network.
- In general, ICMP traffic does not work (so you cannot use ping within a guest).
- As port mappings need to be defined before launching qemu, clients which use dynamically generated ports cannot communicate with external network.
- There is a bug in the SLIRP implementation which filters out all IPv6 packets from the guest. See https://bugs.launchpad.net/qemu/+bug/1724590 for details. Therefore, IPv6 will not work with User Networking.

Networking with multiple Zephyr instances

- **Prerequisites**
- **Basic Setup**
  - Step 1 - Create configuration files
  - Step 2 - Create Ethernet interfaces
This page describes how to set up a virtual network between multiple Zephyr instances. The Zephyr instances could be running inside QEMU or could be native_sim board processes. The Linux host can be used to route network traffic between these systems.

**Prerequisites** On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:

```
git clone https://github.com/zephyrproject-rtos/net-tools
```

**Basic Setup** For the steps below, you will need five terminal windows:

- Terminal #1 and #2 are terminal windows with net-tools being the current directory (cd net-tools)
- Terminal #3, where you setup bridging in Linux host
- Terminal #4 and #5 are your usual Zephyr development terminal, with the Zephyr environment initialized.

As there are multiple ways to setup the Zephyr network, the example below uses qemu_x86 board with e1000 Ethernet controller and native_sim board to simplify the setup instructions. You can use other QEMU boards and drivers if needed, see Networking with QEMU Ethernet for details. You can also use two or more native_sim board Zephyr instances and connect them together.

**Step 1 - Create configuration files** Before starting QEMU with network connectivity, a network interfaces for each Zephyr instance should be created in the host system. The default setup for creating network interface cannot be used here as that is for connecting one Zephyr instance to Linux host.

For Zephyr instance #1, create file called `zephyr1.conf` to net-tools project, or to some other suitable directory.

```
# Configuration file for setting IP addresses for a network interface.
INTERFACE="$1"
HWADDR="00:00:5e:00:53:11"
IPV6_ADDR_1="2001:db8:100::2"
IPV6_ROUTE_1="2001:db8:100::/64"
IPV4_ADDR_1="198.51.100.2/24"
IPV4_ROUTE_1="198.51.100.0/24"
ip link set dev $INTERFACE up
ip link set dev $INTERFACE address $HWADDR
ip -6 address add $IPV6_ADDR_1 dev $INTERFACE nodad
ip -6 route add $IPV6_ROUTE_1 dev $INTERFACE
ip address add $IPV4_ADDR_1 dev $INTERFACE
ip route add $IPV4_ROUTE_1 dev $INTERFACE > /dev/null 2>&1
```

For Zephyr instance #2, create file called `zephyr2.conf` to net-tools project, or to some other suitable directory.

```
# Configuration file for setting IP addresses for a network interface.
INTERFACE="$1"
HWADDR="00:00:5e:00:53:22"
IPV6_ADDR_1="2001:db8:200::2"
IPV6_ROUTE_1="2001:db8:200::/64"
IPV4_ADDR_1="203.0.113.2/24"
```

(continues on next page)
Step 2 - Create Ethernet interfaces

The following net-setup.sh commands should be typed in net-tools directory (cd net-tools).

In terminal #1, type:

```
./net-setup.sh -c zephyr1.conf -i zeth.1
```

In terminal #2, type:

```
./net-setup.sh -c zephyr2.conf -i zeth.2
```

Step 3 - Setup network bridging

In terminal #3, type:

```
sudo brctl addbr zeth-br
sudo brctl addif zeth-br zeth.1
sudo brctl addif zeth-br zeth.2
sudo ifconfig zeth-br up
```

Step 4 - Start Zephyr instances

In this example we start sockets-echo-server and sockets-echo-client sample applications. You can use other applications too as needed.

In terminal #4, if you are using QEMU, type this:

```
w west build -d build/server -b qemu_x86 -t run \samples/net/sockets/echo_server -- \ -DEXTRA_CONF_FILE=overlay-e1000.conf \ -DCONFIG_NET_CONFIG_MY_IPV4_ADDR="198.51.100.1" \ -DCONFIG_NET_CONFIG_PEER_IPV4_ADDR="203.0.113.1" \ -DCONFIG_NET_CONFIG_MY_IPV6_ADDR="2001:db8:100::1" \ -DCONFIG_NET_CONFIG_PEER_IPV6_ADDR="2001:db8:200::1" \ -DCONFIG_NET_CONFIG_MY_IPV4_GW="203.0.113.1" \ -DCONFIG_ETH_QEMU_IFACE_NAME="zeth.1" \ -DCONFIG_ETH_QEMU_EXTRA_ARGS="mac=00:00:5e:00:53:01"
```

or if you want to use native_sim board, type this:

```
w west build -d build/server -b native_sim -t run \samples/net/sockets/echo_server -- \ -DCONFIG_NET_CONFIG_MY_IPV4_ADDR="198.51.100.1" \ -DCONFIG_NET_CONFIG_PEER_IPV4_ADDR="203.0.113.1" \ -DCONFIG_NET_CONFIG_MY_IPV6_ADDR="2001:db8:100::1" \ -DCONFIG_NET_CONFIG_PEER_IPV6_ADDR="2001:db8:200::1" \ -DCONFIG_NET_CONFIG_MY_IPV4_GW="203.0.113.1" \ -DCONFIG_ETH_NATIVE_POSIX_DRV_NAME="zeth.1" \ -DCONFIG_ETH_NATIVE_POSIX_MAC_ADDR="00:00:5e:00:53:01" \ -DCONFIG_ETH_NATIVE_POSIX_RANDOM_MAC=n
```

In terminal #5, if you are using QEMU, type this:
Networking with QEMU and IEEE 802.15.4

**Basic Setup**

- **Step 1 - Compile and start echo-server**
- **Step 2 - Compile and start echo-client**

This page describes how to set up a virtual network between two QEMUs that are connected together via UART and are running IEEE 802.15.4 link layer between them. Note that this only works in Linux host.

**Basic Setup**  For the steps below, you will need two terminal windows:

- Terminal #1 is terminal window with echo-server Zephyr sample application.
- Terminal #2 is terminal window with echo-client Zephyr sample application.

If you want to capture the transferred network data, you must compile the monitor_15_4 program in net-tools directory.

Open a terminal window and type:

```bash
cd $ZEPHYR_BASE/../net-tools
make monitor_15_4
```

**Step 1 - Compile and start echo-server**  In terminal #1, type:

```bash
west build -b qemu_x86 -d build/server samples/net/sockets/echo_server -- \
-DEXTRA_CONF_FILE=overlay-qemu_802154.conf \
-west build -t server -d build/server
```

or if you want to use native_sim board, type this:

```bash
west build -d build/client -b native_sim -t run \
samples/net/sockets/echo_client -- \
-DEXTRA_CONF_FILE=overlay-e1000.conf \
-DCONFIG_NET_CONFIG_MY_IPV4_ADDR="203.0.113.1" \
-DCONFIG_NET_CONFIG_PEER_IPV4_ADDR="198.51.100.1" \
-DCONFIG_NET_CONFIG_MY_IPV6_ADDR="2001:db8:200::1" \
-DCONFIG_NET_CONFIG_PEER_IPV6_ADDR="2001:db8:100::1" \
-DCONFIG_NET_CONFIG_MY_IPV4_GW="198.51.100.1" \
-DCONFIG_ETH_QEMU_IFACE_NAME="zeth.2" \
-DCONFIG_ETH_QEMU_EXTRA_ARGS="mac=00:00:5e:00:53:02"
```

Also if you have firewall enabled in your host, you need to allow traffic between zeth.1, zeth.2 and zeth-br interfaces.

Networking with QEMU and IEEE 802.15.4

**Basic Setup**

For the steps below, you will need two terminal windows:

- Terminal #1 is terminal window with echo-server Zephyr sample application.
- Terminal #2 is terminal window with echo-client Zephyr sample application.

If you want to capture the transferred network data, you must compile the monitor_15_4 program in net-tools directory.

Open a terminal window and type:

```bash
 cd $ZEPHYR_BASE/../net-tools
 make monitor_15_4
```

**Step 1 - Compile and start echo-server**  In terminal #1, type:

```bash
 west build -b qemu_x86 -d build/server samples/net/sockets/echo_server -- \
 -DEXTRA_CONF_FILE=overlay-qemu_802154.conf \
 west build -t server -d build/server
```
If you want to capture the network traffic between the two QEMUs, type:

```
west build -b qemu_x86 -d build/server samples/net/sockets/echo_server -- -G'Unix Makefiles
-DEXTRA_CONF_FILE=overlay-qemu_802154.conf -DPCAP=capture.pcap
west build -t server -d build/server
```

Note that the make must be used for server target if packet capture option is set in command line. The build/server/capture.pcap file will contain the transferred data.

**Step 2 - Compile and start echo-client**  In terminal #2, type:

```
west build -b qemu_x86 -d build/client samples/net/sockets/echo_client -- -DEXTRA_CONF_FILE=overlay-qemu_802154.conf
west build -t client -d build/client
```

You should see data passed between the two QEMUs. Exit QEMU by pressing CTRL+A x.

### Networking with Arm FVP User Mode

- **Introduction**
- **Using Arm FVP User Mode Networking with Zephyr**
- **Limitations**

This page is intended to serve as a starting point for anyone interested in using Arm FVP user mode networking with Zephyr.

**Introduction**  User mode networking emulates a built-in IP router and DHCP server, and routes TCP and UDP traffic between the guest and host. It uses the user mode socket layer of the host to communicate with other hosts. This allows the use of a significant number of IP network services without requiring administrative privileges, or the installation of a separate driver on the host on which the model is running.

By default, Arm FVP uses the 172.20.51.0/24 network and runs a gateway at 172.20.51.254. This gateway also functions as a DHCP server for the GOS, allowing it to be automatically assigned with an IP address 172.20.51.1.


**Using Arm FVP User Mode Networking with Zephyr**  Arm FVP user mode networking can be enabled in any applications and it doesn’t need any configurations on the host system. This feature has been enabled in DHCPv4 client sample. See dhcpv4-client sample application.

**Limitations**

- You can use TCP and UDP over IP, but not ICMP (ping).
- User mode networking does not support forwarding UDP ports on the host to the model.
- You can only use DHCP within the private network.
- You can only make inward connections by mapping TCP ports on the host to the model. This is common to all implementations that provide host connectivity using NAT.
- Operations that require privileged source ports, for example NFS in its default configuration, do not work.
• If setup fails, or the parameter syntax is incorrect, there is no error reporting.

While developing networking software, it is usually necessary to connect and exchange data with the host system like a Linux desktop computer. Depending on what board is used for development, the following options are possible:

• QEMU using SLIP (Serial Line Internet Protocol).
  – Here IP packets are exchanged between Zephyr and the host system via serial port. This is the legacy way of transferring data. It is also quite slow so use it only when necessary. See Networking with QEMU for details.

• QEMU using built-in Ethernet driver.
  – Here IP packets are exchanged between Zephyr and the host system via QEMU’s built-in Ethernet driver. Not all QEMU boards support built-in Ethernet so in some cases, you might need to use the SLIP method for host connectivity. See Networking with QEMU Ethernet for details.

• QEMU using SLIRP (Qemu User Networking).
  – QEMU User Networking is implemented using “slirp”, which provides a full TCP/IP stack within QEMU and uses that stack to implement a virtual NAT’d network. As this support is built into QEMU, it can be used with any model and requires no admin privileges on the host machine, unlike TAP. However, it has several limitations including performance which makes it less valuable for practical purposes. See Networking with QEMU User for details.

• Arm FVP (User Mode Networking).
  – User mode networking emulates a built-in IP router and DHCP server, and routes TCP and UDP traffic between the guest and host. It uses the user mode socket layer of the host to communicate with other hosts. This allows the use of a significant number of IP network services without requiring administrative privileges, or the installation of a separate driver on the host on which the model is running. See Networking with Arm FVP User Mode for details.

• native_sim board.
  – The Zephyr instance can be executed as a user space process in the host system. This is the most convenient way to debug the Zephyr system as one can attach host debugger directly to the running Zephyr instance. This requires that there is an adaptation driver in Zephyr for interfacing with the host system. An Ethernet driver exists in Zephyr for this purpose. See Networking with native_sim board for details.

• USB device networking.
  – Here, the Zephyr instance is run on a real board and the connectivity to the host system is done via USB. See USB Device Networking for details.

• Connecting multiple Zephyr instances together.
  – If you have multiple Zephyr instances, either QEMU or native_sim ones, and want to create a connection between them, see Networking with multiple Zephyr instances for details.

• Simulating IEEE 802.15.4 network between two QEMUs.
  – Here, two Zephyr instances are running and there is IEEE 802.15.4 link layer run over an UART between them. See Networking with QEMU and IEEE 802.15.4 for details.

6.3.5 Monitor Network Traffic
It is useful to be able to monitor the network traffic especially when debugging a connectivity issues or when developing new protocol support in Zephyr. This page describes how to set up a way to capture network traffic so that user is able to use Wireshark or similar tool in remote host to see the network packets sent or received by a Zephyr device.

See also the net-capture sample application from the Zephyr source distribution for configuration options that need to be enabled.

**Host Configuration**

The instructions here describe how to setup a Linux host to capture Zephyr network RX and TX traffic. Similar instructions should work also in other operating systems. On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:

```
git clone https://github.com/zephyrproject-rtos/net-tools
```

The net-tools project provides a configure file to setup IP-to-IP tunnel interface so that we can transfer monitoring data from Zephyr to host.

In terminal #1, type:

```
./net-setup.sh -c zeth-tunnel.conf
```

This script will create following IPIP tunnel interfaces:

<table>
<thead>
<tr>
<th>Interface name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>zeth-ip6ip</td>
<td>IPv6-over-IP4 tunnel</td>
</tr>
<tr>
<td>zeth-ipip</td>
<td>IPv4-over-IP4 tunnel</td>
</tr>
<tr>
<td>zeth-ipip6</td>
<td>IPv4-over-IP6 tunnel</td>
</tr>
<tr>
<td>zeth-ip6ip6</td>
<td>IPv6-over-IP6 tunnel</td>
</tr>
</tbody>
</table>

Zephyr will send captured network packets to one of these interfaces. The actual interface will depend on how the capturing is configured. You can then use Wireshark to monitor the proper network interface.

After the tunneling interfaces have been created, you can use for example `net-capture.py` script from net-tools project to print or save the captured network packets. The `net-capture.py` provides an UDP listener, it can print the captured data to screen and optionally can also save the data to a pcap file.

```
$ ./net-capture.py -i zeth-ip6ip -w capture.pcap
```

The `net-capture.py` has following command line options:
Listen captured network data from Zephyr and save it optionally to pcap file.

```
./net-capture.py \
  -i | --interface <network interface>  
      Listen this interface for the data
[-p | --port <UDP port>]  
      UDP port (default is 4242) where the capture data is received
[-q | --quiet]  
      Do not print packet information
[-t | --type <L2 type of the data>]  
      Scapy L2 type name of the UDP payload, default is Ether
[-w | --write <pcap file name>]  
      Write the received data to file in PCAP format
```

Instead of the `net-capture.py` script, you can for example use `netcat` to provide an UDP listener so that the host will not send port unreachable message to Zephyr:

```
nc -l -u 2001:db8:200::2 4242 > /dev/null
```

The IP address above is the inner tunnel endpoint, and can be changed and it depends on how the Zephyr is configured. Zephyr will send UDP packets containing the captured network packets to the configured IP tunnel, so we need to terminate the network connection like this.

### Zephyr Configuration

In this example, we use the `native_sim` board. You can also use any other board that supports networking.

In terminal #3, type:

```
west build -b native_sim samples/net/capture -- -DCONFIG_NATIVE_UART_AUTOATTACH_DEFAULT=true  
  --CMD="gnome-terminal -- screen %s"
```

To see the Zephyr console and shell, start Zephyr instance like this:

```
build/zephyr/zephyr.exe -attach_uart
```

Any other application can be used too, just make sure that suitable configuration options are enabled (see `samples/net/capture/prj.conf` file for examples).

The network capture can be configured automatically if needed, but currently the sample application does not do that. User has to use `net-shell` to setup and enable the monitoring.

The network packet monitoring needs to be setup first. The `net-shell` has `net capture setup` command for doing that. The command syntax is

```
net capture setup <remote-ip-addr> <local-ip-addr> <peer-ip-addr>  
  <remote> is the (outer) endpoint IP address  
  <local> is the (inner) local IP address  
  <peer> is the (inner) peer IP address  
Local and Peer IP addresses can have UDP port number in them (optional)  
like 198.0.51.2:9000 or [2001:db8:100::2]:4242
```

In Zephyr console, type:

```
net capture setup 192.0.2.2 2001:db8:200::1 2001:db8:200::2
```

This command will create the tunneling interface. The 192.0.2.2 is the remote host where the tunnel is terminated. The address is used to select the local network interface where the tunneling interface is attached to. The 2001:db8:200::1 tells the local IP address for the tunnel, the 2001:db8:200::2 is the peer IP address where the captured network packets are sent. The port numbers for UDP packet can be given in the setup command like this for IPv6-over-IPv4 tunneling.
net capture setup 192.0.2.2 [2001:db8:200::1]:9999 [2001:db8:200::2]:9998

and like this for IPv4-over-IPv4 tunnel

net capture setup 192.0.2.2 198.51.100.1:9999 198.51.100.2:9998

If the port number is omitted, then 4242 UDP port is used as a default.

The current monitoring configuration can be checked like this:

<table>
<thead>
<tr>
<th>Device</th>
<th>Capture</th>
<th>Tunnel</th>
</tr>
</thead>
<tbody>
<tr>
<td>NET_CAPTURE0</td>
<td>-</td>
<td>1 [2001:db8:200::1]:4242 [2001:db8:200::2]:4242</td>
</tr>
</tbody>
</table>

which will print the current configuration. As we have not yet enabled monitoring, the Capture iface is not set.

Then we need to enable the network packet monitoring like this:

```
net capture enable 2
```

The 2 tells the network interface which traffic we want to capture. In this example, the 2 is the native_sim board Ethernet interface. Note that we send the network traffic to the same interface that we are monitoring in this example. The monitoring system avoids to capture already captured network traffic as that would lead to recursion. You can use net iface command to see what network interfaces are available. Note that you cannot capture traffic from the tunnel interface as that would cause recursion loop. The captured network traffic can be sent to some other network interface if configured so. Just set the <remote-ip-addr> option properly in net capture setup so that the IP tunnel is attached to desired network interface. The capture status can be checked again like this:

```
net capture
```

After enabling the monitoring, the system will send captured (either received or sent) network packets to the tunnel interface for further processing.

The monitoring can be disabled like this:

```
net capture disable
```

which will turn currently running monitoring off. The monitoring setup can be cleared like this:

```
net capture cleanup
```

It is not necessary to use net-shell for configuring the monitoring. The network capture API functions can be called by the application if needed.

**Wireshark Configuration**

The Wireshark tool can be used to monitor the captured network traffic in a useful way.

You can monitor either the tunnel interfaces or the zeth interface. In order to see the actual captured data inside an UDP packet, see Wireshark decapsulate UDP document for instructions.
Zephyr provides support for the standard BSD socket APIs (defined in `include/zephyr/net/socket.h`) for the applications to use. See BSD socket API for more details.

Apart of the standard API, Zephyr provides a set of custom networking APIs and libraries for the application to use. See the list below for details.

**Note:** The legacy connectivity API in `include/zephyr/net/net_context.h` should not be used by applications.

### Network APIs

**BSD Sockets**

- **Overview**
- **Secure Sockets**
  - TLS credentials subsystem
  - Secure Socket Creation
  - Secure Sockets options
- **Socket offloading**
  - Offloaded socket creation
  - Dealing with multiple offloaded interfaces
- **API Reference**
  - BSD Sockets
  - TLS Credentials

---

**Overview**  Zephyr offers an implementation of a subset of the BSD Sockets API (a part of the POSIX standard). This API allows to reuse existing programming experience and port existing simple networking applications to Zephyr.

Here are the key requirements and concepts which governed BSD Sockets compatible API implementation for Zephyr:

- Has minimal overhead, similar to the requirement for other Zephyr subsystems.
- Is namedpaced by default, to avoid name conflicts with well-known names like `close()`, which may be part of libc or other POSIX compatibility libraries. If enabled by `CONFIG_NET_SOCKETS_POSIX_NAMES`, it will also expose native POSIX names.

BSD Sockets compatible API is enabled using `CONFIG_NET_SOCKETS` config option and implements the following operations: `socket()`, `close()`, `recv()`, `recvfrom()`, `send()`, `sendto()`, `connect()`, `bind()`, `listen()`, `accept()`, `fcntl()`, `getsockopt()`, `setsockopt()`, `poll()`, `select()`, `getaddrinfo()`, `getnameinfo()`.

Based on the namespacing requirements above, these operations are by default exposed as functions with `zsock_` prefix, e.g. `zsock_socket()` and `zsock_close()`. If the config option `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined, all the functions will be also exposed as aliases without the prefix. This includes the functions like `close()` and `fcntl()` (which may conflict with functions in libc or other libraries, for example, with the filesystem libraries).
Another entailment of the design requirements above is that the Zephyr API aggressively employs the short-read/short-write property of the POSIX API whenever possible (to minimize complexity and overheads). POSIX allows for calls like `recv()` and `send()` to actually process (receive or send) less data than requested by the user (on SOCK_STREAM type sockets). For example, a call `recv(sock, 1000, 0)` may return 100, meaning that only 100 bytes were read (short read), and the application needs to retry call(s) to receive the remaining 900 bytes.

The BSD Sockets API uses file descriptors to represent sockets. File descriptors are small integers, consecutively assigned from zero, shared among sockets, files, special devices (like stdin/stdout), etc. Internally, there is a table mapping file descriptors to internal object pointers. The file descriptor table is used by the BSD Sockets API even if the rest of the POSIX subsystem (filesystem, stdin/stdout) is not enabled.

See sockets-echo-server and sockets-echo-client sample applications to learn how to create a simple server or client BSD socket based application.

**Secure Sockets** Zephyr provides an extension of standard POSIX socket API, allowing to create and configure sockets with TLS protocol types, facilitating secure communication. Secure functions for the implementation are provided by mbedTLS library. Secure sockets implementation allows use of both TLS and DTLS protocols with standard socket calls. See `net_ip_protocol_secure` type for supported secure protocol versions.

To enable secure sockets, set the `CONFIG_NET_SOCKETS_SOCKOPT_TLS` option. To enable DTLS support, use `CONFIG_NET_SOCKETS_ENABLE_DTLS` option.

**TLS credentials subsystem** TLS credentials must be registered in the system before they can be used with secure sockets. See `tls_credential_add()` for more information.

When a specific TLS credential is registered in the system, it is assigned with numeric value of type `sec_tag_t`, called a tag. This value can be used later on to reference the credential during secure socket configuration with socket options.

The following TLS credential types can be registered in the system:

- `TLS_CREDENTIAL_CA_CERTIFICATE`
- `TLS_CREDENTIAL_SERVER_CERTIFICATE`
- `TLS_CREDENTIAL_PRIVATE_KEY`
- `TLS_CREDENTIAL_PSK`
- `TLS_CREDENTIAL_PSK_ID`

An example registration of CA certificate (provided in `ca_certificate` array) looks like this:

```c
ret = tls_credential_add(CA_CERTIFICATE_TAG, TLS_CREDENTIAL_CA_CERTIFICATE, ca_certificate, sizeof(ca_certificate));
```

By default certificates in DER format are supported. PEM support can be enabled in mbedTLS settings.

**Secure Socket Creation** A secure socket can be created by specifying secure protocol type, for instance:

```c
sock = socket(AF_INET, SOCK_STREAM, IPPROTO_TLS_1_2);
```

Once created, it can be configured with socket options. For instance, the CA certificate and hostname can be set:
Once configured, socket can be used just like a regular TCP socket.

Several samples in Zephyr use secure sockets for communication. For a sample use see e.g. echo-server sample application or HTTP GET sample application.

**Secure Sockets options** Secure sockets offer the following options for socket management:

Related code samples

**HTTP GET using plain sockets**
Implement an HTTP(S) client using plain BSD sockets.

**HTTP client**
Implement an HTTP(S) client that issues a variety of HTTP requests.

---

**group secure_sockets_options**

**Socket options for TLS**

**SOL_TLS**
Protocol level for TLS.
Here, the same socket protocol level for TLS as in Linux was used.

**TLS_SEC_TAG_LIST**
Socket option to select TLS credentials to use.
It accepts and returns an array of sec_tag_t that indicate which TLS credentials should be used with specific socket.

**TLS_HOSTNAME**
Write-only socket option to set hostname.
It accepts a string containing the hostname (may be NULL to disable hostname verification). By default, hostname check is enforced for TLS clients.

**TLS_CIPHERSUITE_LIST**
Socket option to select ciphersuites to use.
It accepts and returns an array of integers with IANA assigned ciphersuite identifiers. If not set, socket will allow all ciphersuites available in the system (mbedTLS default behavior).
TLS_CIPHERSUITE_USED
Read-only socket option to read a ciphersuite chosen during TLS handshake.
It returns an integer containing an IANA assigned ciphersuite identifier of chosen ciphersuite.

TLS_PEER_VERIFY
Write-only socket option to set peer verification level for TLS connection.
This option accepts an integer with a peer verification level, compatible with mbedTLS values:
• 0 - none
• 1 - optional
• 2 - required
If not set, socket will use mbedTLS defaults (none for servers, required for clients).

TLS_DTLS_ROLE
Write-only socket option to set role for DTLS connection.
This option is irrelevant for TLS connections, as for them role is selected based on connect()/listen() usage. By default, DTLS will assume client role. This option accepts an integer with a TLS role, compatible with mbedTLS values:
• 0 - client
• 1 - server

TLS_ALPN_LIST
Socket option for setting the supported Application Layer Protocols.
It accepts and returns a const char array of NULL terminated strings representing the supported application layer protocols listed during the TLS handshake.

TLS_DTLS_HANDSHAKE_TIMEOUT_MIN
Socket option to set DTLS min handshake timeout.
The timeout starts at min, and upon retransmission the timeout is doubled until max is reached. Min and max arguments are separate options. The time unit is ms.

TLS_DTLS_HANDSHAKE_TIMEOUT_MAX
Socket option to set DTLS max handshake timeout.
The timeout starts at min, and upon retransmission the timeout is doubled until max is reached. Min and max arguments are separate options. The time unit is ms.

TLS_CERT_NOCOPY
Socket option for preventing certificates from being copied to the mbedTLS heap if possible.
The option is only effective for DER certificates and is ignored for PEM certificates.

TLS_NATIVE
TLS socket option to use with offloading.
The option instructs the network stack only to offload underlying TCP/UDP communication. The TLS/DTLS operation is handled by a native TLS/DTLS socket implementation from Zephyr.
Note, that this option is only applicable if socket dispatcher is used (CON-
FIG_NET_SOCKETS_OFFLOAD_DISPATCHER is enabled). In such case, it should be the
first socket option set on a newly created socket. After that, the application may
use SO_BINDTODEVICE to choose the dedicated network interface for the underlying
TCP/UDP socket.

**TLS_SESSION_CACHE**

Socket option to control TLS session caching on a socket.

Accepted values:

- 0 - Disabled.
- 1 - Enabled.

**TLS_SESSION_CACHE_PURGE**

Write-only socket option to purge session cache immediately.

This option accepts any value.

**TLS_DTLS_CID**

Write-only socket option to control DTLS CID.

The option accepts an integer, indicating the setting. Accepted values for the option
are: 0, 1 and 2. Effective when set before connecting to the socket.

- 0 - DTLS CID will be disabled.
- 1 - DTLS CID will be enabled, and a 0 length CID value to be sent to the peer.
- 2 - DTLS CID will be enabled, and the most recent value set with
TLS_DTLS_CID_VALUE will be sent to the peer. Otherwise, a random value
will be used.

**TLS_DTLS_CID_STATUS**

Read-only socket option to get DTLS CID status.

The option accepts a pointer to an integer, indicating the setting upon return. Returned
vaules for the option are:

- 0 - DTLS CID is disabled.
- 1 - DTLS CID is received on the downlink.
- 2 - DTLS CID is sent to the uplink.
- 3 - DTLS CID is used in both directions.

**TLS_DTLS_CID_VALUE**

Socket option to set or get the value of the DTLS connection ID to be used for the DTLS
session.

The option accepts a byte array, holding the CID value.

**TLS_DTLS_PEER_CID_VALUE**

Read-only socket option to get the value of the DTLS connection ID received from the
peer.

The option accepts a pointer to a byte array, holding the CID value upon return. The
optlen returned will be 0 if the peer did not provide a connection ID, otherwise will
contain the length of the CID value.
**TLS_DTLS_HANDSHAKE_ON_CONNECT**

Socket option to configure DTLS socket behavior on `connect()`. If set, DTLS `connect()` will execute the handshake with the configured peer. This is the default behavior. Otherwise, DTLS `connect()` will only configure peer address (as with regular UDP socket) and will not attempt to execute DTLS handshake. The handshake will take place in consecutive `send()`/`recv()` call.

**TLS_PEER_VERIFY_NONE**

Peer verification disabled.

**TLS_PEER_VERIFY_OPTIONAL**

Peer verification optional.

**TLS_PEER_VERIFY_REQUIRED**

Peer verification required.

**TLS_DTLS_ROLE_CLIENT**

Client role in a DTLS session.

**TLS_DTLS_ROLE_SERVER**

Server role in a DTLS session.

**TLS_CERT_NOCOPY_NONE**

Cert duplicated in heap.

**TLS_CERT_NOCOPY_OPTIONAL**

Cert not copied in heap if DER.

**TLS_SESSION_CACHE_DISABLED**

Disable TLS session caching.

**TLS_SESSION_CACHE_ENABLED**

Enable TLS session caching.

**TLS_DTLS_CID_DISABLED**

CID is disabled

**TLS_DTLS_CID_SUPPORTED**

CID is supported.

**TLS_DTLS_CID_ENABLED**

CID is enabled

**TLS_DTLS_CID_STATUS_DISABLED**

CID is disabled.

**TLS_DTLS_CID_STATUS_DOWNLINK**

CID is in use by us.
TLS_DTLS_CID_STATUS_UPLINK
CID is in use by peer.

TLS_DTLS_CID_STATUS_BIDIRECTIONAL
CID is in use by us and peer.

**Socket offloading** Zephyr allows to register custom socket implementations (called offloaded sockets). This allows for seamless integration for devices which provide an external IP stack and expose socket-like API.

Socket offloading can be enabled with `CONFIG_NET_SOCKETS_OFFLOAD` option. A network driver that wants to register a new socket implementation should use `NET_SOCKET_OFFLOAD_REGISTER` macro. The macro accepts the following parameters:

- **socket_name**
  An arbitrary name for the socket implementation.

- **prio**
  Socket implementation's priority. The higher the priority, the earlier this particular implementation will be processed when creating a new socket. Lower numeric value indicates higher priority.

- **_family**
  Socket family implemented by the offloaded socket. `AF_UNSPEC` indicates any family.

- **_is_supported**
  A filtering function, used to verify whether a particular socket family, type and protocol are supported by the offloaded socket implementation.

- **_handler**
  A function compatible with `socket()` API, used to create an offloaded socket.

Every offloaded socket implementation should also implement a set of socket APIs, specified in `socket_op_vtable` struct.

The function registered for socket creation should allocate a new file descriptor using `z_reserve_fd()` function. Any additional actions, specific to the creation of a particular offloaded socket implementation should take place after the file descriptor is allocated. As a final step, if the offloaded socket was created successfully, the file descriptor should be finalized with `z_finalize_fd()` function. The finalize function allows to register a `socket_op_vtable` structure implementing socket APIs for an offloaded socket along with an optional socket context data pointer.

Finally, when an offloaded network interface is initialized, it should indicate that the interface is offloaded with `net_if_socket_offload_set()` function. The function registers the function used to create an offloaded socket (the same as the one provided in `NET_SOCKET_OFFLOAD_REGISTER`) at the network interface.

**Offloaded socket creation** When application creates a new socket with `socket()` function, the network stack iterates over all registered socket implementations (native and offloaded). Higher priority socket implementations are processed first. For each registered socket implementation, an address family is verified, and if it matches (or the socket was registered as `AF_UNSPEC`), the corresponding `_is_supported` function is called to verify the remaining socket parameters. The first implementation that fulfills the socket requirements (i.e. `_is_supported` returns true) will create a new socket with its `_handler` function.

The above indicates the importance of the socket priority. If multiple socket implementations support the same set of socket family/type/protocol, the first implementation processed by the system will create a socket. Therefore it's important to give the highest priority to the implementation that should be the system default.
The socket priority for native socket implementation is configured with Kconfig. Use CONFIG_NET_SOCKETS_TLS_PRIORITY to set the priority for the native TLS sockets. Use CONFIG_NET_SOCKETS_PRIORITY_DEFAULT to set the priority for the remaining native sockets.

**Dealing with multiple offloaded interfaces**  As the socket() function does not allow to specify which network interface should be used by a socket, it's not possible to choose a specific implementation in case multiple offloaded socket implementations, supporting the same type of sockets, are available. The same problem arises when both native and offloaded sockets are available in the system.

To address this problem, a special socket implementation (called socket dispatcher) was introduced. The sole reason for this module is to postpone the socket creation for until the first operation on a socket is performed. This leaves an opening to use SO_BINDTODEVICE socket option, to bind a socket to a particular network interface (and thus offloaded socket implementation). The socket dispatcher can be enabled with CONFIG_NET_SOCKETS_OFFLOAD_DISPATCHER Kconfig option.

When enabled, the application can specify the network interface to use with setsockopt() function:

```c
/* A "dispatcher" socket is created */
sock = socket(AF_INET, SOCK_DGRAM, IPPROTO_UDP);

struct ifreq ifreq = {
    .ifr_name = "SimpleLink"
};

/* The socket is "dispatched" to a particular network interface
   *(offloaded or not). */
setsockopt(sock, SOL_SOCKET, SO_BINDTODEVICE, &ifreq, sizeof(ifreq));
```

Similarly, if TLS is supported by both native and offloaded sockets, TLS_NATIVE socket option can be used to indicate that a native TLS socket should be created. The underlying socket can then be bound to a particular network interface:

```c
/* A "dispatcher" socket is created */
sock = socket(AF_INET, SOCK_STREAM, IPPROTO_TLS_1_2);

int tls_native = 1;

/* The socket is "dispatched" to a native TLS socket implementation.
   * The underlying socket is a "dispatcher" socket now. */
setsockopt(sock, SOL_TLS, TLS_NATIVE, &tls_native, sizeof(tls_native));

struct ifreq ifreq = {
    .ifr_name = "SimpleLink"
};

/* The underlying socket is "dispatched" to a particular network interface
   *(offloaded or not). */
setsockopt(sock, SOL_SOCKET, SO_BINDTODEVICE, &ifreq, sizeof(ifreq));
```

In case no SO_BINDTODEVICE socket option is used on a socket, the socket will be dispatched according to the default priority and filtering rules on a first socket API call.

**API Reference**
BSD Sockets

Related code samples

AWS IoT Core MQTT
Connect to AWS IoT Core and publish messages using MQTT.

Asynchronous echo server using poll()
Implement an asynchronous IPv4/IPv6 TCP echo server using BSD sockets and poll().

Asynchronous echo server using select()
Implement an asynchronous IPv4/IPv6 TCP echo server using BSD sockets and select().

Dumb HTTP server
Implement a simple, portable, HTTP server using BSD sockets.

Dumb HTTP server (multi-threaded)
Implement a simple HTTP server supporting simultaneous connections using BSD sockets.

Echo client (advanced)
Implement a client that sends IP packets, waits for data to be sent back, and verifies it.

Echo server (advanced)
Implement a UDP/TCP server that sends received packets back to the sender.

Echo server (service)
Implements a simple IPv4/IPv6 TCP echo server using BSD sockets and socket service API.

Echo server (simple)
Implements a simple IPv4/IPv6 TCP echo server using BSD sockets.

HTTP GET using plain sockets
Implement an HTTP(S) client using plain BSD sockets.

HTTP client
Implement an HTTP(S) client that issues a variety of HTTP requests.

Large HTTP download
Download a large file from a web server using BSD sockets.

Microsoft Azure IoT Hub MQTT
Connect to Azure IoT Hub and publish messages using MQTT.

Modbus TCP server
Implement a Modbus TCP server exposing Modbus commands to control LEDs.

Modbus TCP-to-serial gateway
Implement a gateway between an Ethernet TCP-IP network and a Modbus serial line.

Network management socket
Listen to network management events using a network management socket.

Packet socket
Use raw packet sockets over Ethernet.

SNTP client
Use SNTP to get the current time from the host.

SocketCAN
Send and receive raw CAN frames using BSD sockets API.

Socketpair
Implement communication between threads using socket pairs.

TCP sample for TTCN-3 based sanity check
Use TTCN-3 to validate the functionality of the TCP stack.

TagoIO HTTP Post
Send random temperature values to TagoIO IoT Cloud Platform using HTTP.
UDP sender using SO_TXTIME
   Control the transmission time of a packet using SO_TXTIME socket option.

Video TCP server sink
   Capture video frames and send them over the network to a TCP client.

WebSocket Client
   Implement a Websocket client that connects to a Websocket server.

mDNS responder
   Listen and respond to mDNS queries.

---

group bsd_sockets
   BSD Sockets compatible API.

Socket APIs available if CONFIG_NET_SOCKETS_POSIX_NAMES is enabled

static inline int socket(int family, int type, int proto)
   POSIX wrapper for zsock_socket.

static inline int socketpair(int family, int type, int proto, int sv[2])
   POSIX wrapper for zsock_socketpair.

static inline int close(int sock)
   POSIX wrapper for zsock_close.

static inline int shutdown(int sock, int how)
   POSIX wrapper for zsock_shutdown.

static inline int bind(int sock, const struct sockaddr *addr, socklen_t addrlen)
   POSIX wrapper for zsock_bind.

static inline int connect(int sock, const struct sockaddr *addr, socklen_t addrlen)
   POSIX wrapper for zsock_connect.

static inline int listen(int sock, int backlog)
   POSIX wrapper for zsock_listen.

static inline int accept(int sock, struct sockaddr *addr, socklen_t *addrlen)
   POSIX wrapper for zsock_accept.

static inline ssize_t send(int sock, const void *buf, size_t len, int flags)
   POSIX wrapper for zsock_send.

static inline ssize_t sendto(int sock, const void *buf, size_t len, int flags, const struct sockaddr *dest_addr, socklen_t addrlen)
   POSIX wrapper for zsock_sendto.

static inline ssize_t sendmsg(int sock, const struct msghdr *message, int flags)
   POSIX wrapper for zsock_sendmsg.

static inline ssize_t recvfrom(int sock, void *buf, size_t max_len, int flags, struct sockaddr *src_addr, socklen_t *addrlen)
   POSIX wrapper for zsock_recvfrom.
static inline ssize_t recvmsg(int sock, struct msghdr *msg, int flags)
    POSIX wrapper for zsock_recvmsg.
static inline int poll(struct zsock_pollfd *fds, int nfds, int timeout)
    POSIX wrapper for zsock_poll.
static inline int getsockopt(int sock, int level, int optname, void *optval, socklen_t *optlen)
    POSIX wrapper for zsock_getsockopt.
static inline int setsockopt(int sock, int level, int optname, const void *optval, socklen_t optlen)
    POSIX wrapper for zsock_setsockopt.
static inline int getpeername(int sock, struct sockaddr *addr, socklen_t *addrlen)
    POSIX wrapper for zsock_getpeername.
static inline int getsockname(int sock, struct sockaddr *addr, socklen_t *addrlen)
    POSIX wrapper for zsock_getsockname.
static inline int getaddrinfo(const char *host, const char *service, const struct zsock_addrinfo *hints, struct zsock_addrinfo **res)
    POSIX wrapper for zsock_getaddrinfo.
static inline void freeaddrinfo(struct zsock_addrinfo *ai)
    POSIX wrapper for zsock_freeaddrinfo.
static inline const char *gai_strerror(int errcode)
    POSIX wrapper for zsock_gai_strerror.
static inline int getnameinfo(const struct sockaddr *addr, socklen_t addrlen, char *host, socklen_t hostlen, char *serv, socklen_t servlen, int flags)
    POSIX wrapper for zsock_getnameinfo.
static inline int gethostname(char *buf, size_t len)
    POSIX wrapper for zsock_gethostname.
static inline int inet_pton(sa_family_t family, const char *src, void *dst)
    POSIX wrapper for zsock_inet_pton.
static inline char *inet_ntop(sa_family_t family, const void *src, char *dst, size_t size)
    POSIX wrapper for zsock_inet_ntop.

pollfd
    POSIX wrapper for zsock_pollfd.
addrrinfo
    POSIX wrapper for zsock_addrrinfo.

POLLIN
    POSIX wrapper for ZSOCK_POLLIN.
POLLOUT
    POSIX wrapper for ZSOCK_POLLOUT.
POLLERR
    POSIX wrapper for ZSOCK_POLLERR.
POLLHUP
   POSIX wrapper for ZSOCK_POLLHUP.

POLLNVAL
   POSIX wrapper for ZSOCK_POLLNVAL.

MSG_PEEK
   POSIX wrapper for ZSOCK_MSG_PEEK.

MSG_CTRUNC
   POSIX wrapper for ZSOCK_MSG_CTRUNC.

MSG_TRUNC
   POSIX wrapper for ZSOCK_MSG_TRUNC.

MSG_DONTWAIT
   POSIX wrapper for ZSOCK_MSG_DONTWAIT.

MSG_WAITALL
   POSIX wrapper for ZSOCK_MSG_WAITALL.

SHUT_RD
   POSIX wrapper for ZSOCK_SHUT_RD.

SHUT_WR
   POSIX wrapper for ZSOCK_SHUT_WR.

SHUT_RDWR
   POSIX wrapper for ZSOCK_SHUT_RDWR.

EAI_BADFLAGS
   POSIX wrapper for DNS_EAI_BADFLAGS.

EAI_NONAME
   POSIX wrapper for DNS_EAI_NONAME.

EAI_AGAIN
   POSIX wrapper for DNS_EAI_AGAIN.

EAI_FAIL
   POSIX wrapper for DNS_EAI_FAIL.

EAI_NODATA
   POSIX wrapper for DNS_EAI_NODATA.

EAI_MEMORY
   POSIX wrapper for DNS_EAI_MEMORY.
EAI_SYSTEM
    POSIX wrapper for DNS_EAI_SYSTEM.

EAI_SERVICE
    POSIX wrapper for DNS_EAI_SERVICE.

EAI_SOCKTYPE
    POSIX wrapper for DNS_EAI_SOCKTYPE.

EAI_FAMILY
    POSIX wrapper for DNS_EAI_FAMILY.

Options for poll()

ZSOCK_POLLIN
    zsock_poll: Poll for readability

ZSOCK_POLLPRI
    zsock_poll: Poll for exceptional condition

ZSOCK_POLLOUT
    zsock_poll: Poll for writability

ZSOCK_POLLERR
    zsock_poll: Poll results in error condition (output value only)

ZSOCK_POLLHUP
    zsock_poll: Poll detected closed connection (output value only)

ZSOCK_POLLNVAL
    zsock_poll: Invalid socket (output value only)

Options for sending and receiving data

ZSOCK_MSG_PEEK
    zsock_recv: Read data without removing it from socket input queue

ZSOCK_MSG_CTRUNC
    zsock_recvmsg: Control data buffer too small.

ZSOCK_MSG_TRUNC
    zsock_recv: return the real length of the datagram, even when it was longer than the passed buffer

ZSOCK_MSG_DONTWAIT
    zsock_recv/zsock_send: Override operation to non-blocking
ZSOCK_MSG_WAITALL
    zsock_recv: block until the full amount of data can be returned

Options for shutdown() function

ZSOCK_SHUT_RD
    zsock_shutdown: Shut down for reading

ZSOCK_SHUT_WR
    zsock_shutdown: Shut down for writing

ZSOCK_SHUT_RDWR
    zsock_shutdown: Shut down for both reading and writing

Flags for getaddrinfo() hints

AI_PASSIVE
    Address for bind() (vs for connect())

AI_CANONNAME
    Fill in ai_canonname.

AI_NUMERICHOST
    Assume host address is in numeric notation, don't DNS lookup.

AI_V4MAPPED
    May return IPv4 mapped address for IPv6

AI_ALL
    May return both native IPv6 and mapped IPv4 address for IPv6.

AI_ADDRCONFIG
    IPv4/IPv6 support depends on local system config.

AI_NUMERICSERV
    Assume service (port) is numeric.

Flags for getnameinfo()

NI_NUMERICHOST
    zsock_getnameinfo(): Resolve to numeric address.

NI_NUMERICSERV
    zsock_getnameinfo(): Resolve to numeric port number.
NI_NOFQDN
   zsock_getnameinfo(): Return only hostname instead of FQDN

NI_NAMEREQD
   zsock_getnameinfo(): Dummy option for compatibility

NI_DGRAM
   zsock_getnameinfo(): Dummy option for compatibility

NI_MAXHOST
   zsock_getnameinfo(): Max supported hostname length

Network interface name description

IFNAMSIZ
   Network interface name length.

Socket level options (SOL_SOCKET)

SOL_SOCKET
   Socket-level option.

SO_DEBUG
   Recording debugging information (ignored, for compatibility)

SO_REUSEADDR
   address reuse

SO_TYPE
   Type of the socket.

SO_ERROR
   Async error.

SO_DONTROUTE
   Bypass normal routing and send directly to host (ignored, for compatibility)

SO_BROADCAST
   Transmission of broadcast messages is supported (ignored, for compatibility)

SO_SNDBUF
   Size of socket send buffer.

SO_RCVBUF
   Size of socket recv buffer.
SO_KEEPALIVE
   Enable sending keep-alive messages on connections.

SO_OOBINLINE
   Place out-of-band data into receive stream (ignored, for compatibility)

SO_PRIORITY
   Socket priority.

SO_LINGER
   Socket lingers on close (ignored, for compatibility)

SO_REUSEPORT
   Allow multiple sockets to reuse a single port.

SO_RCVLOWAT
   Receive low watermark (ignored, for compatibility)

SO_SNDLOWAT
   Send low watermark (ignored, for compatibility)

SO_RCVTIMEO
   Receive timeout Applies to receive functions like recv(), but not to connect()

SO_SNDTIMEO
   Send timeout.

SO_BINDTODEVICE
   Bind a socket to an interface.

SO_ACCEPTCONN
   Socket accepts incoming connections (ignored, for compatibility)

SO_TIMESTAMPING
   Timestamp TX packets.

SO_PROTOCOL
   Protocol used with the socket.

SO_DOMAIN
   Domain used with SOCKET.

SO.SOCKS5
   Enable SOCKS5 for Socket.

SO_TXTIME
   Socket TX time (when the data should be sent)

SCM_TXTIME
   Socket TX time (same as SO_TXTIME)
TCP level options (IPPROTO_TCP)

TCP_NODELAY
Disable TCP buffering (ignored, for compatibility)

TCP_KEEPIDLE
Start keepalives after this period (seconds)

TCP_KEEPINTVL
Interval between keepalives (seconds)

TCP_KEEPCNT
Number of keepalives before dropping connection.

IPv4 level options (IPPROTO_IP)

IP_TOS
Set or receive the Type-Of-Service value for an outgoing packet.

IP_TTL
Set or receive the Time-To-Live value for an outgoing packet.

IP_PKTINFO
Pass an IP_PKTINFO ancillary message that contains a pktinfo structure that supplies some information about the incoming packet.

IP_MULTICAST_TTL
Set IPv4 multicast TTL value.

IP_ADD_MEMBERSHIP
Join IPv4 multicast group.

IP_DROP_MEMBERSHIP
Leave IPv4 multicast group.

IPv6 level options (IPPROTO_IPV6)

IPV6_UNICAST_HOPS
Set the unicast hop limit for the socket.

IPV6_MULTICAST_HOPS
Set the multicast hop limit for the socket.

IPV6_ADD_MEMBERSHIP
Join IPv6 multicast group.
IPV6_DROP_MEMBERSHIP
Leave IPv6 multicast group.

IPV6_V6ONLY
Don’t support IPv4 access.

IPV6_RECV_PKTINFO
Pass an IPV6_RECV_PKTINFO ancillary message that contains an in6_pktinfo structure that supplies some information about the incoming packet.
See RFC 3542.

IPV6_TCLASS
Set or receive the traffic class value for an outgoing packet.

Backlog size for listen()

SOMAXCONN
listen: The maximum backlog queue length

Defines

ZSOCK_FD_SETSIZE
Number of file descriptors which can be added to zsock_fd_set.

fd_set

FD_SETSIZE

zsock_timeval

Typedefs

typedef struct zsock_fd_set zsock_fd_set

Functions

void *zsock_get_context_object(int sock)
Obtain a file descriptor’s associated net context.

With CONFIG_USERSPACE enabled, the kernel’s object permission system must apply to socket file descriptors. When a socket is opened, by default only the caller has permission, access by other threads will fail unless they have been specifically granted permission.

This is achieved by tagging data structure definitions that implement the underlying object associated with a network socket file descriptor with ‘__net_socket’. All
pointers to instances of these will be known to the kernel as kernel objects with type
K_OBJ_NET_SOCKET.

This API is intended for threads that need to grant access to the object associated with
a particular file descriptor to another thread. The returned pointer represents the under-
lying K_OBJ_NET_SOCKET and may be passed to APIs like k_object_access_grant().

In a system like Linux which has the notion of threads running in processes in a shared
virtual address space, this sort of management is unnecessary as the scope of file de-
scriptors is implemented at the process level.

However in Zephyr the file descriptor scope is global, and MPU-based systems are not
able to implement a process-like model due to the lack of memory virtualization hard-
ware. They use discrete object permissions and memory domains instead to define
thread access scope.

User threads will have no direct access to the returned object and will fault if they try
to access its memory; the pointer can only be used to make permission assignment
calls, which follow exactly the rules for other kernel objects like device drivers and
IPC.

Parameters

• sock – file descriptor

Returns

pointer to associated network socket object, or NULL if the file descriptor
wasn't valid or the caller had no access permission

int zsock_socket(int family, int type, int proto)
Create a network socket.

See POSIX.1-2017 article for normative description. This function is also exposed as
socket() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

If CONFIG_USERSPACE is enabled, the caller will be granted access to the context object
associated with the returned file descriptor.

See also:

zsock_get_context_object()

int zsock_socketpair(int family, int type, int proto, int *sv)
Create an unnamed pair of connected sockets.

See POSIX.1-2017 article for normative description. This function is also exposed as
socketpair() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_close(int sock)
Close a network socket.

Close a network socket. This function is also exposed as close() if CON-
FIG_NET_SOCKETS_POSIX_NAMES is defined (in which case it may conflict with generic
POSIX close() function).

int zsock_shutdown(int sock, int how)
Shutdown socket send/receive operations.

See POSIX.1-2017 article for normative description, but currently this function has no
effect in Zephyr and provided solely for compatibility with existing code. This function
is also exposed as shutdown() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_bind(int sock, const struct sockaddr *addr, socklen_t addrlen)
Bind a socket to a local network address.

See POSIX.1-2017 article for normative description. This function is also exposed as
bind() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.
int zsock_connect(int sock, const struct sockaddr *addr, socklen_t addrlen)
    Connect a socket to a peer network address.
    See POSIX.1-2017 article for normative description. This function is also exposed as connect() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_listen(int sock, int backlog)
    Set up a STREAM socket to accept peer connections.
    See POSIX.1-2017 article for normative description. This function is also exposed as listen() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_accept(int sock, struct sockaddr *addr, socklen_t *addrlen)
    Accept a connection on listening socket.
    See POSIX.1-2017 article for normative description. This function is also exposed as accept() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

ssize_t zsock_sendto(int sock, const void *buf, size_t len, int flags, const struct sockaddr *dest_addr, socklen_t addrlen)
    Send data to an arbitrary network address.
    See POSIX.1-2017 article for normative description. This function is also exposed as sendto() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

static inline ssize_t zsock_send(int sock, const void *buf, size_t len, int flags)
    Send data to a connected peer.
    See POSIX.1-2017 article for normative description. This function is also exposed as send() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

ssize_t zsock_sendmsg(int sock, const struct msghdr *msg, int flags)
    Send data to an arbitrary network address.
    See POSIX.1-2017 article for normative description. This function is also exposed as sendmsg() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

ssize_t zsock_recvfrom(int sock, void *buf, size_t max_len, int flags, struct sockaddr *src_addr, socklen_t *addrlen)
    Receive data from an arbitrary network address.
    See POSIX.1-2017 article for normative description. This function is also exposed as recvfrom() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

ssize_t zsock_recvmsg(int sock, struct msghdr *msg, int flags)
    Receive a message from an arbitrary network address.
    See POSIX.1-2017 article for normative description. This function is also exposed as recvmsg() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

static inline ssize_t zsock_recv(int sock, void *buf, size_t max_len, int flags)
    Receive data from a connected peer.
    See POSIX.1-2017 article for normative description. This function is also exposed as recv() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_fcntl(int sock, int cmd, int flags)
    Control blocking/non-blocking mode of a socket.
    This functions allow to (only) configure a socket for blocking or non-blocking operation (O_NONBLOCK). This function is also exposed as fcntl() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined (in which case it may conflict with generic POSIX fcntl() function).
int zsock_ioctl(int sock, unsigned long request, va_list ap)
Control underlying socket parameters.

See POSIX.1-2017 article for normative description. This function enables querying or manipulating underlying socket parameters. Currently supported @p request values include ZFD_IOCTL_FIONBIO, and ZFD_IOCTL_FIONREAD, to set non-blocking mode, and query the number of bytes available to read, respectively. This function is also exposed as ioctl() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined (in which case it may conflict with generic POSIX ioctl() function).

int zsock_poll(struct zsock_pollfd *fds, int nfds, int timeout)
Efficiently poll multiple sockets for events.

See POSIX.1-2017 article for normative description. This function is also exposed as poll() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined (in which case it may conflict with generic POSIX poll() function).

int zsock_getsockopt(int sock, int level, int optname, void *optval, socklen_t *optlen)
Get various socket options.

See POSIX.1-2017 article for normative description. In Zephyr this function supports a subset of socket options described by POSIX, but also some additional options available in Linux (some options are dummy and provided to ease porting of existing code). This function is also exposed as getsockopt() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_setsockopt(int sock, int level, int optname, const void *optval, socklen_t optlen)
Set various socket options.

See POSIX.1-2017 article for normative description. In Zephyr this function supports a subset of socket options described by POSIX, but also some additional options available in Linux (some options are dummy and provided to ease porting of existing code). This function is also exposed as setsockopt() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_getpeername(int sock, struct sockaddr *addr, socklen_t *addrlen)
Get peer name.

See POSIX.1-2017 article for normative description. This function is also exposed as getpeername() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_getsockname(int sock, struct sockaddr *addr, socklen_t *addrlen)
Get socket name.

See POSIX.1-2017 article for normative description. This function is also exposed as getsockname() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_gethostname(char *buf, size_t len)
Get local host name.

See POSIX.1-2017 article for normative description. This function is also exposed as gethostname() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

static inline char *zsock_inet_ntop(sa_family_t family, const void *src, char *dst, size_t size)
Convert network address from internal to numeric ASCII form.

See POSIX.1-2017 article for normative description. This function is also exposed as inet_ntop() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_inet_pton(sa_family_t family, const char *src, void *dst)
Convert network address from numeric ASCII form to internal representation.

See POSIX.1-2017 article for normative description. This function is also exposed as inet_pton() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.
int zsock_getaddrinfo(const char *host, const char *service, const struct zsock_addrinfo *hints, struct zsock_addrinfo **res)

Resolve a domain name to one or more network addresses.

See POSIX.1-2017 article for normative description. This function is also exposed as getaddrinfo() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

void zsock_freeaddrinfo(struct zsock_addrinfo *ai)

Free results returned by zsock_getaddrinfo()

See POSIX.1-2017 article for normative description. This function is also exposed as freeaddrinfo() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

code>const char *zsock_gai_strerror(int errcode)

Convert zsock_getaddrinfo() error code to textual message.

See POSIX.1-2017 article for normative description. This function is also exposed as gai_strerror() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_getnameinfo(const struct sockaddr *addr, socklen_t addrlen, char *host, socklen_t hostlen, char *serv, socklen_t servlen, int flags)

Resolve a network address to a domain name or ASCII address.

See POSIX.1-2017 article for normative description. This function is also exposed as getnameinfo() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_select(int nfds, zsock_fd_set *readfds, zsock_fd_set *writefds, zsock_fd_set *exceptfds, struct zsock_timeval *timeout)

Legacy function to poll multiple sockets for events.

See POSIX.1-2017 article for normative description. This function is provided to ease porting of existing code and not recommended for usage due to its inefficiency, use zsock_poll() instead. In Zephyr this function works only with sockets, not arbitrary file descriptors. This function is also exposed as select() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined (in which case it may conflict with generic POSIX select() function).

void ZSOCK_FD_ZERO(zsock_fd_set *set)

Initialize (clear) fd_set.

See POSIX.1-2017 article for normative description. This function is also exposed as FD_ZERO() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int ZSOCK_FD_ISSET(int fd, zsock_fd_set *set)

Check whether socket is a member of fd_set.

See POSIX.1-2017 article for normative description. This function is also exposed as FD_ISSET() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

void ZSOCK_FD_CLR(int fd, zsock_fd_set *set)

Remove socket from fd_set.

See POSIX.1-2017 article for normative description. This function is also exposed as FD_CLR() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

void ZSOCK_FD_SET(int fd, zsock_fd_set *set)

Add socket to fd_set.

See POSIX.1-2017 article for normative description. This function is also exposed as FD_SET() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

static inline int select(int nfds, zsock_fd_set *readfds, zsock_fd_set *writefds, zsock_fd_set *exceptfds, struct timeval *timeout)
static inline void FD_ZERO(zsock_fd_set *set)
static inline int FD_ISSET(int fd, zsock_fd_set *set)
static inline void FD_CLR(int fd, zsock_fd_set *set)
static inline void FD_SET(int fd, zsock_fd_set *set)

struct zsock_pollfd
#include <socket.h> Definition of the monitored socket/file descriptor.
An array of these descriptors is passed as an argument to poll().

Public Members

int fd
Socket descriptor.

short events
Requested events.

short revents
Returned events.

struct zsock_addrinfo
#include <socket.h> Definition used when querying address information.
A linked list of these descriptors is returned by getaddrinfo(). The struct is also passed
as hints when calling the getaddrinfo() function.

Public Members

struct zsock_addrinfo *ai_next
Pointer to next address entry.

int ai_flags
Additional options.

int ai_family
Address family of the returned addresses.

int ai_socktype
Socket type, for example SOCK_STREAM or SOCK_DGRAM.

int ai_protocol
Protocol for addresses, 0 means any protocol.

socklen_t ai_addrlen
Length of the socket address.
struct sockaddr *ai_addr
    Pointer to the address.

char *ai_canonname
    Optional official name of the host.

struct ifreq
    #include <socket.h> Interface description structure.

    Public Members

    char ifr_name[Z_DEVICE_MAX_NAME_LEN]
        Network interface name.

struct in_pktinfo
    #include <socket.h> Incoming IPv4 packet information.
    Used as ancillary data when calling recvmsg() and IP_PKTINFO socket option is set.

    Public Members

    unsigned int ipi_ifindex
        Network interface index.

    struct in_addr ipi_spec_dst
        Local address.

    struct in_addr ipi_addr
        Header Destination address.

struct ip_mreqn
    #include <socket.h> Struct used when joining or leaving a IPv4 multicast group.

    Public Members

    struct in_addr imr_multiaddr
        IP multicast group address.

    struct in_addr imr_address
        IP address of local interface.

    int imr_ifindex
        Network interface index.

struct ipv6_mreq
    #include <socket.h> Struct used when joining or leaving a IPv6 multicast group.
Public Members

struct `in6_addr` `ipv6mr_multiaddr`
IPv6 multicast address of group.

int `ipv6mr_ifindex`
Network interface index of the local IPv6 address.

struct `in6_pktinfo`

#include `<socket.h>`
Incoming IPv6 packet information.
Used as ancillary data when calling `recvmsg()` and IPV6_RECVPKTINFO socket option is set.

Public Members

struct `in6_addr` `ipi6_addr`
Destination IPv6 address.

unsigned int `ipi6_ifindex`
Receive interface index.

struct `zsock_fd_set`

#include `<socket_select.h>`

TLS Credentials

Related code samples

AWS IoT Core MQTT
Connect to AWS IoT Core and publish messages using MQTT.

Dumb HTTP server (multi-threaded)
Implement a simple HTTP server supporting simultaneous connections using BSD sockets.

Echo client (advanced)
Implement a client that sends IP packets, waits for data to be sent back, and verifies it.

Echo server (advanced)
Implement a UDP/TCP server that sends received packets back to the sender.

HTTP GET using plain sockets
Implement an HTTP(S) client using plain BSD sockets.

HTTP client
Implement an HTTP(S) client that issues a variety of HTTP requests.

Large HTTP download
Download a large file from a web server using BSD sockets.

Microsoft Azure IoT Hub MQTT
Connect to Azure IoT Hub and publish messages using MQTT.

TagoIO HTTP Post
Send random temperature values to TagoIO IoT Cloud Platform using HTTP.
group tls_credentials
 TLS credentials management.

Typedefs

typedef int sec_tag_t
 Secure tag, a reference to TLS credential.
 Secure tag can be used to reference credential after it was registered in the system.

Note: Some TLS credentials come in pairs:
• TLS_CREDENTIAL_SERVER_CERTIFICATE with TLS_CREDENTIAL_PRIVATE_KEY,
• TLS_CREDENTIAL_PSK with TLS_CREDENTIAL_PSK_ID. Such pairs of credentials
  must be assigned the same secure tag to be correctly handled in the system.

Note: Negative values are reserved for internal use.

Enums

enum tls_credential_type
 TLS credential types.
 Values:

 enumerator TLS_CREDENTIAL_NONE
  Unspecified credential.

 enumerator TLS_CREDENTIAL_CA_CERTIFICATE
  A trusted CA certificate.
  Use this to authenticate remote servers. Used with certificate-based ciphersuites.

 enumerator TLS_CREDENTIAL_SERVER_CERTIFICATE
  A public server certificate.
  Use this to register your own server certificate. Should be registered together with
  a corresponding private key. Used with certificate-based ciphersuites.

 enumerator TLS_CREDENTIAL_PRIVATE_KEY
  Private key.
  Should be registered together with a corresponding public certificate. Used with
  certificate-based ciphersuites.

 enumerator TLS_CREDENTIAL_PSK
  Pre-shared key.
  Should be registered together with a corresponding PSK identity. Used with PSK-based ciphersuites.
enumerator TLS_CREDENTIAL_PSK_ID
    Pre-shared key identity.
    Should be registered together with a corresponding PSK. Used with PSK-based ciphersuites.

Functions

int tlsCredentialAdd(const void *cred, size_t credlen)
    Add a TLS credential.
    This function adds a TLS credential, that can be used by TLS/DTLS for authentication.

Parameters

- tag – A security tag that credential will be referenced with.
- type – A TLS/DTLS credential type.
- cred – A TLS/DTLS credential.
- credlen – A TLS/DTLS credential length.

Return values

- 0 – TLS credential successfully added.
- -EACCES – Access to the TLS credential subsystem was denied.
- -ENOMEM – Not enough memory to add new TLS credential.
- -EEXIST – TLS credential of specific tag and type already exists.

int tlsCredentialGet(void *cred, size_t *credlen)
    Get a TLS credential.
    This function gets an already registered TLS credential, referenced by tag secure tag of type.

Parameters

- tag – A security tag of requested credential.
- type – A TLS/DTLS credential type of requested credential.
- cred – A buffer for TLS/DTLS credential.
- credlen – A buffer size on input. TLS/DTLS credential length on output.

Return values

- 0 – TLS credential successfully obtained.
- -EACCES – Access to the TLS credential subsystem was denied.
- -ENOENT – Requested TLS credential was not found.
- -EFBIG – Requested TLS credential does not fit in the buffer provided.

int tlsCredentialDelete()
    Delete a TLS credential.
    This function removes a TLS credential, referenced by tag secure tag of type.

Parameters

- tag – A security tag corresponding to removed credential.
• type – A TLS/DTLS credential type of removed credential.

**Return values**

• 0 – TLS credential successfully deleted.
• -EACCES – Access to the TLS credential subsystem was denied.
• -ENOENT – Requested TLS credential was not found.

**IPv4/IPv6 Primitives and Helpers**

- Overview
  - API Reference

**Overview**  
Miscellaneous defines and helper functions for IP addresses and IP protocols.

**API Reference**

group ip_4_6  
IPv4/IPv6 primitives and helpers.

**Defines**

**PF_UNSPEC**
Unspecified protocol family.

**PF_INET**
IP protocol family version 4.

**PF_INET6**
IP protocol family version 6.

**PF_PACKET**
Packet family.

**PF_CAN**
Controller Area Network.

**PF_NET_MGMT**
Network management info.

**PF_LOCAL**
Inter-process communication

**PF_UNIX**
Inter-process communication
AF_UNSPEC
Unspecified address family.

AF_INET
IP protocol family version 4.

AF_INET6
IP protocol family version 6.

AF_PACKET
Packet family.

AF_CAN
Controller Area Network.

AF_NET_MGMT
Network management info.

AF_LOCAL
Inter-process communication

AF_UNIX
Inter-process communication

ntohs(x)
Convert 16-bit value from network to host byte order.

Parameters
• x – The network byte order value to convert.

Returns
Host byte order value.

ntohl(x)
Convert 32-bit value from network to host byte order.

Parameters
• x – The network byte order value to convert.

Returns
Host byte order value.

ntohll(x)
Convert 64-bit value from network to host byte order.

Parameters
• x – The network byte order value to convert.

Returns
Host byte order value.

htons(x)
Convert 16-bit value from host to network byte order.

Parameters
• x – The host byte order value to convert.
**Returns**
Network byte order value.

`htonl(x)`
Convert 32-bit value from host to network byte order.

**Parameters**
- `x` – The host byte order value to convert.

**Returns**
Network byte order value.

`htonl1(x)`
Convert 64-bit value from host to network byte order.

**Parameters**
- `x` – The host byte order value to convert.

**Returns**
Network byte order value.

**NET_IPV6_ADDR_SIZE**

**NET_IPV4_ADDR_SIZE**

**ALIGN_H(x)**

**ALIGN_D(x)**

**CMMSG_FISTHDR(msghdr)**

**CMMSG_NXTHDR(msghdr, cmsg)**

**CMMSG_DATA(cmsg)**

**CMMSG_SPACE(length)**

**CMMSG_LEN(length)**

**INET_ADDRSTRLEN**
Max length of the IPv4 address as a string.
Defined by POSIX.

**INET6_ADDRSTRLEN**
Max length of the IPv6 address as a string.
Takes into account possible mapped IPv4 addresses.

**NET_MAX_PRIORITIES**

`net_ipaddr_copy(dest, src)`
Copy an IPv4 or IPv6 address.

**Parameters**
- `dest` – Destination IP address.
- `src` – Source IP address.

**Returns**
Destination address.
**Typedefs**

typedef unsigned short int sa_family_t
  Socket address family type.

typedef size_t socklen_t
  Length of a socket address.

**Enums**

define enum net_ip_protocol
  Protocol numbers from IANA/BSD.
  *Values:*

  enumerator IPPROTO_IP = 0
    IP protocol (pseudo-val for setsockopt())

  enumerator IPPROTO_ICMP = 1
    ICMP protocol

  enumerator IPPROTO_IGMP = 2
    IGMP protocol

  enumerator IPPROTO_IPIP = 4
    IPIP tunnels

  enumerator IPPROTO_TCP = 6
    TCP protocol

  enumerator IPPROTO_UDP = 17
    UDP protocol

  enumerator IPPROTO_IPV6 = 41
    IPv6 protocol

  enumerator IPPROTO_ICMPV6 = 58
    ICMPv6 protocol.

  enumerator IPPROTO_RAW = 255
    RAW IP packets

define enum net_ip_protocol_secure
  Protocol numbers for TLS protocols.
  *Values:*

  enumerator IPPROTO_TLS_1_0 = 256
    TLS 1.0 protocol.
enumerator IPPROTO_TLS_1_1 = 257
    TLS 1.1 protocol.

enumerator IPPROTO_TLS_1_2 = 258
    TLS 1.2 protocol.

enumerator IPPROTO_DTLS_1_0 = 272
    DTLS 1.0 protocol.

enumerator IPPROTO_DTLS_1_2 = 273
    DTLS 1.2 protocol.

definition of net_sock_type
    Socket type.
    Values:

    enumerator SOCK_STREAM = 1
        Stream socket type

    enumerator SOCK_DGRAM
        Datagram socket type.

    enumerator SOCK_RAW
        RAW socket type

definition of net_ip_mtu
    Values:

    enumerator NET_IPV6_MTU = 1280
        IPv6 MTU length.
        We must be able to receive this size IPv6 packet without fragmentation.

    enumerator NET_IPV4_MTU = 576
        IPv4 MTU length.
        We must be able to receive this size IPv4 packet without fragmentation.

definition of net_priority
    Network packet priority settings described in IEEE 802.1Q Annex I.1.
    Values:

    enumerator NET_PRIORITY_BK = 1
        Background (lowest)

    enumerator NET_PRIORITY_BE = 0
        Best effort (default)

    enumerator NET_PRIORITY_EE = 2
        Excellent effort
enumerator NET_PRIORITY_CA = 3
    Critical applications

enumerator NET_PRIORITY_VI = 4
    Video, < 100 ms latency and jitter.

enumerator NET_PRIORITY_VO = 5
    Voice, < 10 ms latency and jitter

enumerator NET_PRIORITY_IC = 6
    Internetwork control

enumerator NET_PRIORITY_NC = 7
    Network control (highest)

define enum net_addr_state
    What is the current state of the network address.
    Values:
    enumerator NET_ADDR_ANY_STATE = -1
        Default (invalid) address type.
    enumerator NET_ADDR_TENTATIVE = 0
        Tentative address
    enumerator NET_ADDR_PREFERRED
        Preferred address
    enumerator NET_ADDR_DEPRECATED
        Deprecated address

define enum net_addr_type
    How the network address is assigned to network interface.
    Values:
    enumerator NET_ADDR_ANY = 0
        Default value.
        This is not a valid value.
    enumerator NET_ADDR_AUTOCONF
        Auto configured address.
    enumerator NET_ADDR_DHCP
        Address is from DHCP.
    enumerator NET_ADDR_MANUAL
        Manually set address.
enumerator NET_ADDR_OVERRIDEABLE
  Manually set address which is overridable by DHCP.

Functions

static inline bool net_ipv6_is_addr_loopback(struct in6_addr *addr)
  Check if the IPv6 address is a loopback address (::1).

  Parameters
  • addr – IPv6 address

  Returns
  True if address is a loopback address, False otherwise.

static inline bool net_ipv6_is_addr_mcast(const struct in6_addr *addr)
  Check if the IPv6 address is a multicast address.

  Parameters
  • addr – IPv6 address

  Returns
  True if address is multicast address, False otherwise.

struct net_if_addr *net_if_ipv6_addr_lookup(const struct in6_addr *addr, struct net_if **iface)

static inline bool net_ipv6_is_my_addr(struct in6_addr *addr)
  Check if IPv6 address is found in one of the network interfaces.

  Parameters
  • addr – IPv6 address

  Returns
  True if address was found, False otherwise.

struct net_if_mcast_addr *net_if_ipv6_maddr_lookup(const struct in6_addr *addr, struct net_if **iface)

static inline bool net_ipv6_is_my_maddr(struct in6_addr *maddr)
  Check if IPv6 multicast address is found in one of the network interfaces.

  Parameters
  • maddr – Multicast IPv6 address

  Returns
  True if address was found, False otherwise.

static inline bool net_ipv6_is_prefix(const uint8_t *addr1, const uint8_t *addr2, uint8_t length)
  Check if two IPv6 addresses are same when compared after prefix mask.

  Parameters
  • addr1 – First IPv6 address.
  • addr2 – Second IPv6 address.
  • length – Prefix length (max length is 128).

  Returns
  True if IPv6 prefixes are the same, False otherwise.
static inline bool \textbf{net_ipv4_is_addr_loopback}(\textit{struct in_addr *addr})
\begin{align*}
\text{Check if the IPv4 address is a loopback address (127.0.0.0/8).}
\end{align*}

\textbf{Parameters}
\begin{itemize}
\item \textit{addr} – IPv4 address
\end{itemize}

\textbf{Returns}
True if address is a loopback address, False otherwise.

static inline bool \textbf{net_ipv4_is_addr_unspecified}(\textit{const struct in_addr *addr})
\begin{align*}
\text{Check if the IPv4 address is unspecified (all bits zero)}
\end{align*}

\textbf{Parameters}
\begin{itemize}
\item \textit{addr} – IPv4 address.
\end{itemize}

\textbf{Returns}
True if the address is unspecified, false otherwise.

static inline bool \textbf{net_ipv4_is_addr_mcast}(\textit{const struct in_addr *addr})
\begin{align*}
\text{Check if the IPv4 address is a multicast address.}
\end{align*}

\textbf{Parameters}
\begin{itemize}
\item \textit{addr} – IPv4 address
\end{itemize}

\textbf{Returns}
True if address is multicast address, False otherwise.

static inline bool \textbf{net_ipv4_is_ll_addr}(\textit{const struct in_addr *addr})
\begin{align*}
\text{Check if the given IPv4 address is a link local address.}
\end{align*}

\textbf{Parameters}
\begin{itemize}
\item \textit{addr} – A valid pointer on an IPv4 address
\end{itemize}

\textbf{Returns}
True if it is, false otherwise.

static inline void \textbf{net_ipv4_addr_copy_raw}(\textit{uint8_t *dest, const uint8_t *src})
\begin{align*}
\text{Copy an IPv4 address raw buffer.}
\end{align*}

\textbf{Parameters}
\begin{itemize}
\item \textit{dest} – Destination IP address.
\item \textit{src} – Source IP address.
\end{itemize}

static inline void \textbf{net_ipv6_addr_copy_raw}(\textit{uint8_t *dest, const uint8_t *src})
\begin{align*}
\text{Copy an IPv6 address raw buffer.}
\end{align*}

\textbf{Parameters}
\begin{itemize}
\item \textit{dest} – Destination IP address.
\item \textit{src} – Source IP address.
\end{itemize}

static inline bool \textbf{net_ipv4_addr_cmp}(\textit{const struct in_addr *addr1, const struct in_addr *addr2})
\begin{align*}
\text{Compare two IPv4 addresses.}
\end{align*}

\textbf{Parameters}
\begin{itemize}
\item \textit{addr1} – Pointer to IPv4 address.
\item \textit{addr2} – Pointer to IPv4 address.
\end{itemize}

\textbf{Returns}
True if the addresses are the same, false otherwise.
static inline bool net_ipv4_addr_cmp_raw(const uint8_t *addr1, const uint8_t *addr2)
  Compare two raw IPv4 address buffers.

Parameters
  • addr1 – Pointer to IPv4 address buffer.
  • addr2 – Pointer to IPv4 address buffer.

Returns
  True if the addresses are the same, false otherwise.

static inline bool net_ipv6_addr_cmp(const struct in6_addr *addr1, const struct in6_addr *addr2)
  Compare two IPv6 addresses.

Parameters
  • addr1 – Pointer to IPv6 address.
  • addr2 – Pointer to IPv6 address.

Returns
  True if the addresses are the same, false otherwise.

static inline bool net_ipv6_addr_cmp_raw(const uint8_t *addr1, const uint8_t *addr2)
  Compare two raw IPv6 address buffers.

Parameters
  • addr1 – Pointer to IPv6 address buffer.
  • addr2 – Pointer to IPv6 address buffer.

Returns
  True if the addresses are the same, false otherwise.

static inline bool net_ipv6_is_ll_addr(const struct in6_addr *addr)
  Check if the given IPv6 address is a link local address.

Parameters
  • addr – A valid pointer on an IPv6 address

Returns
  True if it is, false otherwise.

static inline bool net_ipv6_is_sl_addr(const struct in6_addr *addr)
  Check if the given IPv6 address is a site local address.

Parameters
  • addr – A valid pointer on an IPv6 address

Returns
  True if it is, false otherwise.

static inline bool net_ipv6_is_ula_addr(const struct in6_addr *addr)
  Check if the given IPv6 address is a unique local address.

Parameters
  • addr – A valid pointer on an IPv6 address

Returns
  True if it is, false otherwise.
static inline bool net_ipv6_is_global_addr(const struct in6_addr *addr)
    Check if the given IPv6 address is a global address.

Parameters
• addr – A valid pointer on an IPv6 address

Returns
True if it is, false otherwise.

const struct in6_addr *net_ipv6_unspecified_address(void)
    Return pointer to any (all bits zeros) IPv6 address.

Returns
Any IPv6 address.

const struct in_addr *net_ipv4_unspecified_address(void)
    Return pointer to any (all bits zeros) IPv4 address.

Returns
Any IPv4 address.

const struct in_addr *net_ipv4_broadcast_address(void)
    Return pointer to broadcast (all bits ones) IPv4 address.

Returns
Broadcast IPv4 address.

bool net_if_ipv4_addr_mask_cmp(struct net_if *iface, const struct in_addr *addr)
static inline bool net_ipv4_addr_mask_cmp(struct net_if *iface, const struct in_addr *addr)
    Check if the given address belongs to same subnet that has been configured for the interface.

Parameters
• iface – A valid pointer on an interface
• addr – IPv4 address

Returns
True if address is in same subnet, false otherwise.

bool net_if_ipv4_is_addr_bcast(struct net_if *iface, const struct in_addr *addr)
static inline bool net_ipv4_is_addr_bcast(struct net_if *iface, const struct in_addr *addr)
    Check if the given IPv4 address is a broadcast address.

Parameters
• iface – Interface to use. Must be a valid pointer to an interface.
• addr – IPv4 address

Returns
True if address is a broadcast address, false otherwise.

struct net_if_addr *net_if_ipv4_addr_lookup(const struct in_addr *addr, struct net_if **iface)
static inline bool net_ipv4_is_my_addr(const struct in_addr *addr)
    Check if the IPv4 address is assigned to any network interface in the system.

Parameters
• addr – A valid pointer on an IPv4 address
Returns
True if IPv4 address is found in one of the network interfaces, False otherwise.

static inline bool net_ipv6_is_addr_unspecified(const struct in6_addr *addr)
Check if the IPv6 address is unspecified (all bits zero)

Parameters
• addr – IPv6 address.

Returns
True if the address is unspecified, false otherwise.

static inline bool net_ipv6_is_addr_solicited_node(const struct in6_addr *addr)
Check if the IPv6 address is solicited node multicast address FF02:0:0:0:0:1:FFXX:XXXX defined in RFC 3513.

Parameters
• addr – IPv6 address.

Returns
True if the address is solicited node address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_scope(const struct in6_addr *addr, int scope)
Check if the IPv6 address is a given scope multicast address (FFyx::).

Parameters
• addr – IPv6 address
• scope – Scope to check

Returns
True if the address is in given scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_global(const struct in6_addr *addr)
Check if the IPv6 address is a global multicast address (FFxE::/16).

Parameters
• addr – IPv6 address.

Returns
True if the address is global multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_iface(const struct in6_addr *addr)
Check if the IPv6 address is a interface scope multicast address (FFx1::).

Parameters
• addr – IPv6 address.

Returns
True if the address is a interface scope multicast address, false otherwise.
static inline bool net_ipv6_is_addr_mcast_link(const struct in6_addr *addr)
Check if the IPv6 address is a link local scope multicast address (FFx2::).

Parameters
• addr – IPv6 address.

Returns
True if the address is a link local scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_mesh(const struct in6_addr *addr)
Check if the IPv6 address is a mesh-local scope multicast address (FFx3::).

Parameters
• addr – IPv6 address.

Returns
True if the address is a mesh-local scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_site(const struct in6_addr *addr)
Check if the IPv6 address is a site scope multicast address (FFx5::).

Parameters
• addr – IPv6 address.

Returns
True if the address is a site scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_org(const struct in6_addr *addr)
Check if the IPv6 address is an organization scope multicast address (FFx8::).

Parameters
• addr – IPv6 address.

Returns
True if the address is an organization scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_group(const struct in6_addr *addr, const struct in6_addr *group)
Check if the IPv6 address belongs to certain multicast group.

Parameters
• addr – IPv6 address.
• group – Group id IPv6 address, the values must be in network byte order

Returns
True if the IPv6 multicast address belongs to given multicast group, false otherwise.

static inline bool net_ipv6_is_addr_mcast_all_nodes_group(const struct in6_addr *addr)
Check if the IPv6 address belongs to the all nodes multicast group.

Parameters
• addr – IPv6 address

Returns
True if the IPv6 multicast address belongs to the all nodes multicast group, false otherwise.
static inline bool net_ipv6_is_addr_mcast_iface_all_nodes(const struct in6_addr *addr)

Check if the IPv6 address is a interface scope all nodes multicast address (FF01::1).

**Parameters**

- `addr` – IPv6 address.

**Returns**

True if the address is a interface scope all nodes multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_link_all_nodes(const struct in6_addr *addr)

Check if the IPv6 address is a link local scope all nodes multicast address (FF02::1).

**Parameters**

- `addr` – IPv6 address.

**Returns**

True if the address is a link local scope all nodes multicast address, false otherwise.

static inline void net_ipv6_addr_create_solicited_node(const struct in6_addr *src, struct in6_addr *dst)

Create solicited node IPv6 multicast address FF02:0:0:0:1:FFXX:XXXX defined in RFC 3513.

**Parameters**

- `src` – IPv6 address.
- `dst` – IPv6 address.

static inline void net_ipv6_addr_create(struct in6_addr *addr, uint16_t addr0, uint16_t addr1, uint16_t addr2, uint16_t addr3, uint16_t addr4, uint16_t addr5, uint16_t addr6, uint16_t addr7)

Construct an IPv6 address from eight 16-bit words.

**Parameters**

- `addr` – IPv6 address
- `addr0` – 16-bit word which is part of the address
- `addr1` – 16-bit word which is part of the address
- `addr2` – 16-bit word which is part of the address
- `addr3` – 16-bit word which is part of the address
- `addr4` – 16-bit word which is part of the address
- `addr5` – 16-bit word which is part of the address
- `addr6` – 16-bit word which is part of the address
- `addr7` – 16-bit word which is part of the address

static inline void net_ipv6_addr_create_ll_allnodes_mcast(struct in6_addr *addr)

Create link local allnodes multicast IPv6 address.

**Parameters**

- `addr` – IPv6 address
static inline void net_ipv6_addr_create_ll_allrouters_mcast(struct in6_addr *addr)
Create link local allrouters multicast IPv6 address.

Parameters
• addr – IPv6 address

static inline void net_ipv6_addr_create_v4Mapped(const struct in_addr *addr4, struct in6_addr *addr6)
Create IPv4 mapped IPv6 address.

Parameters
• addr4 – IPv4 address
• addr6 – IPv6 address to be created

static inline bool net_ipv6_addr_is_v4Mapped(const struct in6_addr *addr)
Is the IPv6 address an IPv4 mapped one.
The v4 mapped addresses look like ::ffff:a.b.c.d

Parameters
• addr – IPv6 address

Returns
True if IPv6 address is a IPv4 mapped address, False otherwise.

static inline void net_ipv6_addr_create_iid(struct in6_addr *addr, struct net_linkaddr *lladdr)
Create IPv6 address interface identifier.

Parameters
• addr – IPv6 address
• lladdr – Link local address

static inline bool net_ipv6_addr_based_on_ll(const struct in6_addr *addr, const struct net_linkaddr *lladdr)
Check if given address is based on link layer address.

Returns
True if it is, False otherwise

static inline struct sockaddr_in6 *net_sin6(const struct sockaddr *addr)
Get sockaddr_in6 from sockaddr.
This is a helper so that the code calling this function can be made shorter.

Parameters
• addr – Socket address

Returns
Pointer to IPv6 socket address

static inline struct sockaddr_in *net_sin(const struct sockaddr *addr)
Get sockaddr_in from sockaddr.
This is a helper so that the code calling this function can be made shorter.

Parameters
• addr – Socket address

Returns
Pointer to IPv4 socket address
static inline struct sockaddr_in6_ptr *net_sin6_ptr(const struct sockaddr_ptr *addr)
Get sockaddr_in6_ptr from sockaddr_ptr.
This is a helper so that the code calling this function can be made shorter.

**Parameters**
- **addr** – Socket address

**Returns**
Pointer to IPv6 socket address

static inline struct sockaddr_in_ptr *net_sin_ptr(const struct sockaddr_ptr *addr)
Get sockaddr_in_ptr from sockaddr_ptr.
This is a helper so that the code calling this function can be made shorter.

**Parameters**
- **addr** – Socket address

**Returns**
Pointer to IPv4 socket address

static inline struct sockaddr_ll_ptr *net_sll_ptr(const struct sockaddr_ptr *addr)
Get sockaddr_ll_ptr from sockaddr_ptr.
This is a helper so that the code calling this function can be made shorter.

**Parameters**
- **addr** – Socket address

**Returns**
Pointer to linklayer socket address

static inline struct sockaddr_can_ptr *net_can_ptr(const struct sockaddr_ptr *addr)
Get sockaddr_can_ptr from sockaddr_ptr.
This is a helper so that the code needing this functionality can be made shorter.

**Parameters**
- **addr** – Socket address

**Returns**
Pointer to CAN socket address

int net_addr_pton(sa_family_t family, const char *src, void *dst)
Convert a string to IP address.

**Note:** This function doesn’t do precise error checking, do not use for untrusted strings.

**Parameters**
- **family** – IP address family (AF_INET or AF_INET6)
- **src** – IP address in a null terminated string
- **dst** – Pointer to struct in_addr if family is AF_INET or pointer to struct in6_addr if family is AF_INET6

**Returns**
0 if ok, < 0 if error
char *net_addr_ntop(sa_family_t family, const void *src, char *dst, size_t size)
Convert IP address to string form.

Parameters
- family – IP address family (AF_INET or AF_INET6)
- src – Pointer to struct in_addr if family is AF_INET or pointer to struct
  in6_addr if family is AF_INET6
- dst – Buffer for IP address as a null terminated string
- size – Number of bytes available in the buffer

Returns
- dst pointer if ok, NULL if error

bool net_ipaddr_parse(const char *str, size_t str_len, struct sockaddr *addr)
Parse a string that contains either IPv4 or IPv6 address and optional port, and store
the information in user supplied sockaddr struct.

Syntax of the IP address string: 192.0.2.1:80 192.0.2.42 [2001:db8::2] 2001:db::42 Note that the str_len parameter is used to restrict the amount
of characters that are checked. If the string does not contain port number, then the port
number in sockaddr is not modified.

Parameters
- str – String that contains the IP address.
- str_len – Length of the string to be parsed.
- addr – Pointer to user supplied struct sockaddr.

Returns
- True if parsing could be done, false otherwise.

static inline int32_t net_tcp_seq_cmp(uint32_t seq1, uint32_t seq2)
Compare TCP sequence numbers.

This function compares TCP sequence numbers, accounting for wraparound effects.

Parameters
- seq1 – First sequence number
- seq2 – Seconds sequence number

Returns
- < 0 if seq1 < seq2, 0 if seq1 == seq2, > 0 if seq > seq2

static inline bool net_tcp_seq_greater(uint32_t seq1, uint32_t seq2)
Check that one TCP sequence number is greater.

This is convenience function on top of net_tcp_seq_cmp().

Parameters
- seq1 – First sequence number
- seq2 – Seconds sequence number

Returns
- True if seq > seq2

int net_bytes_from_str(uint8_t *buf, int buf_len, const char *src)
Convert a string of hex values to array of bytes.

The syntax of the string is “ab:02:98:fa:42:01”
Parameters

- `buf` – Pointer to memory where the bytes are written.
- `buf_len` – Length of the memory area.
- `src` – String of bytes.

Returns

0 if ok, <0 if error

```c
int net_tx_priority2tc(enum net_priority prio)
```

Convert Tx network packet priority to traffic class so we can place the packet into correct Tx queue.

Parameters

- `prio` – Network priority

Returns

Tx traffic class that handles that priority network traffic.

```c
int net_rx_priority2tc(enum net_priority prio)
```

Convert Rx network packet priority to traffic class so we can place the packet into correct Rx queue.

Parameters

- `prio` – Network priority

Returns

Rx traffic class that handles that priority network traffic.

```c
static inline enum net_priority net_vlan2priority(uint8_t priority)
```

Convert network packet VLAN priority to network packet priority so we can place the packet into correct queue.

Parameters

- `priority` – VLAN priority

Returns

Network priority

```c
static inline uint8_t net_priority2vlan(enum net_priority priority)
```

Convert network packet priority to network packet VLAN priority.

Parameters

- `priority` – Packet priority

Returns

VLAN priority (PCP)

```c
const char *net_family2str(sa_family_t family)
```

Return network address family value as a string.

This is only usable for debugging.

Parameters

- `family` – Network address family code

Returns

Network address family as a string, or NULL if family is unknown.

```c
struct in6_addr
```

`#include <net_ip.h>` IPv6 address struct.
struct in_addr
    #include <net_ip.h> IPv4 address struct.

struct sockaddr_in6
    #include <net_ip.h> Socket address struct for IPv6.

struct sockaddr_in6_ptr
    #include <net_ip.h>

struct sockaddr_in
    #include <net_ip.h> Socket address struct for IPv4.

struct sockaddr_in_ptr
    #include <net_ip.h>

struct sockaddr_ll
    #include <net_ip.h> Socket address struct for packet socket.

struct sockaddr_ll_ptr
    #include <net_ip.h>

struct sockaddr_can_ptr
    #include <net_ip.h>

struct iovec
    #include <net_ip.h>

struct msghdr
    #include <net_ip.h>

struct cmsghdr
    #include <net_ip.h>

struct sockaddr
    #include <net_ip.h> Generic sockaddr struct.
    Must be cast to proper type.

struct net_tuple
    #include <net_ip.h> IPv6/IPv4 network connection tuple.

**Public Members**

struct net_addr *remote_addr
    IPv6/IPv4 remote address.

struct net_addr *local_addr
    IPv6/IPv4 local address.
**Overview** The DNS resolver implements a basic DNS resolver according to IETF RFC1035 on Domain Implementation and Specification. Supported DNS answers are IPv4/IPv6 addresses and CNAME.

If a CNAME is received, the DNS resolver will create another DNS query. The number of additional queries is controlled by the CONFIG_DNS_RESOLVER_ADDITIONAL QUERIES Kconfig variable.

The multicast DNS (mDNS) client resolver support can be enabled by setting CONFIG_MDNS_RESOLVER Kconfig option. See IETF RFC6762 for more details about mDNS.

The link-local multicast name resolution (LLMNR) client resolver support can be enabled by setting the CONFIG_LLMNR_RESOLVER Kconfig variable. See IETF RFC4795 for more details about LLMNR.

For more information about DNS configuration variables, see: subsys/net/lib/dns/Kconfig. The DNS resolver API can be found at include/zephyr/net/dns_resolve.h.

**Sample usage** See dns-resolve sample application for details.

**API Reference**

**Related code samples**

**AWS IoT Core MQTT**
Connect to AWS IoT Core and publish messages using MQTT.

**DNS resolve**
Resolve an IP address for a given hostname.

**TagoIO HTTP Post**
Send random temperature values to TagoIO IoT Cloud Platform using HTTP.

**group dns_resolve**
DNS resolving library.
Defines

**DNS_MAX_NAME_SIZE**

Max size of the resolved name.

TypeDefs

typedef void (*dns_resolve_cb_t)(enum dns_resolve_status status, struct dns_addrinfo *info, void *user_data)

DNS resolve callback.

The DNS resolve callback is called after a successful DNS resolving. The resolver can call this callback multiple times, one for each resolved address.

**Param status**
The status of the query: DNS_EAI_INPROGRESS returned for each resolved address DNS_EAI_ALLDONE mark end of the resolving, info is set to NULL in this case DNS_EAI_CANCELED if the query was canceled manually or timeout happened DNS_EAI_FAIL if the name cannot be resolved by the server DNS_EAI_NODATA if there is no such name other values means that an error happened.

**Param info**
Query results are stored here.

**Param user_data**
The user data given in *dns_resolve_name()* call.

Enums

enum dns_query_type

DNS query type enum.

Values:

- enumerator DNS_QUERY_TYPE_A = 1
  IPv4 query.

- enumerator DNS_QUERY_TYPE_AAAA = 28
  IPv6 query.

enum dns_resolve_status

Status values for the callback.

Values:

- enumerator DNS_EAI_BADFLAGS = -1
  Invalid value for ai_flags field.

- enumerator DNS_EAI_NONAME = -2
  NAME or SERVICE is unknown.
enumerator DNS_EAI_AGAIN = -3
Temporary failure in name resolution.

enumerator DNS_EAI_FAIL = -4
Non-recoverable failure in name res.

enumerator DNS_EAI_NODATA = -5
No address associated with NAME.

enumerator DNS_EAI_FAMILY = -6
ai_family not supported

enumerator DNS_EAI_SOCKTYPE = -7
ai_socktype not supported

enumerator DNS_EAI_SERVICE = -8
SRV not supported for ai_socktype.

enumerator DNS_EAI_ADDRFAMILY = -9
Address family for NAME not supported.

enumerator DNS_EAI_MEMORY = -10
Memory allocation failure.

enumerator DNS_EAI_SYSTEM = -11
System error returned in errno.

enumerator DNS_EAI_OVERFLOW = -12
Argument buffer overflow.

enumerator DNS_EAI_INPROGRESS = -100
Processing request in progress.

enumerator DNS_EAI_CANCELED = -101
Request canceled.

enumerator DNS_EAI_NOTCANCELED = -102
Request not canceled.

enumerator DNS_EAI_ALLDONE = -103
All requests done.

enumerator DNS_EAI_IDN_ENCODE = -105
IDN encoding failed.

enum dns_resolve_context_state
Values:
Functions

int dns_resolve_init(struct dns_resolve_context *ctx, const char *dns_servers_str[], const struct sockaddr *dns_servers_sa[])
Init DNS resolving context.

This function sets the DNS server address and initializes the DNS context that is used by the actual resolver. DNS server addresses can be specified either in textual form, or as struct sockaddr (or both). Note that the recommended way to resolve DNS names is to use the dns_get_addr_info() API. In that case user does not need to call dns_resolve_init() as the DNS servers are already setup by the system.

Parameters

- ctx – DNS context. If the context variable is allocated from the stack, then the variable needs to be valid for the whole duration of the resolving. Caller does not need to fill the variable beforehand or edit the context afterwards.
- dns_servers_str – DNS server addresses using textual strings. The array is NULL terminated. The port number can be given in the string. Syntax for the server addresses with or without port numbers: IPv4 : 10.0.9.1 IPv4 + port : 10.0.9.1:5353 IPv6 : [2001:db8::22:42] IPv6 + port : [2001:db8::22:42]:5353
- dns_servers_sa – DNS server addresses as struct sockaddr. The array is NULL terminated. Port numbers are optional in struct sockaddr, the default will be used if set to 0.

Returns

0 if ok, <0 if error.

int dns_resolve_init_default(struct dns_resolve_context *ctx)
Init DNS resolving context with default Kconfig options.

Parameters

- ctx – DNS context.

Returns

0 if ok, <0 if error.

int dns_resolve_close(struct dns_resolve_context *ctx)
Close DNS resolving context.

This releases DNS resolving context and marks the context unusable. Caller must call the dns_resolve_init() again to make context usable.

Parameters

- ctx – DNS context

Returns

0 if ok, <0 if error.
int dns_resolve_reconfigure(struct dns_resolve_context *ctx, const char *servers_str[], const struct sockaddr *servers_sa[])

Reconfigure DNS resolving context.
Reconfigures DNS context with new server list.

Parameters
• ctx – DNS context
• servers_str – DNS server addresses using textual strings. The array is NULL terminated. The port number can be given in the string. Syntax for the server addresses with or without port numbers: IPv4: 10.0.9.1 IPv4 + port: 10.0.9.1:5353 IPv6: 2001:db8::22:42 IPv6 + port: [2001:db8::22:42]:5353
• servers_sa – DNS server addresses as struct sockaddr. The array is NULL terminated. Port numbers are optional in struct sockaddr, the default will be used if set to 0.

Returns
0 if ok, <0 if error.

int dns_resolve_cancel(struct dns_resolve_context *ctx, uint16_t dns_id)

Cancel a pending DNS query.
This releases DNS resources used by a pending query.

Parameters
• ctx – DNS context
• dns_id – DNS id of the pending query

Returns
0 if ok, <0 if error.

int dns_resolve_cancel_with_name(struct dns_resolve_context *ctx, uint16_t dns_id, const char *query_name, enum dns_query_type query_type)

Cancel a pending DNS query using id, name and type.
This releases DNS resources used by a pending query.

Parameters
• ctx – DNS context
• dns_id – DNS id of the pending query
• query_name – Name of the resource we are trying to query (hostname)
• query_type – Type of the query (A or AAAA)

Returns
0 if ok, <0 if error.

int dns_resolve_name(struct dns_resolve_context *ctx, const char *query, enum dns_query_type type, uint16_t *dns_id, dns_resolve_cb_t cb, void *user_data, int32_t timeout)

Resolve DNS name.
This function can be used to resolve e.g., IPv4 or IPv6 address. Note that this is asynchronous call, the function will return immediately and system will call the callback after resolving has finished or timeout has occurred. We might send the query to multiple servers (if there are more than one server configured), but we only use the result of the first received response.
Parameters

- **ctx** – DNS context
- **query** – What the caller wants to resolve.
- **type** – What kind of data the caller wants to get.
- **dns_id** – DNS id is returned to the caller. This is needed if one wishes to cancel the query. This can be set to NULL if there is no need to cancel the query.
- **cb** – Callback to call after the resolving has finished or timeout has happened.
- **user_data** – The user data.
- **timeout** – The timeout value for the query. Possible values: SYS_FOREVER_MS: the query is tried forever, user needs to cancel it manually if it takes too long time to finish >0: start the query and let the system timeout it after specified ms

Returns

0 if resolving was started ok, < 0 otherwise

```c
struct dns_resolve_context *dns_resolve_get_default(void)
```

Get default DNS context.

The system level DNS context uses DNS servers that are defined in project config file. If no DNS servers are defined by the user, then resolving DNS names using default DNS context will do nothing. The configuration options are described in subsys/net/lib/dns/Kconfig file.

**Returns**

Default DNS context.

```c
static inline int dns_get_addr_info(const char *query, enum dns_query_type type, uint16_t *dns_id, dns_resolve_cb_t cb, void *user_data, int32_t timeout)
```

Get IP address info from DNS.

This function can be used to resolve e.g., IPv4 or IPv6 address. Note that this is asynchronous call, the function will return immediately and system will call the callback after resolving has finished or timeout has occurred. We might send the query to multiple servers (if there are more than one server configured), but we only use the result of the first received response. This variant uses system wide DNS servers.

Parameters

- **query** – What the caller wants to resolve.
- **type** – What kind of data the caller wants to get.
- **dns_id** – DNS id is returned to the caller. This is needed if one wishes to cancel the query. This can be set to NULL if there is no need to cancel the query.
- **cb** – Callback to call after the resolving has finished or timeout has happened.
- **user_data** – The user data.
- **timeout** – The timeout value for the connection. Possible values: SYS_FOREVER_MS: the query is tried forever, user needs to cancel it manually if it takes too long time to finish >0: start the query and let the system timeout it after specified ms
Returns
0 if resolving was started ok, < 0 otherwise

static inline int dns_cancel_addr_info(uint16_t dns_id)
Cancel a pending DNS query.
This releases DNS resources used by a pending query.

Parameters
• dns_id – DNS id of the pending query

Returns
0 if ok, <0 if error.

struct dns_addrinfo
#include <dns_resolve.h> Address info struct is passed to callback that gets all the results.

struct dns_resolve_context
#include <dns_resolve.h> DNS resolve context structure.

Public Members

struct sockaddr dns_server
DNS server information.

struct net_context *net_ctx
Connection to the DNS server.

uint8_t is_mdns
Is this server mDNS one.

uint8_t is_llmnr
Is this server LLMNR one.

struct k_mutex lock
Prevent concurrent access.

k_timeout_t buf_timeout
This timeout is also used when a buffer is required from the buffer pools.

enum dns_resolve_context_state state
Is this context in use.

struct dns_pending_query
#include <dns_resolve.h> Result callbacks.
We have multiple callbacks here so that it is possible to do multiple queries at the same time.
Contents of this structure can be inspected and changed only when the lock is held.
Public Members

struct k_work_delayable timer
    Timeout timer.

struct dns_resolve_context *ctx
    Back pointer to ctx, needed in timeout handler.

dns_resolve_cb_t cb
    Result callback.
    A null value indicates the slot is not in use.

void *user_data
    User data.

k_timeout_t timeout
    TX timeout.

const char *query
    String containing the thing to resolve like www.example.com.
    This is set to a non-null value when the query is started, and is not used thereafter.

    If the query completed at a point where the work item was still pending the pointer is cleared to indicate that the query is complete, but release of the query slot will be deferred until a request for a slot determines that the work item has been released.

enum dns_query_type query_type
    Query type.

uint16_t id
    DNS id of this query.

uint16_t query_hash
    Hash of the DNS name + query type we are querying.
    This hash is calculated so we can match the response that we are receiving.
    This is needed mainly for mDNS which is setting the DNS id to 0, which means that the id alone cannot be used to find correct pending query.

Network Management

- Overview
- Requesting a defined procedure
- Listening to network events
- Defining a network management procedure
- Signaling a network event
Overview. The Network Management APIs allow applications, as well as network layer code itself, to call defined network routines at any level in the IP stack, or receive notifications on relevant network events. For example, by using these APIs, application code can request a scan be done on a Wi-Fi- or Bluetooth-based network interface, or request notification if a network interface IP address changes.

The Network Management API implementation is designed to save memory by eliminating code at build time for management routines that are not used. Distinct and statically defined APIs for network management procedures are not used. Instead, defined procedure handlers are registered by using a `NET_MGMT_REGISTER_REQUEST_HANDLER` macro. Procedure requests are done through a single `net_mgmt()` API that invokes the registered handler for the corresponding request.

The current implementation is experimental and may change and improve in future releases.

Requesting a defined procedure. All network management requests are of the form `net_mgmt(mgmt_request, ...)`. The `mgmt_request` parameter is a bit mask that tells which stack layer is targeted, if a `net_if` object is implied, and the specific management procedure being requested. The available procedure requests depend on what has been implemented in the stack.

To avoid extra cost, all `net_mgmt()` calls are direct. Though this may change in a future release, it will not affect the users of this function.

Listening to network events. You can receive notifications on network events by registering a callback function and specifying a set of events used to filter when your callback is invoked. The callback will have to be unique for a pair of layer and code, whereas on the command part it will be a mask of events.

At runtime two functions are available, `net_mgmt_add_event_callback()` for registering the callback function, and `net_mgmt_del_event_callback()` for unregistering a callback. A helper function, `net_mgmt_init_event_callback()`, can be used to ease the initialization of the callback structure.

Additionally `NET_MGMT_REGISTER_EVENT_HANDLER` can be used to register a callback handler at compile time.

When an event occurs that matches a callback's event set, the associated callback function is invoked with the actual event code. This makes it possible for different events to be handled by the same callback function, if desired.

Warning: Event set filtering allows false positives for events that have the same layer and layer code. A callback handler function must check the event code (passed as an argument) against the specific network events it will handle, regardless of how many events were in the set passed to `net_mgmt_init_event_callback()`.

Note that in order to receive events from multiple layers, one must have multiple listeners registered, one for each layer being listened. The callback handler function can be shared between different layer events.

(False positives can occur for events which have the same layer and layer code.)

An example follows.
/*
 * Set of events to handle.
 * See e.g. include/net/net_event.h for some NET_EVENT_xxx values.
 */
#define EVENT_IFACE_SET (NET_EVENT_IF_xxx | NET_EVENT_IF_yyy)
#define EVENT_IPV4_SET (NET_EVENT_IPV4_xxx | NET_EVENT_IPV4_yyy)

struct net_mgmt_event_callback iface_callback;
struct net_mgmt_event_callback ipv4_callback;

void callback_handler(struct net_mgmt_event_callback *cb,
                      uint32_t mgmt_event,
                      struct net_if *iface)
{
    if (mgmt_event == NET_EVENT_IF_xxx) {
        /* Handle NET_EVENT_IF_xxx */
    } else if (mgmt_event == NET_EVENT_IF_yyy) {
        /* Handle NET_EVENT_IF_yyy */
    } else if (mgmt_event == NET_EVENT_IPV4_xxx) {
        /* Handle NET_EVENT_IPV4_xxx */
    } else if (mgmt_event == NET_EVENT_IPV4_yyy) {
        /* Handle NET_EVENT_IPV4_yyy */
    } else {
        /* Spurious (false positive) invocation. */
    }
}

void register_cb(void)
{
    net_mgmt_init_event_callback(&iface_callback, callback_handler,
                                  EVENT_IFACE_SET);
    net_mgmt_init_event_callback(&ipv4_callback, callback_handler,
                                  EVENT_IPV4_SET);
    net_mgmt_add_event_callback(&iface_callback);
    net_mgmt_add_event_callback(&ipv4_callback);
}

Or similarly using NET_MGMT_REGISTER_EVENT_HANDLER.

Note: The info and info_length arguments are only usable if CONFIG_NET_MGMT_EVENT_INFO is enabled. Otherwise these are NULL and zero.

static void event_handler(uint32_t mgmt_event, struct net_if *iface,
                          void *info, size_t info_length,
                          void *user_data)
{
    if (mgmt_event == NET_EVENT_IF_xxx) {
        /* Handle NET_EVENT_IF_xxx */
    } else if (mgmt_event == NET_EVENT_IF_yyy) {
        /* Handle NET_EVENT_IF_yyy */
    } else if (mgmt_event == NET_EVENT_IPV4_xxx) {
        /* Handle NET_EVENT_IPV4_xxx */
    } else if (mgmt_event == NET_EVENT_IPV4_yyy) {
        /* Handle NET_EVENT_IPV4_yyy */
    } else {
        /* Spurious (false positive) invocation. */
    }
}
} else {
    /* Spurious (false positive) invocation. */
}

NET_MGMT_REGISTER_EVENT_HANDLER(iface_event_handler, EVENT_IFACE_SET, event_handler, NULL);
NET_MGMT_REGISTER_EVENT_HANDLER(ipv4_event_handler, EVENT_IPV4_SET, event_handler, NULL);

See include/zephyr/net/net_event.h for available generic core events that can be listened to.

**Defining a network management procedure** You can provide additional management procedures specific to your stack implementation by defining a handler and registering it with an associated mgmt_request code.

Management request code are defined in relevant places depending on the targeted layer or eventually, if L2 is the layer, on the technology as well. For instance, all IP layer management request code will be found in the include/zephyr/net/net_event.h header file. But in case of an L2 technology, let's say Ethernet, these would be found in include/zephyr/net/ethernet.h

You define your handler modeled with this signature:

```
static int your_handler(uint32_t mgmt_event, struct net_if *iface, void *data, size_t len);
```

and then register it with an associated mgmt_request code:

```
NET_MGMT_REGISTER_REQUEST_HANDLER(<mgmt_request code>, your_handler);
```

This new management procedure could then be called by using:

```
net_mgmt(<mgmt_request code>, ...);
```

**Signaling a network event** You can signal a specific network event using the net_mgmt_event_notify() function and provide the network event code. See include/zephyr/net/net_mgmt.h for details. As for the management request code, event code can be also found on specific L2 technology mgmt headers, for example include/zephyr/net/ieee802154_mgmt.h would be the right place if 802.15.4 L2 is the technology one wants to listen to events.

**API Reference**

**Related code samples**

**DHCPv4 client**
Start a DHCPv4 client to obtain an IPv4 address from a DHCPv4 server.

**DNS resolve**
Resolve an IP address for a given hostname.

**IPv4 autoconf client**
Perform IPv4 autoconfiguration and self-assign a random IPv4 address.

**Telnet console**
Access Zephyr shell over telnet.
group net_mgmt

Network Management.

Defines

net_mgmt(_mgmt_request, _iface, _data, _len)

NET_MGMT_DEFINE_REQUEST_HANDLER(_mgmt_request)

NET_MGMT_REGISTER_REQUEST_HANDLER(_mgmt_request, _func)

NET_MGMT_REGISTER_EVENT_HANDLER(_name, _event_mask, _func, _user_data)

Define a static network event handler.

Parameters

• _name – Name of the event handler.
• _event_mask – A mask of network events on which the passed handler should be called in case those events come. Note that only the command part is treated as a mask, matching one to several commands. Layer and layer code will be made of an exact match. This means that in order to receive events from multiple layers, one must have multiple listeners registered, one for each layer being listened.
• _func – The function to be called upon network events being emitted.
• _user_data – User data passed to the handler being called on network events.

Typedefs

typedef int (*net_mgmt_request_handler_t)(uint32_t mgmt_request, struct net_if *iface, void *data, size_t len)

Signature which all Net MGMT request handler need to follow.

Param mgmt_request
The exact request value the handler is being called through

Param iface
A valid pointer on struct net_if if the request is meant to be tight to a network interface. NULL otherwise.

Param data
A valid pointer on a data understood by the handler. NULL otherwise.

Param len
Length in byte of the memory pointed by data.

typedef void (*net_mgmt_event_handler_t)(struct net_mgmt_event_callback *cb, uint32_t mgmt_event, struct net_if *iface)

Define the user's callback handler function signature.

Param cb
Original struct net_mgmt_event_callback owning this handler.

Param mgmt_event
The network event being notified.
## Param iface
A pointer on a struct `net_if` to which the event belongs to, if it's an event on an iface. NULL otherwise.

typedef void (*net_mgmt_event_static_handler_t)(uint32_t mgmt_event, struct net_if *iface, void *info, size_t info_length, void *user_data)

Define the user's callback handler function signature.

### Param mgmt_event
The network event being notified.

### Param iface
A pointer on a struct `net_if` to which the event belongs to, if it's an event on an iface. NULL otherwise.

### Param info
A valid pointer on a data understood by the handler. NULL otherwise.

### Param info_length
Length in bytes of the memory pointed by `info`.

### Param user_data
Data provided by the user to the handler.

## Functions

### static inline void net_mgmt_init_event_callback(struct net_mgmt_event_callback *cb, net_mgmt_event_handler_t handler, uint32_t mgmt_event_mask)
Helper to initialize a struct `net_mgmt_event_callback` properly.

**Parameters**
- `cb` – A valid application's callback structure pointer.
- `handler` – A valid handler function pointer.
- `mgmt_event_mask` – A mask of relevant events for the handler

### void net_mgmt_add_event_callback(struct net_mgmt_event_callback *cb)
Add a user callback.

**Parameters**
- `cb` – A valid pointer on user's callback to add.

### void net_mgmt_del_event_callback(struct net_mgmt_event_callback *cb)
Delete a user callback.

**Parameters**
- `cb` – A valid pointer on user's callback to delete.

### void net_mgmt_event_notify_with_info(uint32_t mgmt_event, struct net_if *iface, const void *info, size_t length)
Used by the system to notify an event.

**Note:** info and length are disabled if CONFIG_NET_MGMT_EVENT_INFO is not defined.

**Parameters**
- `mgmt_event` – The actual network event code to notify
• iface – a valid pointer on a struct net_if if only the event is based on an iface. NULL otherwise.
• info – a valid pointer on the information you want to pass along with the event. NULL otherwise. Note the data pointed there is normalized by the related event.
• length – size of the data pointed by info pointer.

static inline void net_mgmt_event_notify(uint32_t mgmt_event, struct net_if *iface)

int net_mgmt_event_wait(uint32_t mgmt_event_mask, uint32_t *raised_event, struct net_if **iface, const void **info, size_t *info_length, k_timeout_t timeout)

Used to wait synchronously on an event mask.

Parameters
• mgmt_event_mask – A mask of relevant events to wait on.
• raised_event – a pointer on a uint32_t to get which event from the mask generated the event. Can be NULL if the caller is not interested in that information.
• iface – a pointer on a place holder for the iface on which the event has originated from. This is valid if only the event mask has bit NET_MGMT_IFACE_BIT set relevantly, depending on events the caller wants to listen to.
• info – a valid pointer if user wants to get the information the event might bring along. NULL otherwise.
• info_length – tells how long the info memory area is. Only valid if the info is not NULL.
• timeout – A timeout delay. K_FOREVER can be used to wait indefinitely.

Returns
0 on success, a negative error code otherwise. -ETIMEDOUT will be specifically returned if the timeout kick-in instead of an actual event.

int net_mgmt_event_wait_on_iface(struct net_if *iface, uint32_t mgmt_event_mask, uint32_t *raised_event, const void **info, size_t *info_length, k_timeout_t timeout)

Used to wait synchronously on an event mask for a specific iface.

Parameters
• iface – a pointer on a valid network interface to listen event to
• mgmt_event_mask – A mask of relevant events to wait on. Listened to events should be relevant to iface events and thus have the bit NET_MGMT_IFACE_BIT set.
• raised_event – a pointer on a uint32_t to get which event from the mask generated the event. Can be NULL if the caller is not interested in that information.
• info – a valid pointer if user wants to get the information the event might bring along. NULL otherwise.
• info_length – tells how long the info memory area is. Only valid if the info is not NULL.
• timeout – A timeout delay. K_FOREVER can be used to wait indefinitely.
Returns

0 on success, a negative error code otherwise. -ETIMEDOUT will be specifically returned if the timeout kick-in instead of an actual event.

void net_mgmt_event_init(void)

Used by the core of the network stack to initialize the network event processing.

struct net_event_ipv6_addr
#include <net_event.h> Network Management event information structure Used to pass information on network events like NET_EVENT_IPV6_ADDR_ADD, NET_EVENT_IPV6_ADDR_DEL, NET_EVENT_IPV6_MADDR_ADD and NET_EVENT_IPV6_MADDR_DEL when CONFIG_NET_MGMT_EVENT_INFO enabled and event generator pass the information.

struct net_event_ipv6_nbr
#include <net_event.h> Network Management event information structure Used to pass information on network events like NET_EVENT_IPV6_NBR_ADD and NET_EVENT_IPV6_NBR_DEL when CONFIG_NET_MGMT_EVENT_INFO enabled and event generator pass the information.

Note: : idx will be ‘-1’ in case of NET_EVENT_IPV6_NBR_DEL event.

struct net_event_ipv6_route
#include <net_event.h> Network Management event information structure Used to pass information on network events like NET_EVENT_IPV6_ROUTE_ADD and NET_EVENT_IPV6_ROUTE_DEL when CONFIG_NET_MGMT_EVENT_INFO enabled and event generator pass the information.

struct net_event_ipv6_prefix
#include <net_event.h> Network Management event information structure Used to pass information on network events like NET_EVENT_IPV6_PREFIX_ADD and NET_EVENT_IPV6_PREFIX_DEL when CONFIG_NET_MGMT_EVENT_INFO is enabled and event generator pass the information.

struct net_event_l4_hostname
#include <net_event.h> Network Management event information structure Used to pass information on NET_EVENT_HOSTNAME_CHANGED event when CONFIG_NET_MGMT_EVENT_INFO is enabled and event generator pass the information.

struct net_mgmt_event_callback
#include <net_mgmt.h> Network Management event callback structure Used to register a callback into the network management event part, in order to let the owner of this struct to get network event notification based on given event mask.

Public Members

sys_snnode_t node

Meant to be used internally, to insert the callback into a list.

So nobody should mess with it.
net_mgmt_event_handler_t handler

Actual callback function being used to notify the owner.

struct k_sem *sync_call

Semaphore meant to be used internally for the synchronous net_mgmt_event_wait() function.

uint32_t event_mask

A mask of network events on which the above handler should be called in case those events come.

Note that only the command part is treated as a mask, matching one to several commands. Layer and layer code will be made of an exact match. This means that in order to receive events from multiple layers, one must have multiple listeners registered, one for each layer being listened.

uint32_t raised_event

Internal place holder when a synchronous event wait is successfully unlocked on a event.

union net_mgmt_event_callback

A mask of network events on which the above handler should be called in case those events come.

Such mask can be modified whenever necessary by the owner, and thus will affect the handler being called or not.

Network Statistics

- Overview
- API Reference

Overview

Network statistics are collected if CONFIG_NET_STATISTICS is set. Individual component statistics for IPv4 or IPv6 can be turned off if those statistics are not needed. See various options in subsys/net/ip/Kconfig.stats file for details.

By default, the system collects network statistics per network interface. This can be controlled by CONFIG_NET_STATISTICS_PER_INTERFACE option.

The CONFIG_NET_STATISTICS_USER_API option can be set if the application wants to collect statistics for further processing. The network management interface API is used for that. See Network Management for details.

The CONFIG_NET_STATISTICS ETHERNET option can be set to collect generic Ethernet statistics. If the CONFIG_NET_STATISTICS_ETHERNET_VENDOR option is set, then Ethernet device driver can collect Ethernet device specific statistics. These statistics can then be transferred to application for processing.

If the CONFIG_NET_SHELL option is set, then network shell can show statistics information with net stats command.
**Network statistics**
Query and display network statistics from a user application.

**Wi-Fi shell**
Test Wi-Fi functionality using the Wi-Fi shell module.

```c

// net_stats.h

// Defines
#define NET_TC_TX_STATS_COUNT
#define NET_TC_RX_STATS_COUNT

// Typedefs
typedef uint32_t net_stats_t;
// Network statistics counter.

struct net_stats_bytes
#include <net_stats.h> // Number of bytes sent and received.

// Public Members
net_stats_t sent
// Number of bytes sent.

net_stats_t received
// Number of bytes received.

struct net_stats_pkts
#include <net_stats.h> // Number of network packets sent and received.

// Public Members
net_stats_t tx
// Number of packets sent.

net_stats_t rx
// Number of packets received.

struct net_stats_ip
#include <net_stats.h> // IP layer statistics.
```

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Public Members

`net_stats_t recv`
Number of received packets at the IP layer.

`net_stats_t sent`
Number of sent packets at the IP layer.

`net_stats_t forwarded`
Number of forwarded packets at the IP layer.

`net_stats_t drop`
Number of dropped packets at the IP layer.

```
struct net_stats_ip_errors
#include <net_stats.h> IP layer error statistics.
```

Public Members

`net_stats_t vhlerr`
Number of packets dropped due to wrong IP version or header length.

`net_stats_t hblenerr`
Number of packets dropped due to wrong IP length, high byte.

`net_stats_t lblenerr`
Number of packets dropped due to wrong IP length, low byte.

`net_stats_t fragerr`
Number of packets dropped because they were IP fragments.

`net_stats_t chkerr`
Number of packets dropped due to IP checksum errors.

`net_stats_t protoerr`
Number of packets dropped because they were neither ICMP, UDP nor TCP.

```
struct net_stats_icmp
#include <net_stats.h> ICMP statistics.
```

Public Members

`net_stats_t recv`
Number of received ICMP packets.

`net_stats_t sent`
Number of sent ICMP packets.
`net_stats_t drop`
  Number of dropped ICMP packets.

`net_stats_t typeerr`
  Number of ICMP packets with a wrong type.

`net_stats_t chkerr`
  Number of ICMP packets with a bad checksum.

```c
struct net_stats_tcp
#include <net_stats.h> TCP statistics.
```

**Public Members**

```c
struct net_stats_bytes bytes
Amount of received and sent TCP application data.

net_stats_t resent
Amount of retransmitted data.

net_stats_t drop
Number of dropped packets at the TCP layer.

net_stats_t recv
Number of received TCP segments.

net_stats_t sent
Number of sent TCP segments.

net_stats_t seg_drop
Number of dropped TCP segments.

net_stats_t chkerr
Number of TCP segments with a bad checksum.

net_stats_t acknowl
Number of received TCP segments with a bad ACK number.

net_stats_t rsterr
Number of received bad TCP RST (reset) segments.

net_stats_t rst
Number of received TCP RST (reset) segments.

net_stats_t rexmit
Number of retransmitted TCP segments.
net_stats_t conndrop
Number of dropped connection attempts because too few connections were available.

net_stats_t connrst
Number of connection attempts for closed ports, triggering a RST.

struct net_stats_udp
#include <net_stats.h> UDP statistics.

Public Members

net_stats_t drop
Number of dropped UDP segments.

net_stats_t recv
Number of received UDP segments.

net_stats_t sent
Number of sent UDP segments.

net_stats_t chkerr
Number of UDP segments with a bad checksum.

struct net_stats_ipv6_nd
#include <net_stats.h> IPv6 neighbor discovery statistics.

struct net_stats_ipv6_mld
#include <net_stats.h> IPv6 multicast listener daemon statistics.

Public Members

net_stats_t recv
Number of received IPv6 MLD queries.

net_stats_t sent
Number of sent IPv6 MLD reports.

net_stats_t drop
Number of dropped IPv6 MLD packets.

struct net_stats_ipv4_igmp
#include <net_stats.h> IPv4 IGMP daemon statistics.
Public Members

*net_stats_t* `recv`
Number of received IPv4 IGMP queries.

*net_stats_t* `sent`
Number of sent IPv4 IGMP reports.

*net_stats_t* `drop`
Number of dropped IPv4 IGMP packets.

```c
struct net_stats_tx_time
#include <net_stats.h> Network packet transfer times for calculating average TX time.

struct net_stats_rx_time
#include <net_stats.h> Network packet receive times for calculating average RX time.

struct net_stats_tc
#include <net_stats.h> Traffic class statistics.

struct net_stats_pm
#include <net_stats.h> Power management statistics.

struct net_stats
#include <net_stats.h> All network statistics in one struct.
```

Public Members

*net_stats_t* `processing_error`
Count of malformed packets or packets we do not have handler for.

```c
struct net_stats_bytes bytes
This calculates amount of data transferred through all the network interfaces.

struct net_stats_ip_errors ip_errors
IP layer errors.

struct net_stats_eth_errors
#include <net_stats.h> Ethernet error statistics.

struct net_stats_eth_flow
#include <net_stats.h> Ethernet flow control statistics.

struct net_stats_eth_csum
#include <net_stats.h> Ethernet checksum statistics.

struct net_stats_eth_hw_timestamp
#include <net_stats.h> Ethernet hardware timestamp statistics.
```
struct net_stats_eth
   #include <net_stats.h> All Ethernet specific statistics.

struct net_stats_ppp
   #include <net_stats.h> All PPP specific statistics.

Public Members

net_stats_t drop
   Number of received and dropped PPP frames.

net_stats_t chkerr
   Number of received PPP frames with a bad checksum.

struct net_stats_sta_mgmt
   #include <net_stats.h> All Wi-Fi management statistics.

Public Members

net_stats_t beacons_rx
   Number of received beacons.

net_stats_t beacons_miss
   Number of missed beacons.

struct net_stats_wifi
   #include <net_stats.h> All Wi-Fi specific statistics.

Network Timeout

Overview
Zephyr's network infrastructure mostly uses the millisecond-resolution uptime clock to track timeouts, with both deadlines and durations measured with 32-bit unsigned values. The 32-bit value rolls over at 49 days 17 hours 2 minutes 47.296 seconds.

Timeout processing is often affected by latency, so that the time at which the timeout is checked may be some time after it should have expired. Handling this correctly without arbitrary expectations of maximum latency requires that the maximum delay that can be directly represented be a 31-bit non-negative number (INT32_MAX), which overflows at 24 days 20 hours 31 minutes 23.648 seconds.

Most network timeouts are shorter than the delay rollover, but a few protocols allow for delays that are represented as unsigned 32-bit values counting seconds, which corresponds to a 42-bit millisecond count.
The net_timeout API provides a generic timeout mechanism to correctly track the remaining time for these extended-duration timeouts.

**Use**  The simplest use of this API is:

1. Configure a network timeout using `net_timeout_set()`.
2. Use `net_timeout_evaluate()` to determine how long it is until the timeout occurs. Schedule a timeout to occur after this delay.
3. When the timeout callback is invoked, use `net_timeout_evaluate()` again to determine whether the timeout has completed, or whether there is additional time remaining. If the latter, reschedule the callback.
4. While the timeout is running, use `net_timeout_remaining()` to get the number of seconds until the timeout expires. This may be used to explicitly update the timeout, which should be done by canceling any pending callback and restarting from step 1 with the new timeout.

The `net_timeout` contains a `sys_snode_t` that allows multiple timeout instances to be aggregated to share a single kernel timer element. The application must use `net_timeout_evaluate()` on all instances to determine the next timeout event to occur.

`net_timeout_deadline()` may be used to reconstruct the full-precision deadline of the timeout. This exists primarily for testing but may have use in some applications, as it does allow a millisecond-resolution calculation of remaining time.

**API Reference**

`group net_timeout`

Network long timeout primitives and helpers.

**Defines**

`NET_TIMEOUT_MAX_VALUE`

Divisor used to support ms resolution timeouts.

Because delays are processed in work queues which are not invoked synchronously with clock changes we need to be able to detect timeouts after they occur, which requires comparing “deadline” to “now” with enough “slop” to handle any observable latency due to “now” advancing past “deadline”.

The simplest solution is to use the native conversion of the well-defined 32-bit unsigned difference to a 32-bit signed difference, which caps the maximum delay at INT32_MAX. This is compatible with the standard mechanism for detecting completion of deadlines that do not overflow their representation.

**Functions**

`void net_timeout_set(struct net_timeout *timeout, uint32_t lifetime, uint32_t now)`

Configure a network timeout structure.

**Parameters**

- `timeout` – a pointer to the timeout state.
- `lifetime` – the duration of the timeout in seconds.
- `now` – the time at which the timeout started counting down, in milliseconds. This is generally a captured value of `k_uptime_get_320`. 
int64_t net_timeout_deadline(const struct net_timeout *timeout, int64_t now)
Return the 64-bit system time at which the timeout will complete.

**Note:** Correct behavior requires invocation of `net_timeout_evaluate()` at its specified intervals.

**Parameters**

- `timeout` – state a pointer to the timeout state, initialized by `net_timeout_set()` and maintained by `net_timeout_evaluate()`.
- `now` – the full-precision value of `k_uptime_get()` relative to which the deadline will be calculated.

**Returns**

the value of `k_uptime_get()` at which the timeout will expire.

uint32_t net_timeout_remaining(const struct net_timeout *timeout, uint32_t now)
Calculate the remaining time to the timeout in whole seconds.

**Note:** This function rounds the remaining time down, i.e. if the timeout will occur in 3500 milliseconds the value 3 will be returned.

**Note:** Correct behavior requires invocation of `net_timeout_evaluate()` at its specified intervals.

**Parameters**

- `timeout` – a pointer to the timeout state
- `now` – the time relative to which the estimate of remaining time should be calculated. This should be recently captured value from `k_uptime_get_32()`.

**Return values**

- `0` – if the timeout has completed.
- `positive` – the remaining duration of the timeout, in seconds.

uint32_t net_timeout_evaluate(struct net_timeout *timeout, uint32_t now)
Update state to reflect elapsed time and get new delay.

This function must be invoked periodically to (1) apply the effect of elapsed time on what remains of a total delay that exceeded the maximum representable delay, and (2) determine that either the timeout has completed or that the infrastructure must wait a certain period before checking again for completion.

**Parameters**

- `timeout` – a pointer to the timeout state
- `now` – the time relative to which the estimate of remaining time should be calculated. This should be recently captured value from `k_uptime_get_32()`.

**Return values**

- `0` – if the timeout has completed
• positive – the maximum delay until the state of this timeout should be re-evaluated, in milliseconds.

```c
struct net_timeout
#include <net_timeout.h> Generic struct for handling network timeouts.
```

Except for the linking node, all access to state from these objects must go through the defined API.

### Public Members

```c
sys_snode_t node
```

Used to link multiple timeouts that share a common timer infrastructure.

For examples a set of related timers may use a single delayed work structure, which is always scheduled at the shortest time to a timeout event.

### Networking Context

The net_context API is not meant for application use. Application should use BSD Sockets API instead.

### Promiscuous Mode

#### Overview

Promiscuous mode is a mode for a network interface controller that causes it to pass all traffic it receives to the application rather than passing only the frames that the controller is specifically programmed to receive. This mode is normally used for packet sniffing as used to diagnose network connectivity issues by showing an application all the data being transferred over the network. (See the Wikipedia article on promiscuous mode for more information.)

The network promiscuous APIs are used to enable and disable this mode, and to wait for and receive a network data to arrive. Not all network technologies or network device drivers support promiscuous mode.

#### Sample usage

First the promiscuous mode needs to be turned ON by the application like this:

```c
ret = net_promisc_mode_on(iface);
if (ret < 0) {
    if (ret == -EALREADY) {
        printf("Promiscuous mode already enabled\n");
    } else {
        printf("Cannot enable promiscuous mode for ",
              "interface %p (%d)\n", iface, ret);
    }
}
```

If there is no error, then the application can start to wait for network data:
```
while (true) {
    pkt = net_promisc_mode_wait_data(K_FOREVER);
    if (pkt) {
        print_info(pkt);
    }
    net_pkt_unref(pkt);
}
```

Finally the promiscuous mode can be turned OFF by the application like this:

```
ret = net_promisc_mode_off(iface);
if (ret < 0) {
    if (ret == -EALREADY) {
        printf("Promiscuous mode already disabled\n");
    } else {
        printf("Cannot disable promiscuous mode for "
            "interface %p (%d)\n", iface, ret);
    }
}
```

See net-promiscuous-mode for a more comprehensive example.

### API Reference

#### Related code samples

**Promiscuous mode**

Enable promiscuous mode on all interfaces and print information about incoming packets.

**group promiscuous**

Promiscuous mode support.

**Functions**

- static inline struct *net_pkt* net_promisc_mode_wait_data(*k_timeout_t* timeout)
  
  Start to wait received network packets.

  **Parameters**

  - `timeout` – How long to wait before returning.

  **Returns**

  Received `net_pkt`, NULL if not received any packet.

- static inline int net_promisc_mode_on(struct *net_if* iface)
  
  Enable promiscuous mode for a given network interface.

  **Parameters**

  - `iface` – Network interface

  **Returns**

  0 if ok, <0 if error

- static inline int net_promisc_mode_off(struct *net_if* iface)
  
  Disable promiscuous mode for a given network interface.

  **Parameters**

  - `iface` – Network interface
Simple Network Time Protocol Library

Overview  The SNTP library implements IETF RFC4330 (Simple Network Time Protocol v4). SNTP provides a way to synchronize clocks in computer networks.

API Reference  

Related code samples  

AWS IoT Core MQTT  
Connect to AWS IoT Core and publish messages using MQTT.

SNTP client  
Use SNTP to get the current time from the host.

group snntp  
Simple Network Time Protocol API.

Functions  

int snntp_init(struct snntp_ctx *ctx, struct sockaddr *addr, socklen_t addr_len)  
Initialize SNTP context.

Parameters  

- ctx – Address of sntp context.
- addr – IP address of NTP/SNTP server.
- addr_len – IP address length of NTP/SNTP server.

Returns  

0 if ok, <0 if error.

int snntp_query(struct snntp_ctx *ctx, uint32_t timeout, struct snntp_time *time)  
Perform SNTP query.

Parameters  

- ctx – Address of sntp context.
- timeout – Timeout of waiting for sntp response (in milliseconds).
- time – Timestamp including integer and fractional seconds since 1 Jan 1970 (output).

Returns  

0 if ok, <0 if error (-ETIMEDOUT if timeout).
void sntp_close(struct sntp_ctx *ctx)
   Release SNTP context.

   Parameters
   • ctx – Address of sntp context.

int sntp_simple(const char *server, uint32_t timeout, struct sntp_time *time)
   Convenience function to query SNTP in one-shot fashion.

   Convenience wrapper which calls getaddrinfo(), sntp_init(), sntp_query(), and sntp_close().

   Parameters
   • server – Address of server in format addr[:port]
   • timeout – Query timeout
   • time – Timestamp including integer and fractional seconds since 1 Jan 1970 (output).

   Returns
   0 if ok, <0 if error (-ETIMEDOUT if timeout).

struct sntp_time
   #include <sntp.h> Time as returned by SNTP API, fractional seconds since 1 Jan 1970.

struct sntp_ctx
   #include <sntp.h> SNTP context.

Public Members

struct sntp_time expected_orig_ts
   Timestamp when the request was sent from client to server.

   This is used to check if the originated timestamp in the server reply matches the one in client request.

SOCKS5 Proxy Support

• Overview
• SOCKS5 API
• SOCKS5 Proxy Usage in MQTT

Overview    The SOCKS library implements SOCKS5 support, which allows Zephyr to connect to peer devices via a network proxy.

See this SOCKS5 Wikipedia article for a detailed overview of how SOCKS5 works.

For more information about the protocol itself, see IETF RFC1928 SOCKS Protocol Version 5.
SOCKS5 API  The SOCKS5 support is enabled by CONFIG_SOCKS Kconfig variable. Application wanting to use the SOCKS5 must set the SOCKS5 proxy host address by calling setsockopt() like this:

```c
static int set_proxy(int sock, const struct sockaddr *proxy_addr,
    socklen_t proxy_addrlen)
{
    int ret;
    ret = setsockopt(sock, SOL_SOCKET, SO_SOCKS5, proxy_addr, proxy_addrlen);
    if (ret < 0) {
        return -errno;
    }
    return 0;
}
```

SOCKS5 Proxy Usage in MQTT  For MQTT client, there is mqtt_client_set_proxy() API that the application can call to setup SOCKS5 proxy. See mqtt-publisher sample application for usage example.

Trickle Timer Library

- **Overview**
- **API Reference**

Overview  The Trickle timer library implements IETF RFC6206 (Trickle Algorithm). The Trickle algorithm allows nodes in a lossy shared medium (e.g., low-power and lossy networks) to exchange information in a highly robust, energy efficient, simple, and scalable manner.

API Reference

group trickle
    Trickle algorithm library.

Typedefs

typedef void (*net_trickle_cb_t)(struct net_trickle *trickle, bool do_suppress, void *user_data)
    Trickle timer callback.
The callback is called after Trickle timeout expires.

    **Param trickle**
    The trickle context to use.

    **Param do_suppress**
    Is TX allowed (true) or not (false).

    **Param user_data**
    The user data given in net_trickle_start() call.
Functions

int net_trickle_create(struct net_trickle *trickle, uint32_t Imin, uint8_t Imax, uint8_t k)
Create a Trickle timer.

Parameters
• trickle – Pointer to Trickle struct.
• Imin – Imin configuration parameter in ms.
• Imax – Max number of doublings.
• k – Redundancy constant parameter. See RFC 6206 for details.

Returns
Return 0 if ok and <0 if error.

int net_trickle_start(struct net_trickle *trickle, net_trickle_cb_t cb, void *user_data)
Start a Trickle timer.

Parameters
• trickle – Pointer to Trickle struct.
• cb – User callback to call at time T within the current trickle interval
• user_data – User pointer that is passed to callback.

Returns
Return 0 if ok and <0 if error.

int net_trickle_stop(struct net_trickle *trickle)
Stop a Trickle timer.

Parameters
• trickle – Pointer to Trickle struct.

Returns
Return 0 if ok and <0 if error.

void net_trickle_consistency(struct net_trickle *trickle)
To be called by the protocol handler when it hears a consistent network transmission.

Parameters
• trickle – Pointer to Trickle struct.

void net_trickle_inconsistency(struct net_trickle *trickle)
To be called by the protocol handler when it hears an inconsistent network transmission.

Parameters
• trickle – Pointer to Trickle struct.

static inline bool net_trickle_is_running(struct net_trickle *trickle)
Check if the Trickle timer is running or not.

Parameters
• trickle – Pointer to Trickle struct.

Returns
Return True if timer is running and False if not.
struct net_trickle

#include <trickle.h> The variable names are taken directly from RFC 6206 when applicable.

Note that the struct members should not be accessed directly but only via the Trickle API.

Public Members

uint32_t Imin
    Min interval size in ms.

uint8_t Imax
    Max number of doublings.

uint8_t k
    Redundancy constant.

uint32_t I
    Current interval size.

uint32_t Istart
    Start of the interval in ms.

uint8_t c
    Consistency counter.

uint32_t Imax_abs
    Max interval size in ms (not doublings)

net_trickle_cb_t cb
    Callback to be called when timer expires.

Websocket Client API

- Overview
- Websocket Transport
- API Reference

Overview  The Websocket client library allows Zephyr to connect to a Websocket server. The Websocket client API can be used directly by application to establish a Websocket connection to server, or it can be used as a transport for other network protocols like MQTT.

See this Websocket Wikipedia article for a detailed overview of how Websocket works.
For more information about the protocol itself, see IETF RFC6455 The WebSocket Protocol.
Websocket Transport  The Websocket API allows it to be used as a transport for other high level protocols like MQTT. The Zephyr MQTT client library can be configured to use Websocket transport by enabling CONFIG_MQTT_LIB_WEBSOCKET and CONFIG_WEBSOCKET_CLIENT Kconfig options.

First a socket needs to be created and connected to the Websocket server:

```c
sock = socket(family, SOCK_STREAM, IPPROTO_TCP);
...
ret = connect(sock, addr, addr_len);
...```

The Websocket transport socket is then created like this:

```c
ws_sock = websocket_connect(sock, &config, timeout, user_data);
```

The Websocket transport socket can then be used to send or receive data, and the Websocket client API will encapsulate the sent or received data to/from Websocket packet payload. Both the websocket_xxx() API or normal BSD socket API functions can be used to send and receive application data.

```c
ret = websocket_send_msg(ws_sock, buf_to_send, buf_len, WEBSOCKET_OPCODE_DATA_BINARY, true, true, K_FOREVER);
...
ret = send(ws_sock, buf_to_send, buf_len, 0);
```

If normal BSD socket functions are used, then currently only TEXT data is supported. In order to send BINARY data, the websocket_send_msg() must be used.

When done, the Websocket transport socket must be closed. User should handle the lifecycle(close/reuse) of tcp socket after websocket_disconnect.

```c
ret = close(ws_sock);
or
ret = websocket_disconnect(ws_sock);
```

API Reference

Related code samples

WebSocket Client

Implement a Websocket client that connects to a Websocket server.

group websocket

WebSocket API.

Defines

WEBSOCKET_FLAG_FINAL

Message type values.

Returned in websocket_recv_msg() Final frame

WEBSOCKET_FLAG_TEXT

Textual data
WEBSOCKET_FLAG_BINARY
  Binary data

WEBSOCKET_FLAG_CLOSE
  Closing connection.

WEBSOCKET_FLAG_PING
  Ping message

WEBSOCKET_FLAG_PONG
  Pong message

**Typedefs**

typedef int (*websocket_connect_cb_t)(int ws_sock, struct http_request *req, void *user_data)
  Callback called after Websocket connection is established.

  **Param ws_sock**
  Websocket id

  **Param req**
  HTTP handshake request

  **Param user_data**
  A valid pointer on some user data or NULL

  **Return**
  0 if ok, <0 if there is an error and connection should be aborted

**Enums**

enum websocket_opcode
  **Values:**

  enumerator WEBSOCKET_OPCODE_CONTINUE = 0x00

  enumerator WEBSOCKET_OPCODE_DATA_TEXT = 0x01

  enumerator WEBSOCKET_OPCODE_DATA_BINARY = 0x02

  enumerator WEBSOCKET_OPCODE_CLOSE = 0x08

  enumerator WEBSOCKET_OPCODE_PING = 0x09

  enumerator WEBSOCKET_OPCODE_PONG = 0x0A
Functions

```c
int websocket_connect(int http_sock, struct websocket_request *req, int32_t timeout, void *user_data)
```

Connect to a server that provides Websocket service.

The callback is called after connection is established. The returned value is a new socket descriptor that can be used to send / receive data using the BSD socket API.

**Parameters**

- `http_sock` – Socket id to the server. Note that this socket is used to do HTTP handshakes etc. The actual Websocket connectivity is done via the returned websocket id. Note that the http_sock must not be closed after this function returns as it is used to deliver the Websocket packets to the Websocket server.
- `req` – Websocket request. User should allocate and fill the request data.
- `timeout` – Max timeout to wait for the connection. The timeout value is in milliseconds. Value SYS_FOREVER_MS means to wait forever.
- `user_data` – User specified data that is passed to the callback.

**Returns**

Websocket id to be used when sending/receiving Websocket data.

```c
int websocket_send_msg(int ws_sock, const uint8_t *payload, size_t payload_len, enum websocket_opcode opcode, bool mask, bool final, int32_t timeout)
```

Send websocket msg to peer.

The function will automatically add websocket header to the message.

**Parameters**

- `ws_sock` – Websocket id returned by `websocket_connect()`.
- `payload` – Websocket data to send.
- `payload_len` – Length of the data to be sent.
- `opcode` – Operation code (text, binary, ping, pong, close)
- `mask` – Mask the data, see RFC 6455 for details
- `final` – Is this final message for this message send. If final == false, then the first message must have valid opcode and subsequent messages must have opcode WEBSOCKET_OPCODE_CONTINUE. If final == true and this is the only message, then opcode should have proper opcode (text or binary) set.
- `timeout` – How long to try to send the message. The value is in milliseconds. Value SYS_FOREVER_MS means to wait forever.

**Returns**

<0 if error, >=0 amount of bytes sent

```c
int websocket_recv_msg(int ws_sock, uint8_t *buf, size_t buf_len, uint32_t *message_type, uint64_t *remaining, int32_t timeout)
```

Receive websocket msg from peer.

The function will automatically remove websocket header from the message.

**Parameters**

- `ws_sock` – Websocket id returned by `websocket_connect()`.
- `buf` – Buffer where websocket data is read.
• **buf_len** – Length of the data buffer.
• **message_type** – Type of the message.
• **remaining** – How much there is data left in the message after this read.
• **timeout** – How long to try to receive the message. The value is in milliseconds. Value SYS_FOREVER_MS means to wait forever.

**Return values**
• \( \geq 0 \) – amount of bytes received.
• -EAGAIN – on timeout.
• -ENOTCONN – on socket close.
• -errno – other negative errno value in case of failure.

```c
int websocket_disconnect(int ws_sock)
```
Close websocket.
One must call `websocket_connect()` after this call to re-establish the connection.

**Parameters**
• **ws_sock** – Websocket id returned by `websocket_connect()`.

```c
static inline void websocket_init(void)
```

```c
struct websocket_request
```
`#include <websocket.h>` Websocket client connection request.
This contains all the data that is needed when doing a Websocket connection request.

**Public Members**

```c
cnst char *host
```
Host of the Websocket server when doing HTTP handshakes.

```c
cnst char *url
```
URL of the Websocket.

```c
http_header_cb_t optional_headers_cb
```
User supplied callback function to call when optional headers need to be sent.
This can be NULL, in which case the optional_headers field in `http_request` is used.
The idea of this optional_headers callback is to allow user to send more HTTP header data that is practical to store in allocated memory.

```c
cnst char **optional_headers
```
A NULL terminated list of any optional headers that should be added to the HTTP request.
May be NULL. If the optional_headers_cb is specified, then this field is ignored.

```c
websocket_connect_cb_t cb
```
User supplied callback function to call when a connection is established.
const struct http_parser_settings *http_cb
  User supplied list of callback functions if the calling application wants to know the parsing status or the HTTP fields during the handshake.
  This is optional parameter and normally not needed but is useful if the caller wants to know something about the fields that the server is sending.

uint8_t *tmp_buf
  User supplied buffer where HTTP connection data is stored.

size_t tmp_buf_len
  Length of the user supplied temp buffer.

Network Packet Capture

- Overview
- Sample usage
- API Reference

Overview  The net_capture API allows user to monitor the network traffic in one of the Zephyr network interfaces and send that traffic to external system for analysis. The monitoring can be setup either manually using net-shell or automatically by using the net_capture API.

Sample usage  See net-capture sample application and Monitor Network Traffic for details.

API Reference
Related code samples
Network packet capture
  Capture network packets and send them to a remote host via IPIP tunnel.

group net_capture
  Network packet capture support functions.

Functions

int net_capture_setup(const char *remote_addr, const char *my_local_addr, const char *peer_addr, const struct device **dev)
  Setup network packet capturing support.

Parameters

- remote_addr – The value tells the tunnel remote/outer endpoint IP address. The IP address can be either IPv4 or IPv6 address. This address is used to select the network interface where the tunnel is created.
- my_local_addr – The local/inner IP address of the tunnel. Can contain also port number which is used as UDP source port.
• **peer_addr** – The peer/inner IP address of the tunnel. Can contain also port number which is used as UDP destination port.

• **dev** – Network capture device. This is returned to the caller.

**Returns**

0 if ok, <0 if network packet capture setup failed

static inline int net_capture_cleanup(const struct device *dev)

Cleanup network packet capturing support.

This should be called after the capturing is done and resources can be released.

**Parameters**

• **dev** – Network capture device. User must allocate using the `net_capture_setup()` function.

**Returns**

0 if ok, <0 if network packet capture cleanup failed

static inline int net_capture_enable(const struct device *dev, struct net_if *iface)

Enable network packet capturing support.

This creates tunnel network interface where all the captured packets are pushed. The captured network packets are placed in UDP packets that are sent to tunnel peer.

**Parameters**

• **dev** – Network capture device

• **iface** – Network interface we are starting to capture packets.

**Returns**

0 if ok, <0 if network packet capture enable failed

static inline bool net_capture_is_enabled(const struct device *dev)

Is network packet capture enabled or disabled.

**Parameters**

• **dev** – Network capture device

**Returns**

True if enabled, False if network capture is disabled.

static inline int net_capture_disable(const struct device *dev)

Disable network packet capturing support.

**Parameters**

• **dev** – Network capture device

**Returns**

0 if ok, <0 if network packet capture disable failed

### Network Buffer Management

### Network Buffer

- **Overview**
- **Creating buffers**
- **Common Operations**
- **Reference Counting**
Overview  Network buffers are a core concept of how the networking stack (as well as the Bluetooth stack) pass data around. The API for them is defined in include/zephyr/net/buf.h:

Creating buffers  Network buffers are created by first defining a pool of them:

```c
NET_BUF_POOL_DEFINE(pool_name, buf_count, buf_size, user_data_size, NULL);
```

The pool is a static variable, so if it’s needed to be exported to another module a separate pointer is needed.

Once the pool has been defined, buffers can be allocated from it with:

```c
buf = net_buf_alloc(&pool_name, timeout);
```

There is no explicit initialization function for the pool or its buffers, rather this is done implicitly as `net_buf_alloc()` gets called.

If there is a need to reserve space in the buffer for protocol headers to be prepended later, it’s possible to reserve this headroom with:

```c
net_buf_reserve(buf, headroom);
```

In addition to actual protocol data and generic parsing context, network buffers may also contain protocol-specific context, known as user data. Both the maximum data and user data capacity of the buffers is compile-time defined when declaring the buffer pool.

The buffers have native support for being passed through `k_fifo` kernel objects. This is a very practical feature when the buffers need to be passed from one thread to another. However, since a `net_buf` may have a fragment chain attached to it, instead of using the `k_fifo_put()` and `k_fifo_get()` APIs, special `net_buf_put()` and `net_buf_get()` APIs must be used when passing buffers through FIFOs. These APIs ensure that the buffer chains stay intact. The same applies for passing buffers through a singly linked list, in which case the `net_buf_slist_put()` and `net_buf_slist_get()` functions must be used instead of `sys_slist_append()` and `sys_slist_get()`.

Common Operations  The network buffer API provides some useful helpers for encoding and decoding data in the buffers. To fully understand these helpers it’s good to understand the basic names of operations used with them:

Add  Add data to the end of the buffer. Modifies the data length value while leaving the actual data pointer intact. Requires that there is enough tailroom in the buffer. Some examples of APIs for adding data:

```c
void *net_buf_add(struct net_buf *buf, size_t len);
void *net_buf_add_mem(struct net_buf *buf, const void *mem, size_t len);
uint8_t *net_buf_add_u8(struct net_buf *buf, uint8_t value);
void net_buf_add_le16(struct net_buf *buf, uint16_t value);
void net_buf_add_le32(struct net_buf *buf, uint32_t value);
```

Remove  Remove data from the end of the buffer. Modifies the data length value while leaving the actual data pointer intact. Some examples of APIs for removing data:
Push
Prepend data to the beginning of the buffer. Modifies both the data length value as well as the data pointer. Requires that there is enough headroom in the buffer. Some examples of APIs for pushing data:

```c
void *net_buf_push(struct net_buf *buf, size_t len);
void *net_buf_push_mem(struct net_buf *buf, const void *mem, size_t len);
void net_buf_push_u8(struct net_buf *buf, uint8_t value);
void net_buf_push_le16(struct net_buf *buf, uint16_t value);

Pull
Remove data from the beginning of the buffer. Modifies both the data length value as well as the data pointer. Some examples of APIs for pulling data:

```c
void *net_buf_pull(struct net_buf *buf, size_t len);
void *net_buf_pull_mem(struct net_buf *buf, size_t len);
uint8_t net_buf_pull_u8(struct net_buf *buf);
uint16_t net_buf_pull_le16(struct net_buf *buf);
uint32_t net_buf_pull_le32(struct net_buf *buf);
```

The Add and Push operations are used when encoding data into the buffer, whereas the Remove and Pull operations are used when decoding data from a buffer.

**Reference Counting** Each network buffer is reference counted. The buffer is initially acquired from a free buffers pool by calling `net_buf_alloc()`, resulting in a buffer with reference count 1. The reference count can be incremented with `net_buf_ref()` or decremented with `net_buf_unref()`. When the count drops to zero the buffer is automatically placed back to the free buffers pool.

**API Reference**

*group net_buf*

Network buffer library.

**Defines**

`NET_BUF_SIMPLE_DEFINE(_name, _size)`

Define a `net_buf_simple` stack variable.

This is a helper macro which is used to define a `net_buf_simple` object on the stack.

**Parameters**

- `_name` – Name of the `net_buf_simple` object.
- `_size` – Maximum data storage for the buffer.

`NET_BUF_SIMPLE_DEFINE_STATIC(_name, _size)`

Define a static `net_buf_simple` variable.

This is a helper macro which is used to define a static `net_buf_simple` object.

**Parameters**

- `_name` – Name of the `net_buf_simple` object.
• _size – Maximum data storage for the buffer.

**NET_BUF_SIMPLE(_size)**

Define a *net_buf_simple* stack variable and get a pointer to it.

This is a helper macro which is used to define a *net_buf_simple* object on the stack and the get a pointer to it as follows:

```c
struct net_buf_simple *my_buf = NET_BUF_SIMPLE(10);
```

After creating the object it needs to be initialized by calling *net_buf_simple_init()*.

**Parameters**

• _size – Maximum data storage for the buffer.

**Returns**

Pointer to stack-allocated *net_buf_simple* object.

**NET_BUF_EXTERNAL_DATA**

Flag indicating that the buffer’s associated data pointer, points to externally allocated memory.

Therefore once ref goes down to zero, the pointed data will not need to be deallocated. This never needs to be explicitly set or unset by the *net_buf* API user. Such *net_buf* is exclusively instantiated via *net_buf_alloc_with_data()* function. Reference count mechanism however will behave the same way, and ref count going to 0 will free the *net_buf* but no the data pointer in it.

**NET_BUF_POOL_HEAP_DEFINE(_name, _count, _ud_size, _destroy)**

Define a new pool for buffers using the heap for the data.

Defines a *net_buf_pool* struct and the necessary memory storage (array of structs) for the needed amount of buffers. After this, the buffers can be accessed from the pool through *net_buf_alloc*. The pool is defined as a static variable, so if it needs to be exported outside the current module this needs to happen with the help of a separate pointer rather than an extern declaration.

The data payload of the buffers will be allocated from the heap using k_malloc, so CONFIG_HEAP_MEM_POOL_SIZE must be set to a positive value. This kind of pool does not support blocking on the data allocation, so the timeout passed to *net_buf_alloc* will be always treated as K_NO_WAIT when trying to allocate the data. This means that allocation failures, i.e. NULL returns, must always be handled cleanly.

If provided with a custom destroy callback, this callback is responsible for eventually calling *net_buf_destroy()* to complete the process of returning the buffer to the pool.

**Parameters**

• _name – Name of the pool variable.

• _count – Number of buffers in the pool.

• _ud_size – User data space to reserve per buffer.

• _destroy – Optional destroy callback when buffer is freed.

**NET_BUF_POOL_FIXED_DEFINE(_name, _count, _data_size, _ud_size, _destroy)**

Define a new pool for buffers based on fixed-size data.

Defines a *net_buf_pool* struct and the necessary memory storage (array of structs) for the needed amount of buffers. After this, the buffers can be accessed from the pool through *net_buf_alloc*. The pool is defined as a static variable, so if it needs to be exported outside the current module this needs to happen with the help of a separate pointer rather than an extern declaration.
The data payload of the buffers will be allocated from a byte array of fixed sized chunks. This kind of pool does not support blocking on the data allocation, so the timeout passed to net_buf_alloc will be always treated as K_NO_WAIT when trying to allocate the data. This means that allocation failures, i.e. NULL returns, must always be handled cleanly.

If provided with a custom destroy callback, this callback is responsible for eventually calling `net_buf_destroy()` to complete the process of returning the buffer to the pool.

**Parameters**

- `__name` – Name of the pool variable.
- `__count` – Number of buffers in the pool.
- `__data_size` – Maximum data payload per buffer.
- `__ud_size` – User data space to reserve per buffer.
- `__destroy` – Optional destroy callback when buffer is freed.

```c
NET_BUF_POOL_VAR_DEFINE(__name, __count, __data_size, __ud_size, __destroy)
```

Define a new pool for buffers with variable size payloads.

Defines a `net_buf_pool` struct and the necessary memory storage (array of structs) for the needed amount of buffers. After this, the buffers can be accessed from the pool through `net_buf_alloc`. The pool is defined as a static variable, so if it needs to be exported outside the current module this needs to happen with the help of a separate pointer rather than an extern declaration.

The data payload of the buffers will be based on a memory pool from which variable size payloads may be allocated.

If provided with a custom destroy callback this callback is responsible for eventually calling `net_buf_destroy()` to complete the process of returning the buffer to the pool.

**Parameters**

- `__name` – Name of the pool variable.
- `__count` – Number of buffers in the pool.
- `__data_size` – Total amount of memory available for data payloads.
- `__ud_size` – User data space to reserve per buffer.
- `__destroy` – Optional destroy callback when buffer is freed.

```c
NET_BUF_POOL_DEFINE(__name, __count, __data_size, __ud_size, __destroy)
```

Define a new pool for buffers.

Defines a `net_buf_pool` struct and the necessary memory storage (array of structs) for the needed amount of buffers. After this, the buffers can be accessed from the pool through `net_buf_alloc`. The pool is defined as a static variable, so if it needs to be exported outside the current module this needs to happen with the help of a separate pointer rather than an extern declaration.

If provided with a custom destroy callback this callback is responsible for eventually calling `net_buf_destroy()` to complete the process of returning the buffer to the pool.

**Parameters**

- `__name` – Name of the pool variable.
- `__count` – Number of buffers in the pool.
- `__size` – Maximum data size for each buffer.
- `__ud_size` – Amount of user data space to reserve.
- `__destroy` – Optional destroy callback when buffer is freed.
**Typedefs**

typedef struct net_buf *(net_buf_allocator_cb)(k_timeout_t timeout, void *user_data)
Network buffer allocator callback.

The allocator callback is called when net_buf_append_bytes needs to allocate a new net_buf.

**Param timeout**
Affects the action taken should the net_buf pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout.

**Param user_data**
The user data given in net_buf_append_bytes call.

**Return**
pointer to allocated net_buf or NULL on error.

**Functions**

static inline void net_buf_simple_init(struct net_buf_simple *buf, size_t reserve_head)
Initialize a net_buf_simple object.

This needs to be called after creating a net_buf_simple object using the NET_BUF_SIMPLE macro.

**Parameters**

- buf – Buffer to initialize.
- reserve_head – Headroom to reserve.

void net_buf_simple_init_with_data(struct net_buf_simple *buf, void *data, size_t size)
Initialize a net_buf_simple object with data.

Initialized buffer object with external data.

**Parameters**

- buf – Buffer to initialize.
- data – External data pointer
- size – Amount of data the pointed data buffer if able to fit.

static inline void net_buf_simple_reset(struct net_buf_simple *buf)
Reset buffer.

Reset buffer data so it can be reused for other purposes.

**Parameters**

- buf – Buffer to reset.

void net_buf_simple_clone(const struct net_buf_simple *original, struct net_buf_simple *clone)
Clone buffer state, using the same data buffer.

Initializes a buffer to point to the same data as an existing buffer. Allows operations on the same data without altering the length and offset of the original.

**Parameters**

- original – Buffer to clone.
• clone – The new clone.

```c
void *net_buf_simple_add(struct net_buf_simple *buf, size_t len)
```

Prepare data to be added at the end of the buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**

- `buf` – Buffer to update.
- `len` – Number of bytes to increment the length with.

**Returns**

The original tail of the buffer.

```c
void *net_buf_simple_add_mem(struct net_buf_simple *buf, const void *mem, size_t len)
```

Copy given number of bytes from memory to the end of the buffer. Increments the data length of the buffer to account for more data at the end.

**Parameters**

- `buf` – Buffer to update.
- `mem` – Location of data to be added.
- `len` – Length of data to be added.

**Returns**

The original tail of the buffer.

```c
uint8_t *net_buf_simple_add_u8(struct net_buf_simple *buf, uint8_t val)
```

Add (8-bit) byte at the end of the buffer. Increments the data length of the buffer to account for more data at the end.

**Parameters**

- `buf` – Buffer to update.
- `val` – byte value to be added.

**Returns**

Pointer to the value added

```c
void net_buf_simple_add_le16(struct net_buf_simple *buf, uint16_t val)
```

Add 16-bit value at the end of the buffer. Adds 16-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**

- `buf` – Buffer to update.
- `val` – 16-bit value to be added.

```c
void net_buf_simple_add_be16(struct net_buf_simple *buf, uint16_t val)
```

Add 16-bit value at the end of the buffer. Adds 16-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**

- `buf` – Buffer to update.
- `val` – 16-bit value to be added.
void net_buf_simple_add_le24(struct net_buf_simple *buf, uint32_t val)
Add 24-bit value at the end of the buffer.
Adds 24-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 24-bit value to be added.

void net_buf_simple_add_be24(struct net_buf_simple *buf, uint32_t val)
Add 24-bit value at the end of the buffer.
Adds 24-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 24-bit value to be added.

void net_buf_simple_add_le32(struct net_buf_simple *buf, uint32_t val)
Add 32-bit value at the end of the buffer.
Adds 32-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 32-bit value to be added.

void net_buf_simple_add_be32(struct net_buf_simple *buf, uint32_t val)
Add 32-bit value at the end of the buffer.
Adds 32-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 32-bit value to be added.

void net_buf_simple_add_le48(struct net_buf_simple *buf, uint64_t val)
Add 48-bit value at the end of the buffer.
Adds 48-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 48-bit value to be added.

void net_buf_simple_add_be48(struct net_buf_simple *buf, uint64_t val)
Add 48-bit value at the end of the buffer.
Adds 48-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 48-bit value to be added.
void net_buf_simple_add_le64(struct net_buf_simple *buf, uint64_t val)
Add 64-bit value at the end of the buffer.
Adds 64-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 64-bit value to be added.

void net_buf_simple_add_be64(struct net_buf_simple *buf, uint64_t val)
Add 64-bit value at the end of the buffer.
Adds 64-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 64-bit value to be added.

void *net_buf_simple_remove_mem(struct net_buf_simple *buf, size_t len)
Remove data from the end of the buffer.
Removes data from the end of the buffer by modifying the buffer length.

Parameters
• buf – Buffer to update.
• len – Number of bytes to remove.

Returns
New end of the buffer data.

uint8_t net_buf_simple_remove_u8(struct net_buf_simple *buf)
Remove a 8-bit value from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 8-bit values.

Parameters
• buf – A valid pointer on a buffer.

Returns
The 8-bit removed value

uint16_t net_buf_simple_remove_le16(struct net_buf_simple *buf)
Remove and convert 16 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 16-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
16-bit value converted from little endian to host endian.

uint16_t net_buf_simple_remove_be16(struct net_buf_simple *buf)
Remove and convert 16 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 16-bit big endian data.

Parameters
- buf – A valid pointer on a buffer.

**Returns**
16-bit value converted from big endian to host endian.

```c
uint32_t net_buf_simple_remove_le24(struct net_buf_simple *buf)
```

Remove and convert 24 bits from the end of the buffer.
Same idea as with `net_buf_simple_remove_mem()`, but a helper for operating on 24-bit little endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
24-bit value converted from little endian to host endian.

```c
uint32_t net_buf_simple_remove_be24(struct net_buf_simple *buf)
```

Remove and convert 24 bits from the end of the buffer.
Same idea as with `net_buf_simple_remove_mem()`, but a helper for operating on 24-bit big endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
32-bit value converted from little endian to host endian.

```c
uint32_t net_buf_simple_remove_le32(struct net_buf_simple *buf)
```

Remove and convert 32 bits from the end of the buffer.
Same idea as with `net_buf_simple_remove_mem()`, but a helper for operating on 32-bit little endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
32-bit value converted from big endian to host endian.

```c
uint32_t net_buf_simple_remove_be32(struct net_buf_simple *buf)
```

Remove and convert 32 bits from the end of the buffer.
Same idea as with `net_buf_simple_remove_mem()`, but a helper for operating on 32-bit big endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
48-bit value converted from little endian to host endian.

```c
uint64_t net_buf_simple_remove_le48(struct net_buf_simple *buf)
```

Remove and convert 48 bits from the end of the buffer.
Same idea as with `net_buf_simple_remove_mem()`, but a helper for operating on 48-bit little endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
48-bit value converted from little endian to host endian.
uint64_t net_buf_simple_remove_be48(struct net_buf_simple *buf)
Remove and convert 48 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 48-bit big endian data.

Parameters

• buf – A valid pointer on a buffer.

Returns

48-bit value converted from big endian to host endian.

uint64_t net_buf_simple_remove_le64(struct net_buf_simple *buf)
Remove and convert 64 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 64-bit little endian data.

Parameters

• buf – A valid pointer on a buffer.

Returns

64-bit value converted from little endian to host endian.

uint64_t net_buf_simple_remove_be64(struct net_buf_simple *buf)
Remove and convert 64 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 64-bit big endian data.

Parameters

• buf – A valid pointer on a buffer.

Returns

64-bit value converted from big endian to host endian.

void *net_buf_simple_push(struct net_buf_simple *buf, size_t len)
Prepare data to be added to the start of the buffer.
Modifies the data pointer and buffer length to account for more data in the beginning of the buffer.

Parameters

• buf – Buffer to update.

• len – Number of bytes to add to the beginning.

Returns

The new beginning of the buffer data.

void *net_buf_simple_push_mem(struct net_buf_simple *buf, const void *mem, size_t len)
Copy given number of bytes from memory to the start of the buffer.
Modifies the data pointer and buffer length to account for more data in the beginning of the buffer.

Parameters

• buf – Buffer to update.

• mem – Location of data to be added.

• len – Length of data to be added.

Returns

The new beginning of the buffer data.
void net_buf_simple_push_le16(struct net_buf_simple *buf, uint16_t val)
Push 16-bit value to the beginning of the buffer.
Adds 16-bit value in little endian format to the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 16-bit value to be pushed to the buffer.

void net_buf_simple_push_be16(struct net_buf_simple *buf, uint16_t val)
Push 16-bit value to the beginning of the buffer.
Adds 16-bit value in big endian format to the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 16-bit value to be pushed to the buffer.

void net_buf_simple_push_u8(struct net_buf_simple *buf, uint8_t val)
Push 8-bit value to the beginning of the buffer.
Adds 8-bit value the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 8-bit value to be pushed to the buffer.

void net_buf_simple_push_le24(struct net_buf_simple *buf, uint32_t val)
Push 24-bit value to the beginning of the buffer.
Adds 24-bit value in little endian format to the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 24-bit value to be pushed to the buffer.

void net_buf_simple_push_be24(struct net_buf_simple *buf, uint32_t val)
Push 24-bit value to the beginning of the buffer.
Adds 24-bit value in big endian format to the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 24-bit value to be pushed to the buffer.

void net_buf_simple_push_le32(struct net_buf_simple *buf, uint32_t val)
Push 32-bit value to the beginning of the buffer.
Adds 32-bit value in little endian format to the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 32-bit value to be pushed to the buffer.

void net_buf_simple_push_be32(struct net_buf_simple *buf, uint32_t val)
Push 32-bit value to the beginning of the buffer.
Adds 32-bit value in big endian format to the beginning of the buffer.

Parameters
• **buf** – Buffer to update.
• **val** – 32-bit value to be pushed to the buffer.

```c
void net_buf_simple_push_le48(struct net_buf_simple *buf, uint64_t val)
```

Push 48-bit value in little endian format to the beginning of the buffer.

Parameters

• **buf** – Buffer to update.
• **val** – 48-bit value to be pushed to the buffer.

```c
void net_buf_simple_push_be48(struct net_buf_simple *buf, uint64_t val)
```

Push 48-bit value in big endian format to the beginning of the buffer.

Parameters

• **buf** – Buffer to update.
• **val** – 48-bit value to be pushed to the buffer.

```c
void net_buf_simple_push_le64(struct net_buf_simple *buf, uint64_t val)
```

Push 64-bit value in little endian format to the beginning of the buffer.

Parameters

• **buf** – Buffer to update.
• **val** – 64-bit value to be pushed to the buffer.

```c
void net_buf_simple_push_be64(struct net_buf_simple *buf, uint64_t val)
```

Push 64-bit value in big endian format to the beginning of the buffer.

Parameters

• **buf** – Buffer to update.
• **val** – 64-bit value to be pushed to the buffer.

```c
void *net_buf_simple_pull(struct net_buf_simple *buf, size_t len)
```

Remove data from the beginning of the buffer.

Removes data from the beginning of the buffer by modifying the data pointer and buffer length.

Parameters

• **buf** – Buffer to update.
• **len** – Number of bytes to remove.

Returns

New beginning of the buffer data.

```c
void *net_buf_simple_pull_mem(struct net_buf_simple *buf, size_t len)
```

Remove data from the beginning of the buffer.

Removes data from the beginning of the buffer by modifying the data pointer and buffer length.

Parameters

• **buf** – Buffer to update.
• `len` – Number of bytes to remove.

**Returns**
Pointer to the old location of the buffer data.

`uint8_t net_buf_simple_pull_u8(struct net_buf_simple *buf)`
Remove a 8-bit value from the beginning of the buffer.
Same idea as with `net_buf_simple_pull()`, but a helper for operating on 8-bit values.

**Parameters**
• `buf` – A valid pointer on a buffer.

**Returns**
The 8-bit removed value

`uint16_t net_buf_simple_pull_le16(struct net_buf_simple *buf)`
Remove and convert 16 bits from the beginning of the buffer.
Same idea as with `net_buf_simple_pull()`, but a helper for operating on 16-bit little endian data.

**Parameters**
• `buf` – A valid pointer on a buffer.

**Returns**
16-bit value converted from little endian to host endian.

`uint16_t net_buf_simple_pull_be16(struct net_buf_simple *buf)`
Remove and convert 16 bits from the beginning of the buffer.
Same idea as with `net_buf_simple_pull()`, but a helper for operating on 16-bit big endian data.

**Parameters**
• `buf` – A valid pointer on a buffer.

**Returns**
16-bit value converted from big endian to host endian.

`uint32_t net_buf_simple_pull_le24(struct net_buf_simple *buf)`
Remove and convert 24 bits from the beginning of the buffer.
Same idea as with `net_buf_simple_pull()`, but a helper for operating on 24-bit little endian data.

**Parameters**
• `buf` – A valid pointer on a buffer.

**Returns**
24-bit value converted from little endian to host endian.

`uint32_t net_buf_simple_pull_be24(struct net_buf_simple *buf)`
Remove and convert 24 bits from the beginning of the buffer.
Same idea as with `net_buf_simple_pull()`, but a helper for operating on 24-bit big endian data.

**Parameters**
• `buf` – A valid pointer on a buffer.

**Returns**
24-bit value converted from big endian to host endian.
uint32_t net_buf_simple_pull_le32(struct net_buf_simple *buf)
Remove and convert 32 bits from the beginning of the buffer.
Same idea as with net_buf_simple_pull(), but a helper for operating on 32-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
32-bit value converted from little endian to host endian.

uint32_t net_buf_simple_pull_be32(struct net_buf_simple *buf)
Remove and convert 32 bits from the beginning of the buffer.
Same idea as with net_buf_simple_pull(), but a helper for operating on 32-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
32-bit value converted from big endian to host endian.

uint64_t net_buf_simple_pull_le48(struct net_buf_simple *buf)
Remove and convert 48 bits from the beginning of the buffer.
Same idea as with net_buf_simple_pull(), but a helper for operating on 48-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
48-bit value converted from little endian to host endian.

uint64_t net_buf_simple_pull_be48(struct net_buf_simple *buf)
Remove and convert 48 bits from the beginning of the buffer.
Same idea as with net_buf_simple_pull(), but a helper for operating on 48-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
48-bit value converted from big endian to host endian.

uint64_t net_buf_simple_pull_le64(struct net_buf_simple *buf)
Remove and convert 64 bits from the beginning of the buffer.
Same idea as with net_buf_simple_pull(), but a helper for operating on 64-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
64-bit value converted from little endian to host endian.

uint64_t net_buf_simple_pull_be64(struct net_buf_simple *buf)
Remove and convert 64 bits from the beginning of the buffer.
Same idea as with net_buf_simple_pull(), but a helper for operating on 64-bit big endian data.
Parameters

• buf – A valid pointer on a buffer.

Returns

64-bit value converted from big endian to host endian.

static inline uint8_t *net_buf_simple_tail(struct net_buf_simple *buf)
Get the tail pointer for a buffer.
Get a pointer to the end of the data in a buffer.

Parameters

• buf – Buffer.

Returns

Tail pointer for the buffer.

size_t net_buf_simple_headroom(struct net_buf_simple *buf)
Check buffer headroom.
Check how much free space there is in the beginning of the buffer.
buf A valid pointer on a buffer

Returns

Number of bytes available in the beginning of the buffer.

size_t net_buf_simple_tailroom(struct net_buf_simple *buf)
Check buffer tailroom.
Check how much free space there is at the end of the buffer.

Parameters

• buf – A valid pointer on a buffer

Returns

Number of bytes available at the end of the buffer.

uint16_t net_buf_simple_max_len(struct net_buf_simple *buf)
Check maximum net_buf_simple::len value.
This value is depending on the number of bytes being reserved as headroom.

Parameters

• buf – A valid pointer on a buffer

Returns

Number of bytes usable behind the net_buf_simple::data pointer.

static inline void net_buf_simple_save(struct net_buf_simple *buf, struct net_buf_simple_state *state)
Save the parsing state of a buffer.
Saves the parsing state of a buffer so it can be restored later.

Parameters

• buf – Buffer from which the state should be saved.
• state – Storage for the state.

static inline void net_buf_simple_restore(struct net_buf_simple *buf, struct net_buf_simple_state *state)
Restore the parsing state of a buffer.
Restores the parsing state of a buffer from a state previously stored by net_buf_simple_save().
Parameters

- **buf** – Buffer to which the state should be restored.
- **state** – Stored state.

```c
struct net_buf_pool *net_buf_pool_get(int id)
```

Looks up a pool based on its ID.

Parameters

- **id** – Pool ID (e.g. from buf->pool_id).

Returns

Pointer to pool.

```c
int net_buf_id(struct net_buf *buf)
```

Get a zero-based index for a buffer.

This function will translate a buffer into a zero-based index, based on its placement in its buffer pool. This can be useful if you want to associate an external array of metadata contexts with the buffers of a pool.

Parameters

- **buf** – Network buffer.

Returns

Zero-based index for the buffer.

```c
struct net_buf *net_buf_alloc_fixed(struct net_buf_pool *pool, k_timeout_t timeout)
```

Allocate a new fixed buffer from a pool.

Parameters

- **pool** – Which pool to allocate the buffer from.
- **timeout** – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout. Note that some types of data allocators do not support blocking (such as the HEAP type). In this case it's still possible for `net_buf_alloc()` to fail (return NULL) even if it was given K_FOREVER.

Returns

New buffer or NULL if out of buffers.

```c
static inline struct net_buf *net_buf_alloc(struct net_buf_pool *pool, k_timeout_t timeout)
```

Parameters

- **pool** – Which pool to allocate the buffer from.
- **timeout** – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout. Note that some types of data allocators do not support blocking (such as the HEAP type). In this case it's still possible for `net_buf_alloc()` to fail (return NULL) even if it was given K_FOREVER.

Returns

New buffer or NULL if out of buffers.

```c
struct net_buf *net_buf_alloc_len(struct net_buf_pool *pool, size_t size, k_timeout_t timeout)
```

Allocate a new variable length buffer from a pool.
Parameters

- **pool** – Which pool to allocate the buffer from.
- **size** – Amount of data the buffer must be able to fit.
- **timeout** – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout. Note that some types of data allocators do not support blocking (such as the HEAP type). In this case it's still possible for `net_buf_alloc()` to fail (return NULL) even if it was given K_FOREVER.

Returns

New buffer or NULL if out of buffers.

```c
struct net_buf *net_buf_alloc_with_data(struct net_buf_pool *pool, void *data, size_t size, k_timeout_t timeout)
```

Allocate a new buffer from a pool but with external data pointer.

Allocate a new buffer from a pool, where the data pointer comes from the user and not from the pool.

Parameters

- **pool** – Which pool to allocate the buffer from.
- **data** – External data pointer
- **size** – Amount of data the pointed data buffer if able to fit.
- **timeout** – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout. Note that some types of data allocators do not support blocking (such as the HEAP type). In this case it's still possible for `net_buf_alloc()` to fail (return NULL) even if it was given K_FOREVER.

Returns

New buffer or NULL if out of buffers.

```c
struct net_buf *net_buf_get(struct k_fifo *fifo, k_timeout_t timeout)
```

Get a buffer from a FIFO.

This function is NOT thread-safe if the buffers in the FIFO contain fragments.

Parameters

- **fifo** – Which FIFO to take the buffer from.
- **timeout** – Affects the action taken should the FIFO be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout.

Returns

New buffer or NULL if the FIFO is empty.

```c
static inline void net_buf_destroy(struct net_buf *buf)
```

Destroy buffer from custom destroy callback.

This helper is only intended to be used from custom destroy callbacks. If no custom destroy callback is given to NET_BUF_POOL_*.DEFINE() then there is no need to use this API.

Parameters

- **buf** – Buffer to destroy.
void net_buf_reset(struct net_buf *buf)

Reset buffer.
Reset buffer data and flags so it can be reused for other purposes.

Parameters
• buf – Buffer to reset.

void net_buf_simple_reserve(struct net_buf_simple *buf, size_t reserve)

Initialize buffer with the given headroom.
The buffer is not expected to contain any data when this API is called.

Parameters
• buf – Buffer to initialize.
• reserve – How much headroom to reserve.

void net_buf_slist_put(sys_slist_t *list, struct net_buf *buf)

Put a buffer into a list.
If the buffer contains follow-up fragments this function will take care of inserting them as well into the list.

Parameters
• list – Which list to append the buffer to.
• buf – Buffer.

struct net_buf *net_buf_slist_get(sys_slist_t *list)

Get a buffer from a list.
If the buffer had any fragments, these will automatically be recovered from the list as well and be placed to the buffer’s fragment list.

Parameters
• list – Which list to take the buffer from.

Returns
New buffer or NULL if the FIFO is empty.

void net_buf_put(struct k_fifo *fifo, struct net_buf *buf)

Put a buffer to the end of a FIFO.
If the buffer contains follow-up fragments this function will take care of inserting them as well into the FIFO.

Parameters
• fifo – Which FIFO to put the buffer to.
• buf – Buffer.

void net_buf_unref(struct net_buf *buf)

Decrements the reference count of a buffer.
The buffer is put back into the pool if the reference count reaches zero.

Parameters
• buf – A valid pointer on a buffer

struct net_buf *net_buf_ref(struct net_buf *buf)

Increment the reference count of a buffer.

Parameters
Struct net_buf *net_buf_clone(struct net_buf *buf, k_timeout_t timeout)
Clone buffer.
Duplicate given buffer including any data and headers currently stored.

Parameters
- buf – A valid pointer on a buffer
- timeout – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout.

Returns
Cloned buffer or NULL if out of buffers.

static inline void *net_buf_user_data(const struct net_buf *buf)
Get a pointer to the user data of a buffer.

Parameters
- buf – A valid pointer on a buffer

Returns
Pointer to the user data of the buffer.

static inline void net_buf_reserve(struct net_buf *buf, size_t reserve)
Initialize buffer with the given headroom.
The buffer is not expected to contain any data when this API is called.

Parameters
- buf – Buffer to initialize.
- reserve – How much headroom to reserve.

static inline void *net_buf_add(struct net_buf *buf, size_t len)
Prepare data to be added at the end of the buffer.
Increments the data length of a buffer to account for more data at the end.

Parameters
- buf – Buffer to update.
- len – Number of bytes to increment the length with.

Returns
The original tail of the buffer.

static inline void *net_buf_add_mem(struct net_buf *buf, const void *mem, size_t len)
Copies the given number of bytes to the end of the buffer.
Increments the data length of the buffer to account for more data at the end.

Parameters
- buf – Buffer to update.
- mem – Location of data to be added.
- len – Length of data to be added

Returns
The original tail of the buffer.
static inline uint8_t *net_buf_add_u8(struct net_buf *buf, uint8_t val)
Add (8-bit) byte at the end of the buffer.
Increments the data length of the buffer to account for more data at the end.

Parameters
- buf – Buffer to update.
- val – byte value to be added.

Returns
Pointer to the value added

static inline void net_buf_add_le16(struct net_buf *buf, uint16_t val)
Add 16-bit value at the end of the buffer.
Adds 16-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
- buf – Buffer to update.
- val – 16-bit value to be added.

static inline void net_buf_add_be16(struct net_buf *buf, uint16_t val)
Add 16-bit value at the end of the buffer.
Adds 16-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
- buf – Buffer to update.
- val – 16-bit value to be added.

static inline void net_buf_add_le24(struct net_buf *buf, uint32_t val)
Add 24-bit value at the end of the buffer.
Adds 24-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
- buf – Buffer to update.
- val – 24-bit value to be added.

static inline void net_buf_add_be24(struct net_buf *buf, uint32_t val)
Add 24-bit value at the end of the buffer.
Adds 24-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
- buf – Buffer to update.
- val – 24-bit value to be added.

static inline void net_buf_add_le32(struct net_buf *buf, uint32_t val)
Add 32-bit value at the end of the buffer.
Adds 32-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters
- buf – Buffer to update.
• val – 32-bit value to be added.

static inline void net_buf_add_be32(struct net_buf *buf, uint32_t val)
Add 32-bit value at the end of the buffer.

Adds 32-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**

• buf – Buffer to update.
• val – 32-bit value to be added.

static inline void net_buf_add_le48(struct net_buf *buf, uint64_t val)
Add 48-bit value at the end of the buffer.

Adds 48-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**

• buf – Buffer to update.
• val – 48-bit value to be added.

static inline void net_buf_add_be48(struct net_buf *buf, uint64_t val)
Add 48-bit value at the end of the buffer.

Adds 48-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**

• buf – Buffer to update.
• val – 48-bit value to be added.

static inline void net_buf_add_le64(struct net_buf *buf, uint64_t val)
Add 64-bit value at the end of the buffer.

Adds 64-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**

• buf – Buffer to update.
• val – 64-bit value to be added.

static inline void net_buf_add_be64(struct net_buf *buf, uint64_t val)
Add 64-bit value at the end of the buffer.

Adds 64-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**

• buf – Buffer to update.
• val – 64-bit value to be added.

static inline void *net_buf_remove_mem(struct net_buf *buf, size_t len)
Remove data from the end of the buffer.

Removes data from the end of the buffer by modifying the buffer length.

**Parameters**

• buf – Buffer to update.
• len – Number of bytes to remove.
Returns
New end of the buffer data.

static inline uint8_t net_buf_remove_u8(struct net_buf *buf)
Remove a 8-bit value from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 8-bit values.

Parameters
• buf – A valid pointer on a buffer.

Returns
The 8-bit removed value

static inline uint16_t net_buf_remove_le16(struct net_buf *buf)
Remove and convert 16 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 16-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
16-bit value converted from little endian to host endian.

static inline uint16_t net_buf_remove_be16(struct net_buf *buf)
Remove and convert 16 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 16-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
16-bit value converted from big endian to host endian.

static inline uint32_t net_buf_remove_be24(struct net_buf *buf)
Remove and convert 24 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 24-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
24-bit value converted from big endian to host endian.

static inline uint32_t net_buf_remove_le24(struct net_buf *buf)
Remove and convert 24 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 24-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
24-bit value converted from little endian to host endian.
static inline uint32_t net_buf_remove_le32(struct net_buf *buf)
Remove and convert 32 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 32-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
32-bit value converted from little endian to host endian.

static inline uint32_t net_buf_remove_be32(struct net_buf *buf)
Remove and convert 32 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 32-bit big endian data.

Parameters
• buf – A valid pointer on a buffer

Returns
32-bit value converted from big endian to host endian.

static inline uint64_t net_buf_remove_le48(struct net_buf *buf)
Remove and convert 48 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 48-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
48-bit value converted from little endian to host endian.

static inline uint64_t net_buf_remove_be48(struct net_buf *buf)
Remove and convert 48 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 48-bit big endian data.

Parameters
• buf – A valid pointer on a buffer

Returns
48-bit value converted from big endian to host endian.

static inline uint64_t net_buf_remove_le64(struct net_buf *buf)
Remove and convert 64 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 64-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
64-bit value converted from little endian to host endian.

static inline uint64_t net_buf_remove_be64(struct net_buf *buf)
Remove and convert 64 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 64-bit big endian data.
Parameters
  • buf – A valid pointer on a buffer

Returns
  64-bit value converted from big endian to host endian.

static inline void *net_buf_push(struct net_buf *buf, size_t len)
Prepare data to be added at the start of the buffer.
Modifies the data pointer and buffer length to account for more data in the beginning of the buffer.

Parameters
  • buf – Buffer to update.
  • len – Number of bytes to add to the beginning.

Returns
  The new beginning of the buffer data.

static inline void *net_buf_push_mem(struct net_buf *buf, const void *mem, size_t len)
Copies the given number of bytes to the start of the buffer.
Modifies the data pointer and buffer length to account for more data in the beginning of the buffer.

Parameters
  • buf – Buffer to update.
  • mem – Location of data to be added.
  • len – Length of data to be added.

Returns
  The new beginning of the buffer data.

static inline void net_buf_push_u8(struct net_buf *buf, uint8_t val)
Push 8-bit value to the beginning of the buffer.
Adds 8-bit value the beginning of the buffer.

Parameters
  • buf – Buffer to update.
  • val – 8-bit value to be pushed to the buffer.

static inline void net_buf_push_le16(struct net_buf *buf, uint16_t val)
Push 16-bit value to the beginning of the buffer.
Adds 16-bit value in little endian format to the beginning of the buffer.

Parameters
  • buf – Buffer to update.
  • val – 16-bit value to be pushed to the buffer.

static inline void net_buf_push_be16(struct net_buf *buf, uint16_t val)
Push 16-bit value to the beginning of the buffer.
Adds 16-bit value in big endian format to the beginning of the buffer.

Parameters
  • buf – Buffer to update.
  • val – 16-bit value to be pushed to the buffer.
static inline void net_buf_push_le24(struct net_buf *buf, uint32_t val)
Push 24-bit value to the beginning of the buffer.
	Add 24-bit value in little endian format to the beginning of the buffer.

Parameters
- buf – Buffer to update.
- val – 24-bit value to be pushed to the buffer.

static inline void net_buf_push_be24(struct net_buf *buf, uint32_t val)
Push 24-bit value to the beginning of the buffer.
	Add 24-bit value in big endian format to the beginning of the buffer.

Parameters
- buf – Buffer to update.
- val – 24-bit value to be pushed to the buffer.

static inline void net_buf_push_le32(struct net_buf *buf, uint32_t val)
Push 32-bit value to the beginning of the buffer.
	Add 32-bit value in little endian format to the beginning of the buffer.

Parameters
- buf – Buffer to update.
- val – 32-bit value to be pushed to the buffer.

static inline void net_buf_push_be32(struct net_buf *buf, uint32_t val)
Push 32-bit value to the beginning of the buffer.
	Add 32-bit value in big endian format to the beginning of the buffer.

Parameters
- buf – Buffer to update.
- val – 32-bit value to be pushed to the buffer.

static inline void net_buf_push_le48(struct net_buf *buf, uint64_t val)
Push 48-bit value to the beginning of the buffer.
	Add 48-bit value in little endian format to the beginning of the buffer.

Parameters
- buf – Buffer to update.
- val – 48-bit value to be pushed to the buffer.

static inline void net_buf_push_be48(struct net_buf *buf, uint64_t val)
Push 48-bit value to the beginning of the buffer.
	Add 48-bit value in big endian format to the beginning of the buffer.

Parameters
- buf – Buffer to update.
- val – 48-bit value to be pushed to the buffer.

static inline void net_buf_push_le64(struct net_buf *buf, uint64_t val)
Push 64-bit value to the beginning of the buffer.
	Add 64-bit value in little endian format to the beginning of the buffer.

Parameters
• **buf** – Buffer to update.
• **val** – 64-bit value to be pushed to the buffer.

static inline void *net_buf_pull_mem(struct net_buf *buf, size_t len)
Remove data from the beginning of the buffer.
Removes data from the beginning of the buffer by modifying the data pointer and
buffer length.

Parameters
• **buf** – Buffer to update.
• **len** – Number of bytes to remove.

Returns
New beginning of the buffer data.

static inline uint8_t net_buf_pull_u8(struct net_buf *buf)
Remove a 8-bit value from the beginning of the buffer.
Same idea as with `net_buf_pull()`, but a helper for operating on 8-bit values.

Parameters
• **buf** – A valid pointer on a buffer.

Returns
The 8-bit removed value

static inline uint16_t net_buf_pull_le16(struct net_buf *buf)
Remove and convert 16 bits from the beginning of the buffer.
Same idea as with `net_buf_pull()`, but a helper for operating on 16-bit little endian data.

Parameters
• **buf** – A valid pointer on a buffer.

Returns
16-bit value converted from little endian to host endian.
static inline uint16_t net_buf_pull_be16(struct net_buf *buf)
    Remove and convert 16 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 16-bit big endian data.

    Parameters
    • buf – A valid pointer on a buffer.

    Returns
    16-bit value converted from big endian to host endian.

static inline uint32_t net_buf_pull_le24(struct net_buf *buf)
    Remove and convert 24 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 24-bit little endian data.

    Parameters
    • buf – A valid pointer on a buffer.

    Returns
    24-bit value converted from little endian to host endian.

static inline uint32_t net_buf_pull_be24(struct net_buf *buf)
    Remove and convert 24 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 24-bit big endian data.

    Parameters
    • buf – A valid pointer on a buffer.

    Returns
    24-bit value converted from big endian to host endian.

static inline uint32_t net_buf_pull_le32(struct net_buf *buf)
    Remove and convert 32 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 32-bit little endian data.

    Parameters
    • buf – A valid pointer on a buffer.

    Returns
    32-bit value converted from little endian to host endian.

static inline uint32_t net_buf_pull_be32(struct net_buf *buf)
    Remove and convert 32 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 32-bit big endian data.

    Parameters
    • buf – A valid pointer on a buffer.

    Returns
    32-bit value converted from big endian to host endian.

static inline uint64_t net_buf_pull_le48(struct net_buf *buf)
    Remove and convert 48 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 48-bit little endian data.

    Parameters
    • buf – A valid pointer on a buffer.

    Returns
    48-bit value converted from little endian to host endian.
static inline uint64_t net_buf_pull_be48(struct net_buf *buf)
    Remove and convert 48 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 48-bit big endian data.
    Parameters
    • buf – A valid pointer on a buffer
    Returns
    48-bit value converted from big endian to host endian.

static inline uint64_t net_buf_pull_le64(struct net_buf *buf)
    Remove and convert 64 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 64-bit little endian data.
    Parameters
    • buf – A valid pointer on a buffer.
    Returns
    64-bit value converted from little endian to host endian.

static inline uint64_t net_buf_pull_be64(struct net_buf *buf)
    Remove and convert 64 bits from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 64-bit big endian data.
    Parameters
    • buf – A valid pointer on a buffer
    Returns
    64-bit value converted from big endian to host endian.

static inline size_t net_buf_tailroom(struct net_buf *buf)
    Check buffer tailroom.
    Check how much free space there is at the end of the buffer.
    Parameters
    • buf – A valid pointer on a buffer
    Returns
    Number of bytes available at the end of the buffer.

static inline size_t net_buf_headroom(struct net_buf *buf)
    Check buffer headroom.
    Check how much free space there is in the beginning of the buffer.
    buf A valid pointer on a buffer
    Returns
    Number of bytes available in the beginning of the buffer.

static inline uint16_t net_buf_max_len(struct net_buf *buf)
    Check maximum net_buf::len value.
    This value is depending on the number of bytes being reserved as headroom.
    Parameters
    • buf – A valid pointer on a buffer
    Returns
    Number of bytes usable behind the net_buf::data pointer.
static inline uint8_t *net_buf_tail(struct net_buf *buf)
  Get the tail pointer for a buffer.
  Get a pointer to the end of the data in a buffer.

  Parameters
  • buf – Buffer.

  Returns
  Tail pointer for the buffer.

struct net_buf *net_buf_frag_last(struct net_buf *frags)
  Find the last fragment in the fragment list.

  Returns
  Pointer to last fragment in the list.

void net_buf_frag_insert(struct net_buf *parent, struct net_buf *frag)
  Insert a new fragment to a chain of bufs.
  Insert a new fragment into the buffer fragments list after the parent.
  Note: This function takes ownership of the fragment reference so the caller is not re-
  quired to unref.

  Parameters
  • parent – Parent buffer/fragment.
  • frag – Fragment to insert.

struct net_buf *net_buf_frag_add(struct net_buf *head, struct net_buf *frag)
  Add a new fragment to the end of a chain of bufs.
  Append a new fragment into the buffer fragments list.
  Note: This function takes ownership of the fragment reference so the caller is not re-
  quired to unref.

  Parameters
  • head – Head of the fragment chain.
  • frag – Fragment to add.

  Returns
  New head of the fragment chain. Either head (if head was non-NULL) or
  frag (if head was NULL).

struct net_buf *net_buf_frag_del(struct net_buf *parent, struct net_buf *frag)
  Delete existing fragment from a chain of bufs.

  Parameters
  • parent – Parent buffer/fragment, or NULL if there is no parent.
  • frag – Fragment to delete.

  Returns
  Pointer to the buffer following the fragment, or NULL if it had no further
  fragments.

size_t net_buf_linearize(void *dst, size_t dst_len, struct net_buf *src, size_t offset, size_t len)
  Copy bytes from net_buf chain starting at offset to linear buffer.
  Copy (extract) len bytes from src net_buf chain, starting from offset in it, to a linear
  buffer dst. Return number of bytes actually copied, which may be less than requested,
  if net_buf chain doesn't have enough data, or destination buffer is too small.
Parameters
- \texttt{dst} – Destination buffer
- \texttt{dst\_len} – Destination buffer length
- \texttt{src} – Source \texttt{net\_buf} chain
- \texttt{offset} – Starting offset to copy from
- \texttt{len} – Number of bytes to copy

Returns
number of bytes actually copied

\begin{verbatim}
size_t net_buf_append_bytes(struct net_buf *buf, size_t len, const void *value, 
k_timeout_t timeout, net_buf_allocator_cb allocate_cb, void *user_data)
\end{verbatim}

Append data to a list of \texttt{net\_buf}.
If there is not enough space in the \texttt{net\_buf} then more \texttt{net\_buf} will be added, unless there are no free \texttt{net\_buf} and timeout occurs. If not allocator is provided it attempts to allocate from the same pool as the original buffer.

Parameters
- \texttt{buf} – Network buffer.
- \texttt{len} – Total length of input data
- \texttt{value} – Data to be added
- \texttt{timeout} – Timeout is passed to the \texttt{net\_buf} allocator callback.
- \texttt{allocate\_cb} – When a new \texttt{net\_buf} is required, use this callback.
- \texttt{user\_data} – A user data pointer to be supplied to the allocate\_cb. This pointer is can be anything from a mem\_pool or a \texttt{net\_pkt}, the logic is left up to the allocate\_cb function.

Returns
Length of data actually added. This may be less than input length if other timeout than K\_FOREVER was used, and there were no free fragments in a pool to accommodate all data.

\begin{verbatim}
size_t net_buf_data_match(const struct net_buf *buf, size_t offset, const void *data, size_t len)
\end{verbatim}

Match data with a \texttt{net\_buf}'s content.

Compare data with a content of a \texttt{net\_buf}. Provide information about the number of bytes matching between both. If needed, traverse through multiple buffer fragments.

Parameters
- \texttt{buf} – Network buffer
- \texttt{offset} – Starting offset to compare from
- \texttt{data} – Data buffer for comparison
- \texttt{len} – Number of bytes to compare

Returns
The number of bytes compared before the first difference.

\begin{verbatim}
static inline struct net_buf *net_buf_skip(struct net_buf *buf, size_t len)
\end{verbatim}

Skip N number of bytes in a \texttt{net\_buf}.

Skip N number of bytes starting from fragment's offset. If the total length of data is placed in multiple fragments, this function will skip from all fragments until it reaches N number of bytes. Any fully skipped buffers are removed from the \texttt{net\_buf} list.
Parameters

- buf – Network buffer.
- len – Total length of data to be skipped.

Returns

Pointer to the fragment or NULL and pos is 0 after successful skip, NULL and pos is 0xffff otherwise.

static inline size_t net_buf_frags_len(struct net_buf *buf)
Calculate amount of bytes stored in fragments.

Calculates the total amount of data stored in the given buffer and the fragments linked to it.

Parameters

- buf – Buffer to start off with.

Returns

Number of bytes in the buffer and its fragments.

struct net_buf_simple
#include <buf.h> Simple network buffer representation.

This is a simpler variant of the net_buf object (in fact net_buf uses net_buf_simple internally). It doesn't provide any kind of reference counting, user data, dynamic allocation, or in general the ability to pass through kernel objects such as FIFOs.

The main use of this is for scenarios where the meta-data of the normal net_buf isn't needed and causes too much overhead. This could be e.g. when the buffer only needs to be allocated on the stack or when the access to and lifetime of the buffer is well controlled and constrained.

Public Members

uint8_t *data
Pointer to the start of data in the buffer.

uint16_t len
Length of the data behind the data pointer.
To determine the max length, use net_buf_simple_max_len(), not size!

uint16_t size
Amount of data that net_buf_simple::__buf can store.

struct net_buf_simple_state
#include <buf.h> Parsing state of a buffer.

This is used for temporarily storing the parsing state of a buffer while giving control of the parsing to a routine which we don’t control.

Public Members
uint16_t offset
    Offset of the data pointer from the beginning of the storage.

uint16_t len
    Length of data.

struct net_buf
    #include <buf.h> Network buffer representation.
    This struct is used to represent network buffers. Such buffers are normally defined
    through the NET_BUF_POOL_\*_DEFINE() APIs and allocated using the net_buf_alloc() API.

Public Members

    sys_snode_t node
        Allow placing the buffer into sys_slist_t.

    struct net_buf *frags
        Fragments associated with this buffer.

    uint8_t ref
        Reference count.

    uint8_t flags
        Bit-field of buffer flags.

    uint8_t pool_id
        Where the buffer should go when freed up.

    uint8_t *data
        Pointer to the start of data in the buffer.

    uint16_t len
        Length of the data behind the data pointer.

    uint16_t size
        Amount of data that this buffer can store.

    uint8_t user_data[]
        System metadata for this buffer.

struct net_buf_data_cb
    #include <buf.h>

struct net_buf_data_alloc
    #include <buf.h>
struct net_buf_pool

#include <buf.h> Network buffer pool representation.
This struct is used to represent a pool of network buffers.

Public Members

struct k_lifo free
   LIFO to place the buffer into when free.

const uint16_t buf_count
   Number of buffers in pool.

uint16_t uninit_count
   Number of uninitialized buffers.

void (*const destroy)(struct net_buf *buf)
   Optional destroy callback when buffer is freed.

const struct net_buf_data_alloc *alloc
   Data allocation handlers.

Packet Management

• Overview
  – Architectural notes

• Memory management
  – Allocation
  – Buffer allocation
  – Deallocation

• Operations
  – Read and Write access
  – Data access

• API Reference

Overview Network packets are the main data the networking stack manipulates. Such data is represented through the net_pkt structure which provides a means to hold the packet, write and read it, as well as necessary metadata for the core to hold important information. Such an object is called net_pkt in this document.

The data structure and the whole API around it are defined in include/zephyr/net/net_pkt.h.
**Architectural notes**  There are two network packets flows within the stack, TX for the transmission path, and RX for the reception one. In both paths, each net_pkt is written and read from the beginning to the end, or more specifically from the headers to the payload.

### Memory management

**Allocation**  All net_pkt objects come from a pre-defined pool of struct net_pkt. Such pool is defined via

```c
NET_PKT_SLAB_DEFINE(name, count)
```

Note, however, one will rarely have to use it, as the core provides already two pools, one for the TX path and one for the RX path.

Allocating a raw net_pkt can be done through:

```c
pkt = net_pkt_alloc(timeout);
```

However, by its nature, a raw net_pkt is useless without a buffer and needs various metadata information to become relevant as well. It requires at least to get the network interface it is meant to be sent through or through which it was received. As this is a very common operation, a helper exist:

```c
pkt = net_pkt_alloc_on_iface(iface, timeout);
```

A more complete allocator exists, where both the net_pkt and its buffer can be allocated at once:

```c
pkt = net_pkt_alloc_with_buffer(iface, size, family, proto, timeout);
```

See below how the buffer is allocated.

**Buffer allocation**  The net_pkt object does not define its own buffer, but instead uses an existing object for this: net_buf. (See Network Buffer for more information). However, it mostly hides the usage of such a buffer because net_pkt brings network awareness to buffer allocation and, as we will see later, its operation too.

To allocate a buffer, a net_pkt needs to have at least its network interface set. This works if the family of the packet is unknown at the time of buffer allocation. Then one could do:

```c
net_pkt_alloc_buffer(pkt, size, proto, timeout);
```

Where proto could be 0 if unknown (there is no IPPROTO_UNSPEC).

As seen previously, the net_pkt and its buffer can be allocated at once via `net_pkt_alloc_with_buffer()`. It is actually the most widely used allocator.

The network interface, the family, and the protocol of the packet are used by the buffer allocation to determine if the requested size can be allocated. Indeed, the allocator will use the network interface to know the MTU and then the family and protocol for the headers space (if only these 2 are specified). If the whole fits within the MTU, the allocated space will be of the requested size plus, eventually, the headers space. If there is insufficient MTU space, the requested size will be shrunk so the possible headers space and new size will fit within the MTU.

For instance, on an Ethernet network interface, with an MTU of 1500 bytes:

```c
pkt = net_pkt_alloc_with_buffer(iface, 800, AF_INET4, IPPROTO_UDP, K_FOREVER);
```

will successfully allocate 800 + 20 + 8 bytes of buffer for the new net_pkt where:
pkt = net_pkt_alloc_with_buffer(iface, 1600, AF_INET4, IPPROTO_UDP, K_FOREVER);

will successfully allocate 1500 bytes, and where 20 + 8 bytes (IPv4 + UDP headers) will not be used for the payload.

On the receiving side, when the family and protocol are not known:

 pkt = net_pkt_rx_alloc_with_buffer(iface, 800, AF_UNSPEC, 0, K_FOREVER);

will allocate 800 bytes and no extra header space. But a:

 pkt = net_pkt_rx_alloc_with_buffer(iface, 1600, AF_UNSPEC, 0, K_FOREVER);

will allocate 1514 bytes, the MTU + Ethernet header space.

One can increase the amount of buffer space allocated by calling net_pkt_alloc_buffer(), as it will take into account the existing buffer. It will also account for the header space if net_pkt's family is a valid one, as well as the proto parameter. In that case, the newly allocated buffer space will be appended to the existing one, and not inserted in the front. Note however such a use case is rather limited. Usually, one should know from the start how much size should be requested.

**Deallocation**  Each net_pkt is reference counted. At allocation, the reference is set to 1. The reference count can be incremented with net_pkt_ref() or decremented with net_pkt_unref(). When the count drops to zero the buffer is also un-referenced and net_pkt is automatically placed back into the free net_pkt_slabs.

If net_pkt's buffer is needed even after net_pkt deallocation, one will need to reference once more all the chain of net_buf before calling last net_pkt_unref. See Network Buffer for more information.

**Operations**  There are two ways to access the net_pkt buffer, explained in the following sections: basic read/write access and data access, the latter being the preferred way.

**Read and Write access**  As said earlier, though net_pkt uses net_buf for its buffer, it provides its own API to access it. Indeed, a network packet might be scattered over a chain of net_buf objects, the functions provided by net_buf are then limited for such case. Instead, net_pkt provides functions which hide all the complexity of potential non-contiguous access.

Data movement into the buffer is made through a cursor maintained within each net_pkt. All read/write operations affect this cursor. Note as well that read or write functions are strict on their length parameters: if it cannot r/w the given length it will fail. Length is not interpreted as an upper limit, it is instead the exact amount of data that must be read or written.

As there are two paths, TX and RX, there are two access modes: write and overwrite. This might sound a bit unusual, but is in fact simple and provides flexibility.

In write mode, whatever is written in the buffer affects the length of actual data present in the buffer. Buffer length should not be confused with the buffer size which is a limit any mode cannot pass. In overwrite mode then, whatever is written must happen on valid data, and will not affect the buffer length. By default, a newly allocated net_pkt is on write mode, and its cursor points to the beginning of its buffer.

Let's see now, step by step, the functions and how they behave depending on the mode.

When freshly allocated with a buffer of 500 bytes, a net_pkt has 0 length, which means no valid data is in its buffer. One could verify this by:

 len = net_pkt_get_len(pkt);
Now, let's write 8 bytes:

```c
net_pkt_write(pkt, data, 8);
```

The buffer length is now 8 bytes. There are various helpers to write a byte, or big endian uint16_t, uint32_t.

```c
net_pkt_write_u8(pkt, &foo);
net_pkt_write_be16(pkt, &ba);
net_pkt_write_be32(pkt, &bar);
```

Logically, net_pkt's length is now 15. But if we try to read at this point, it will fail because there is nothing to read at the cursor where we are at in the net_pkt. It is possible, while in write mode, to read what has been already written by resetting the cursor of the net_pkt. For instance:

```c
net_pkt_cursor_init(pkt);
net_pkt_read(pkt, data, 15);
```

This will reset the cursor of the pkt to the beginning of the buffer and then let you read the actual 15 bytes present. The cursor is then again pointing at the end of the buffer.

To set a large area with the same byte, a memset function is provided:

```c
net_pkt_memset(pkt, 0, 5);
```

Our net_pkt has now a length of 20 bytes.

Switching between modes can be achieved via `net_pkt_set_overwrite()` function. It is possible to switch mode back and forth at any time. The net_pkt will be set to overwrite and its cursor reset:

```c
net_pkt_set_overwrite(pkt, true);
net_pkt_cursor_init(pkt);
```

Now the same operators can be used, but it will be limited to the existing data in the buffer, i.e. 20 bytes.

If it is necessary to know how much space is available in the net_pkt call:

```c
net_pkt_available_buffer(pkt);
```

Or, if headers space needs to be accounted for, call:

```c
net_pkt_available_payload_buffer(pkt, proto);
```

If you want to place the cursor at a known position use the function `net_pkt_skip()`. For example, to go after the IP header, use:

```c
net_pkt_cursor_init(pkt);
net_pkt_skip(pkt, net_pkt_ip_header_len(pkt));
```

**Data access** Though the API shown previously is rather simple, it involves always copying things to and from the net_pkt buffer. In many occasions, it is more relevant to access the information stored in the buffer contiguously, especially with network packets which embed headers. These headers are, most of the time, a known fixed set of bytes. It is then more natural to have a structure representing a certain type of header. In addition to this, if it is known the header size appears in a contiguous area of the buffer, it will be way more efficient to cast the actual position in the buffer to the type of header. Either for reading or writing the fields of such header, accessing it directly will save memory.

Net pkt comes with a dedicated API for this, built on top of the previously described API. It is able to handle both contiguous and non-contiguous access transparently.
There are two macros used to define a data access descriptor: `NET_PKT_DATA_ACCESS_DEFINE` when it is not possible to tell if the data will be in a contiguous area, and `NET_PKT_DATA_ACCESS_CONTIGUOUS_DEFINE` when it is guaranteed the data is in a contiguous area.

Let's take the example of IP and UDP. Both IPv4 and IPv6 headers are always found at the beginning of the packet and are small enough to fit in a net_buf of 128 bytes (for instance, though 64 bytes could be chosen).

```c
NET_PKT_DATA_ACCESS_CONTIGUOUS_DEFINE(ipv4_access, struct net_ipv4_hdr);
struct net_ipv4_hdr *ipv4_hdr;
ipv4_hdr = (struct net_ipv4_hdr *)net_pkt_get_data(pkt, &ipv4_access);
```

It would be the same for struct `net_ipv4_hdr`. For a UDP header it is likely not to be in a contiguous area in IPv6 for instance so:

```c
NET_PKT_DATA_ACCESS_DEFINE(udp_access, struct net_udp_hdr);
struct net_udp_hdr *udp_hdr;
udp_hdr = (struct net_udp_hdr *)net_pkt_get_data(pkt, &udp_access);
```

At this point, the cursor of the net_pkt points at the beginning of the requested data. On the RX path, these headers will be read but not modified so to proceed further the cursor needs to advance past the data. There is a function dedicated for this:

```c
net_pkt_acknowledge_data(pkt, &ipv4_access);
```

On the TX path, however, the header fields have been modified. In such a case:

```c
net_pkt_set_data(pkt, &ipv4_access);
```

If the data are in a contiguous area, it will advance the cursor relevantly. If not, it will write the data and the cursor will be updated. Note that `net_pkt_set_data()` could be used in the RX path as well, but it is slightly faster to use `net_pkt_acknowledge_data()` as this one does not care about contiguity at all, it just advances the cursor via `net_pkt_skip()` directly.

**API Reference**

**Related code samples**

**Dumb HTTP server**

Implement a simple, portable, HTTP server using BSD sockets.

**Dumb HTTP server (multi-threaded)**

Implement a simple HTTP server supporting simultaneous connections using BSD sockets.

**group net_pkt**

Network packet management library.

**Defines**

`NET_PKT_SLAB_DEFINE(name, count)`

Create a `net_pkt` slab.

A `net_pkt` slab is used to store meta-information about network packets. It must be coupled with a data fragment pool (`NET_PKT_DATA_POOL_DEFINE`) used to store the actual packet data. The macro can be used by an application to define additional custom per-context TX packet slabs (see `net_context_setup_pools()`).
Parameters

- **name** – Name of the slab.
- **count** – Number of net_pkt in this slab.

\[
{\text{NET_PKT_TX_SLAB_DEFINE}}(\text{name, count})
\]

\[
{\text{NET_PKT_DATA_POOL_DEFINE}}(\text{name, count})
\]

Create a data fragment net_buf pool.

A net_buf pool is used to store actual data for network packets. It must be coupled with a net_pkt slab (NET_PKT_SLAB_DEFINE) used to store the packet meta-information. The macro can be used by an application to define additional custom per-context TX packet pools (see net_context_setup_pools()).

Parameters

- **name** – Name of the pool.
- **count** – Number of net_buf in this pool.

\[
{\text{net_pkt_print_frags}}(\text{pkt})
\]

Print fragment list and the fragment sizes.

Only available if debugging is activated.

Parameters

- **pkt** – Network pkt.

\[
{\text{NET_PKT_DATA_ACCESS_DEFINE}}(_{\text{name, _type}})
\]

\[
{\text{NET_PKT_DATA_ACCESS_CONTIGUOUS_DEFINE}}(_{\text{name, _type}})
\]

Functions

\[
\text{struct net_buf} \ast \text{net_pkt_get_reserve_rx_data}(\text{size_t min_len, k_timeout_t timeout})
\]

Get RX DATA buffer from pool.

Normally you should use net_pkt_get_frag() instead.

Normally this version is not useful for applications but is mainly used by network fragmentation code.

Parameters

- **min_len** – Minimum length of the requested fragment.
- **timeout** – Affects the action taken should the net buf pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait up to the specified time.

Returns

Network buffer if successful, NULL otherwise.

\[
\text{struct net_buf} \ast \text{net_pkt_get_reserve_tx_data}(\text{size_t min_len, k_timeout_t timeout})
\]

Get TX DATA buffer from pool.

Normally you should use net_pkt_get_frag() instead.

Normally this version is not useful for applications but is mainly used by network fragmentation code.

Parameters

- **min_len** – Minimum length of the requested fragment.
timeout – Affects the action taken should the net buf pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait up to the specified time.

Returns
Network buffer if successful, NULL otherwise.

struct net_buf *net_pkt_get_frag(struct net_pkt *pkt, size_t min_len, k_timeout_t timeout)

Get a data fragment that might be from user specific buffer pool or from global DATA pool.

Parameters
• pkt – Network packet.
• min_len – Minimum length of the requested fragment.
• timeout – Affects the action taken should the net buf pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait up to the specified time.

Returns
Network buffer if successful, NULL otherwise.

void net_pkt_unref(struct net_pkt *pkt)

Place packet back into the available packets slab.

Releases the packet to other use. This needs to be called by application after it has finished with the packet.

Parameters
• pkt – Network packet to release.

struct net_pkt *net_pkt_ref(struct net_pkt *pkt)

Increase the packet ref count.

Mark the packet to be used still.

Parameters
• pkt – Network packet to ref.

Returns
Network packet if successful, NULL otherwise.

struct net_buf *net_pkt_frag_ref(struct net_buf *frag)

Increase the packet fragment ref count.

Mark the fragment to be used still.

Parameters
• frag – Network fragment to ref.

Returns
a pointer on the referenced Network fragment.

void net_pkt_frag_unref(struct net_buf *frag)

Decrease the packet fragment ref count.

Parameters
• frag – Network fragment to unreff.
struct net_buf *net_pkt_frag_del(struct net_pkt *pkt, struct net_buf *parent, struct net_buf *frag)

Delete existing fragment from a packet.

Parameters

• pkt – Network packet from which frag belongs to.
• parent – parent fragment of frag, or NULL if none.
• frag – Fragment to delete.

Returns

Pointer to the following fragment, or NULL if it had no further fragments.

void net_pkt_frag_add(struct net_pkt *pkt, struct net_buf *frag)

Add a fragment to a packet at the end of its fragment list.

Parameters

• pkt – pkt Network packet where to add the fragment
• frag – Fragment to add

void net_pkt_frag_insert(struct net_pkt *pkt, struct net_buf *frag)

Insert a fragment to a packet at the beginning of its fragment list.

Parameters

• pkt – pkt Network packet where to insert the fragment
• frag – Fragment to insert

void net_pkt_compact(struct net_pkt *pkt)

Compact the fragment list of a packet.

After this there is no more any free space in individual fragments.

Parameters

• pkt – Network packet.

void net_pkt_get_info(struct k_mem_slab **rx, struct k_mem_slab **tx, struct net_buf_pool **rx_data, struct net_buf_pool **tx_data)

Get information about predefined RX, TX and DATA pools.

Parameters

• rx – Pointer to RX pool is returned.
• tx – Pointer to TX pool is returned.
• rx_data – Pointer to RX DATA pool is returned.
• tx_data – Pointer to TX DATA pool is returned.

struct net_pkt *net_pkt_alloc(k_timeout_t timeout)

Allocate an initialized net_pkt.

for the time being, 2 pools are used. One for TX and one for RX. This allocator has to be used for TX.

Parameters

• timeout – Maximum time to wait for an allocation.

Returns

a pointer to a newly allocated net_pkt on success, NULL otherwise.
struct net_pkt *net_pkt_alloc_from_slab(struct k_mem_slab *slab, k_timeout_t timeout)
Allocate an initialized \texttt{net_pkt} from a specific slab.

Unlike \texttt{net_pkt_alloc()} which uses core slabs, this one will use an external slab (see \texttt{NET_PKT_SLAB_DEFINE()}). Do not use it unless you know what you are doing. Basically, only \texttt{net_context} should be using this, in order to allocate packet and then buffer on its local slab/pool (if any).

**Parameters**

- \texttt{slab} – The slab to use for allocating the packet
- \texttt{timeout} – Maximum time to wait for an allocation.

**Returns**

A pointer to a newly allocated \texttt{net_pkt} on success, NULL otherwise.

struct net_pkt *net_pkt_alloc_rx(k_timeout_t timeout)
Allocate an initialized \texttt{net_pkt} for RX.

For the time being, 2 pools are used. One for TX and one for RX. This allocator has to be used for RX.

**Parameters**

- \texttt{timeout} – Maximum time to wait for an allocation.

**Returns**

A pointer to a newly allocated \texttt{net_pkt} on success, NULL otherwise.

struct net_pkt *net_pkt_alloc_on_iface(struct net_if *iface, k_timeout_t timeout)
Allocate a network packet for a specific network interface.

**Parameters**

- \texttt{iface} – The network interface the packet is supposed to go through.
- \texttt{timeout} – Maximum time to wait for an allocation.

**Returns**

A pointer to a newly allocated \texttt{net_pkt} on success, NULL otherwise.

struct net_pkt *net_pkt_alloc_on_iface_rx(struct net_if *iface, k_timeout_t timeout)
int net_pkt_alloc_buffer(struct net_pkt *pkt, size_t size, enum net_ip_protocol proto, k_timeout_t timeout)
Allocate buffer for a \texttt{net_pkt}.

Such allocator will take into account space necessary for headers, MTU, and existing buffer (if any). Beware that, due to all these criteria, the allocated size might be smaller/bigger than requested one.

**Parameters**

- \texttt{pkt} – The network packet requiring buffer to be allocated.
- \texttt{size} – The size of buffer being requested.
- \texttt{proto} – The IP protocol type (can be 0 for none).
- \texttt{timeout} – Maximum time to wait for an allocation.

**Returns**

0 on success, negative errno code otherwise.

int net_pkt_alloc_buffer_raw(struct net_pkt *pkt, size_t size, k_timeout_t timeout)
Allocate buffer for a \texttt{net_pkt}, of specified size, w/o any additional preconditions.

The actual buffer size may be larger than requested one if fixed size buffers are in use.
Parameters

- `pkt` – The network packet requiring buffer to be allocated.
- `size` – The size of buffer being requested.
- `timeout` – Maximum time to wait for an allocation.

Returns

0 on success, negative errno code otherwise.

```c
struct net_pkt  *net_pkt_alloc_with_buffer(struct net_if  *iface, size_t size,
                                          sa_family_t family, enum net_ip_protocol proto,
                                          k_timeout_t timeout)
```

Allocate a network packet and buffer at once.

Parameters

- `iface` – The network interface the packet is supposed to go through.
- `size` – The size of buffer.
- `family` – The family to which the packet belongs.
- `proto` – The IP protocol type (can be 0 for none).
- `timeout` – Maximum time to wait for an allocation.

Returns

A pointer to a newly allocated `net_pkt` on success, NULL otherwise.

```c
struct net_pkt  *net_pkt_rx_alloc_with_buffer(struct net_if  *iface, size_t size,
                                             sa_family_t family, enum net_ip_protocol proto,
                                             k_timeout_t timeout)
```

void `net_pkt_append_buffer(struct net_pkt  *pkt, struct net_buf  *buffer)`

Append a buffer in packet.

Parameters

- `pkt` – Network packet where to append the buffer
- `buffer` – Buffer to append

```c
size_t net_pkt_available_buffer(struct net_pkt  *pkt)
```

Get available buffer space from a `pkt`.

Note: Reserved bytes (headroom) in any of the fragments are not considered to be available.

```c
size_t net_pkt_available_payload_buffer(struct net_pkt  *pkt, enum net_ip_protocol proto)
```

Get available buffer space for payload from a `pkt`.

Unlike `net_pkt_available_buffer()`, this will take into account the headers space.
Note: Reserved bytes (headroom) in any of the fragments are not considered to be available.

Parameters

- `pkt` – The `net_pkt` which payload buffer availability should be evaluated
- `proto` – The IP protocol type (can be 0 for none).

Returns

the amount of buffer available for payload

```c
void net_pkt_trim_buffer(struct net_pkt *pkt)
```
Trim `net_pkt` buffer.
This will basically check for unused buffers and deallocate them relevantly

Parameters

- `pkt` – The `net_pkt` which buffer will be trimmed

```c
int net_pkt_remove_tail(struct net_pkt *pkt, size_t length)
```
Remove `length` bytes from tail of packet.
This function does not take packet cursor into account. It is a helper to remove unneeded bytes from tail of packet (like appended CRC). It takes care of buffer deallocation if removed bytes span whole buffer(s).

Parameters

- `pkt` – Network packet
- `length` – Number of bytes to be removed

Return values

- 0 – On success.
- -EINVAL – If packet length is shorter than `length`.

```c
void net_pkt_cursor_init(struct net_pkt *pkt)
```
Initialize `net_pkt` cursor.
This will initialize the `net_pkt` cursor from its buffer.

Parameters

- `pkt` – The `net_pkt` whose cursor is going to be initialized

```c
static inline void net_pkt_cursor_backup(struct net_pkt *pkt, struct net_pkt_cursor *backup)
```
Backup `net_pkt` cursor.

Parameters

- `pkt` – The `net_pkt` whose cursor is going to be backed up
- `backup` – The cursor where to backup `net_pkt` cursor

```c
static inline void net_pkt_cursor_restore(struct net_pkt *pkt, struct net_pkt_cursor *backup)
```
Restore `net_pkt` cursor from a backup.

Parameters

- `pkt` – The `net_pkt` whose cursor is going to be restored
- `backup` – The cursor from where to restore `net_pkt` cursor
static inline void *net_pkt_cursor_get_pos(struct net_pkt *pkt)
    Returns current position of the cursor.

    Parameters
    • pkt – The net_pkt whose cursor position is going to be returned

    Returns
    cursor’s position

int net_pkt_skip(struct net_pkt *pkt, size_t length)
    Skip some data from a net_pkt.
    net_pkt’s cursor should be properly initialized Cursor position will be updated after
    the operation. Depending on the value of pkt->overwrite bit, this function will af-
    fect the buffer length or not. If it’s true, it will advance the cursor to the requested
    length. If it’s false, it will do the same but if the cursor was already also at the end of
    existing data, it will increment the buffer length. So in this case, its behavior is just
    like net_pkt_write or net_pkt_memset, difference being that it will not affect the buffer
    content itself (which may be just garbage then).

    Parameters
    • pkt – The net_pkt whose cursor will be updated to skip given amount of
          data from the buffer.
    • length – Amount of data to skip in the buffer

    Returns
    0 in success, negative errno code otherwise.

int net_pkt_memset(struct net_pkt *pkt, int byte, size_t length)
    Memset some data in a net_pkt.
    net_pkt’s cursor should be properly initialized and, if needed, positioned using
    net_pkt_skip. Cursor position will be updated after the operation.

    Parameters
    • pkt – The net_pkt whose buffer to fill starting at the current cursor posi-
          tion.
    • byte – The byte to write in memory
    • length – Amount of data to memset with given byte

    Returns
    0 in success, negative errno code otherwise.

int net_pkt_copy(struct net_pkt *pkt_dst, struct net_pkt *pkt_src, size_t length)
    Copy data from a packet into another one.
    Both net_pkt cursors should be properly initialized and, if needed, positioned using
    net_pkt_skip. The cursors will be updated after the operation.

    Parameters
    • pkt_dst – Destination network packet.
    • pkt_src – Source network packet.
    • length – Length of data to be copied.

    Returns
    0 on success, negative errno code otherwise.
struct *net_pkt_clone(struct *pkt, k_timeout_t timeout)
    Clone pkt and its buffer.
    The cloned packet will be allocated on the same pool as the original one.

Parameters
    • pkt – Original pkt to be cloned
    • timeout – Timeout to wait for free buffer

Returns
    NULL if error, cloned packet otherwise.

struct *net_pkt_rx_clone(struct *pkt, k_timeout_t timeout)
    Clone pkt and its buffer.
    The cloned packet will be allocated on the RX packet poll.

Parameters
    • pkt – Original pkt to be cloned
    • timeout – Timeout to wait for free buffer

Returns
    NULL if error, cloned packet otherwise.

struct *net_pkt_shallow_clone(struct *pkt, k_timeout_t timeout)
    Clone pkt and increase the refcount of its buffer.

Parameters
    • pkt – Original pkt to be shallow cloned
    • timeout – Timeout to wait for free packet

Returns
    NULL if error, cloned packet otherwise.

int net_pkt_read(struct *pkt, void *data, size_t length)
    Read some data from a net_pkt.
    net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
    • pkt – The network packet from where to read some data
    • data – The destination buffer where to copy the data
    • length – The amount of data to copy

Returns
    0 on success, negative errno code otherwise.

static inline int net_pkt_read_u8(struct *pkt, uint8_t *data)

int net_pkt_read_be16(struct *pkt, uint16_t *data)
    Read uint16_t big endian data from a net_pkt.
    net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
    • pkt – The network packet from where to read
    • data – The destination uint16_t where to copy the data
Returns
0 on success, negative errno code otherwise.

int net_pkt_read_le16(struct net_pkt *pkt, uint16_t *data)
Read uint16_t little endian data from a net_pkt.

net_pkt's cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet from where to read
• data – The destination uint16_t where to copy the data

Returns
0 on success, negative errno code otherwise.

int net_pkt_read_be32(struct net_pkt *pkt, uint32_t *data)
Read uint32_t big endian data from a net_pkt.

net_pkt's cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet from where to read
• data – The destination uint32_t where to copy the data

Returns
0 on success, negative errno code otherwise.

int net_pkt_write(struct net_pkt *pkt, const void *data, size_t length)
Write data into a net_pkt.

net_pkt's cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet where to write
• data – Data to be written
• length – Length of the data to be written

Returns
0 on success, negative errno code otherwise.

static inline int net_pkt_write_u8(struct net_pkt *pkt, uint8_t data)
static inline int net_pkt_write_be16(struct net_pkt *pkt, uint16_t data)
static inline int net_pkt_write_be32(struct net_pkt *pkt, uint32_t data)
static inline int net_pkt_write_le32(struct net_pkt *pkt, uint32_t data)
static inline int net_pkt_write_le16(struct net_pkt *pkt, uint16_t data)

size_t net_pkt_remaining_data(struct net_pkt *pkt)
Get the amount of data which can be read from current cursor position.

Parameters
• pkt – Network packet

Returns
Amount of data which can be read from current pkt cursor
int net_pkt_update_length(struct net pkt *pkt, size_t length)
Update the overall length of a packet.

Unlike net pkt pull() below, this does not take packet cursor into account. It's mainly
a helper dedicated for ipv4 and ipv6 input functions. It shrinks the overall length by
given parameter.

Parameters

• pkt – Network packet
• length – The new length of the packet

Returns

0 on success, negative errno code otherwise.

int net_pkt_pull(struct net pkt *pkt, size_t length)
Remove data from the packet at current location.

net pkt's cursor should be properly initialized and, eventually, properly positioned us-
ing net_pkt_skip/read/write. Note that net pkt's cursor is reset by this function.

Parameters

• pkt – Network packet
• length – Number of bytes to be removed

Returns

0 on success, negative errno code otherwise.

uint16_t net_pkt_get_current_offset(struct net pkt *pkt)
Get the actual offset in the packet from its cursor.

Parameters

• pkt – Network packet.

Returns

a valid offset on success, 0 otherwise as there is nothing that can be done
to evaluate the offset.

bool net_pkt_is_contiguous(struct net pkt *pkt, size_t size)
Check if a data size could fit contiguously.

net pkt's cursor should be properly initialized and, if needed, positioned using
net_pkt_skip.

Parameters

• pkt – Network packet.
• size – The size to check for contiguity

Returns

ture if that is the case, false otherwise.

size_t net_pkt_get_contiguous_len(struct net pkt *pkt)
Get the contiguous buffer space.

Parameters

• pkt – Network packet

Returns

The available contiguous buffer space in bytes starting from the current
cursor position. 0 in case of an error.
void *net_pkt_get_data(struct net_pkt *pkt, struct net_pkt_data_access *access)

Get data from a network packet in a contiguous way.

net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Unlike other functions, cursor position will not be updated after the operation.

Parameters

• pkt – The network packet from where to get the data.
• access – A pointer to a valid net_pkt_data_access describing the data to get in a contiguous way.

Returns

a pointer to the requested contiguous data, NULL otherwise.

int net_pkt_set_data(struct net_pkt *pkt, struct net_pkt_data_access *access)

Set contiguous data into a network packet.

net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters

• pkt – The network packet to where the data should be set.
• access – A pointer to a valid net_pkt_data_access describing the data to set.

Returns

0 on success, a negative errno otherwise.

static inline int net_pkt_acknowledge_data(struct net_pkt *pkt, struct net_pkt_data_access *access)

Acknowledge previously contiguous data taken from a network packet Packet needs to be set to overwrite mode.

struct net_pkt_cursor

#include <net_pkt.h>

Public Members

struct net_buf *buf

Current net_buf pointer by the cursor.

uint8_t *pos

Current position in the data buffer of the net_buf.

struct net_pkt

#include <net_pkt.h> Network packet.

Note that if you add new fields into net_pkt, remember to update net_pkt_clone() function.

Public Members
### Networking Technologies

#### Ethernet

- **Overview**
- **API Reference**

#### Virtual LAN (VLAN) Support

- **Overview**
- **API Reference**

**Overview**  Virtual LAN (VLAN) is a partitioned and isolated computer network at the data link layer (OSI layer 2). For ethernet network this refers to IEEE 802.1Q

In Zephyr, each individual VLAN is modeled as a virtual network interface. This means that there is an ethernet network interface that corresponds to a real physical ethernet port in the system. A virtual network interface is created for each VLAN, and this virtual network interface connects to the real network interface. This is similar to how Linux implements VLANs. The `eth0` is the real network interface and `vlan0` is a virtual network interface that is run on top of `eth0`.

VLAN support must be enabled at compile time by setting option `CONFIG_NET_VLAN` and `CONFIG_NET_VLAN_COUNT` to reflect how many network interfaces there will be in the system. For example, if there is one network interface without VLAN support, and two with VLAN support, the `CONFIG_NET_VLAN_COUNT` option should be set to 3.
Even if VLAN is enabled in a prj.conf file, the VLAN needs to be activated at runtime by the application. The VLAN API provides a `net_eth_vlan_enable()` function to do that. The application needs to give the network interface and desired VLAN tag as a parameter to that function. The VLAN tagging for a given network interface can be disabled by a `net_eth_vlan_disable()` function. The application needs to configure the VLAN network interface itself, such as setting the IP address, etc.

See also the VLAN sample application for API usage example. The source code for that sample application can be found at `samples/net/vlan`.

The net-shell module contains `net_vlan add` and `net_vlan del` commands that can be used to enable or disable VLAN tags for a given network interface.

See the IEEE 802.1Q spec for more information about ethernet VLANs.

---

### API Reference

### Related code samples

**Virtual LAN**

Setup two virtual LAN networks and use net-shell to view the networks’ settings.

```c

```
Returns
Priority code point.

static inline uint16_t net_eth_vlan_set_vid(uint16_t tci, uint16_t vid)
Set VLAN identifier to TCI.

Parameters
• tci – VLAN tag control information.
• vid – VLAN identifier.

Returns
New TCI value.

static inline uint16_t net_eth_vlan_set_dei(uint16_t tci, bool dei)
Set Drop Eligible Indicator to TCI.

Parameters
• tci – VLAN tag control information.
• dei – Drop eligible indicator.

Returns
New TCI value.

static inline uint16_t net_eth_vlan_set_pcp(uint16_t tci, uint8_t pcp)
Set Priority Code Point to TCI.

Parameters
• tci – VLAN tag control information.
• pcp – Priority code point.

Returns
New TCI value.

Link Layer Discovery Protocol

Overview
The Link Layer Discovery Protocol (LLDP) is a vendor-neutral link layer protocol used by network devices for advertising their identity, capabilities, and neighbors on a wired Ethernet network.

For more information, see this LLDP Wikipedia article.

API Reference

Related code samples

Link Layer Discovery Protocol (LLDP)
Enable LLDP support and setup VLANs.

group lldp
LLDP definitions and helpers.
Defines

```c
net_lldp_set_lldpdu(iface)
```
Set LLDP protocol data unit (LLDPDU) for the network interface.

**Parameters**
- `iface` – Network interface

**Returns**
- `<0 if error, index in lldp array if iface is found there`

```c
net_lldp_unset_lldpdu(iface)
```
Unset LLDP protocol data unit (LLDPDU) for the network interface.

**Parameters**
- `iface` – Network interface

Typedefs

```c
typedef enum net_verdict (*net_lldp_recv_cb_t)(struct net_if *iface, struct net_pkt *pkt)

LLDP Receive packet callback.
```
Callback gets called upon receiving packet. It is responsible for freeing packet or indicating to the stack that it needs to free packet by returning correct net_verdict.

**Returns:**
- `NET_DROP`, if packet was invalid, rejected or we want the stack to free it. In this case the core stack will free the packet.
- `NET_OK`, if the packet was accepted, in this case the ownership of the `net_pkt` goes to callback and core network stack will forget it.

Enums

```c
enum net_lldp_tlv_type
```
TLV Types.
Please refer to table 8-1 from IEEE 802.1AB standard.

**Values:**
- `LLDP_TLV_END_LLDPDU = 0`
  End Of LLDPDU (optional)
- `LLDP_TLV_CHASSIS_ID = 1`
  Chassis ID (mandatory)
- `LLDP_TLV_PORT_ID = 2`
  Port ID (mandatory)
- `LLDP_TLV_TTL = 3`
  Time To Live (mandatory)
enumerator LLDP_TLV_PORT_DESC = 4
Port Description (optional)

enumerator LLDP_TLV_SYSTEM_NAME = 5
System Name (optional)

enumerator LLDP_TLV_SYSTEM_DESC = 6
System Description (optional)

enumerator LLDP_TLV_SYSTEM_CAPABILITIES = 7
System Capability (optional)

enumerator LLDP_TLV_MANAGEMENT_ADDR = 8
Management Address (optional)

enumerator LLDP_TLV_ORG_SPECIFIC = 127
Org specific TLVs (optional)

Functions

int net_lldp_config(struct net_if *iface, const struct net_lldpdu *lldpdu)
Set the LLDP data unit for a network interface.

Parameters
• iface – Network interface
• lldpdu – LLDP data unit struct

Returns
0 if ok, <0 if error

int net_lldp_config_optional(struct net_if *iface, const uint8_t *tlv, size_t len)
Set the Optional LLDP TLVs for a network interface.

Parameters
• iface – Network interface
• tlv – LLDP optional TLVs following mandatory part
• len – Length of the optional TLVs

Returns
0 if ok, <0 if error

void net_lldp_init(void)
Initialize LLDP engine.

int net_lldp_register_callback(struct net_if *iface, net_lldp_recv_cb_t cb)
Register LLDP Rx callback function.

Parameters
• iface – Network interface
• cb – Callback function

Returns
0 if ok, <0 if error
enum net_verdict net_lldp_recv(struct net_if *iface, struct net_pkt *pkt)
    Parse LLDP packet.

    Parameters
    • iface – Network interface
    • pkt – Network packet

    Returns
    Return the policy for network buffer

struct net_lldp_chassis_tlv
    #include <lldp.h> Chassis ID TLV, see chapter 8.5.2 in IEEE 802.1AB.

    Public Members

    uint16_t type_length
        7 bits for type, 9 bits for length

    uint8_t subtype
        ID subtype.

    uint8_t (*value)[NET_LLDP_CHASSIS_ID_VALUE_LEN]
        Chassis ID value.

struct net_lldp_port_tlv
    #include <lldp.h> Port ID TLV, see chapter 8.5.3 in IEEE 802.1AB.

    Public Members

    uint16_t type_length
        7 bits for type, 9 bits for length

    uint8_t subtype
        ID subtype.

    uint8_t (*value)[NET_LLDP_PORT_ID_VALUE_LEN]
        Port ID value.

struct net_lldp_time_to_live_tlv
    #include <lldp.h> Time To Live TLV, see chapter 8.5.4 in IEEE 802.1AB.

    Public Members

    uint16_t type_length
        7 bits for type, 9 bits for length
uint16_t ttl

Time To Live (TTL) value.

struct net_lldpdu

#include <lldp.h> LLDP Data Unit (LLDPDU) shall contain the following ordered TLVs as stated in “8.2 LLDPDU format” from the IEEE 802.1AB.

Public Members

struct net_lldp_chassis_tlv chassis_id

Mandatory Chassis TLV.

struct net_lldp_port_tlv port_id

Mandatory Port TLV.

struct net_lldp_time_to_live_tlv ttl

Mandatory TTL TLV.

IEEE 802.1Qav

Overview Credit-based shaping is an alternative scheduling algorithm used in network schedulers to achieve fairness when sharing a limited network resource. Zephyr has support for configuring a credit-based shaper described in the IEEE 802.1Qav-2009 standard. Zephyr does not implement the actual shaper; it only provides a way to configure the shaper implemented by the Ethernet device driver.

Enabling 802.1Qav To enable 802.1Qav shaper, the Ethernet device driver must declare that it supports credit-based shaping. The Ethernet driver’s capability function must return ETHERNET_QAV value for this purpose. Typically also priority queues ETHERNET_PRIORITY_QUEUES need to be supported.

static enum ethernet_hw_caps eth_get_capabilities(const struct device *dev) {
    ARG_UNUSED(dev);

    return ETHERNET_QAV | ETHERNET_PRIORITY_QUEUES |
        ETHERNET_HW_VLAN | ETHERNET_LINK_10BASE_T |
        ETHERNET_LINK_100BASE_T;
}

See sam-e70-xplained board Ethernet driver drivers/ethernet/eth_sam_gmac.c for an example.

Configuring 802.1Qav The application can configure the credit-based shaper like this:

#include <zephyr/net/net_if.h>
#include <zephyr/net/ethernet.h>
#include <zephyr/net/ethernet_mgmt.h>

static void qav_set_status(struct net_if *iface,
    int queue_id, bool enable)

(continues on next page)
Overview  Ethernet is a networking technology commonly used in local area networks (LAN). For more information, see this Ethernet Wikipedia article.

Zephyr supports following Ethernet features:
• 10, 100 and 1000 Mbit/sec links
• Auto negotiation
• Half/full duplex
• Promiscuous mode
• TX and RX checksum offloading
• MAC address filtering
• Virtual LANs
• Priority queues
• IEEE 802.1AS (gPTP)
• IEEE 802.1Qav (credit based shaping)
• LLDP (Link Layer Discovery Protocol)

Not all Ethernet device drivers support all of these features. You can see what is supported by `net iface net-shell` command. It will print currently supported Ethernet features.

API Reference

Related code samples

Inter-VM Shared Memory (ivshmem) Ethernet
Communicate with another “cell” in the Jailhouse hypervisor using IVSHMEM Ethernet.

Packet socket
Use raw packet sockets over Ethernet.

UDP sender using SO_TXTIME
Control the transmission time of a packet using SO_TXTIME socket option.

---

group ethernet

Ethernet support functions.

Defines

ETH_NET_DEVICE_INIT(dev_id, name, init_fn, pm, data, config, prio, api, mtu)
Create an Ethernet network interface and bind it to network device.

Parameters

• dev_id – Network device id.
• name – The name this instance of the driver exposes to the system.
• init_fn – Address to the init function of the driver.
• pm – Reference to struct pm_device associated with the device. (optional).
• data – Pointer to the device's private data.
• config – The address to the structure containing the configuration information for this instance of the driver.
• prio – The initialization level at which configuration occurs.
• api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
• mtu – Maximum transfer unit in bytes for this network interface.

6.3. Networking
ETH_NET_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, prio, api, mtu)
Like ETH_NET_DEVICE_INIT but taking metadata from a devicetree.
Create an Ethernet network interface and bind it to network device.

Parameters
- node_id – The devicetree node identifier.
- init_fn – Address to the init function of the driver.
- pm – Reference to struct pm_device associated with the device. (optional).
- data – Pointer to the device's private data.
- config – The address to the structure containing the configuration information for this instance of the driver.
- prio – The initialization level at which configuration occurs.
- api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
- mtu – Maximum transfer unit in bytes for this network interface.

ETH_NET_DEVICE_DT_INST_DEFINE(inst, ...)
Like ETH_NET_DEVICE_DT_DEFINE for an instance of a DT_DRV_COMPAT compatible.

Parameters
- inst – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to ETH_NET_DEVICE_DT_DEFINE.
- ... – other parameters as expected by ETH_NET_DEVICE_DT_DEFINE.

Enums

enum ethernet_hw_caps
Ethernet hardware capabilities.
Values:

enumerator ETHERNET_HW_TX_CHKSUM_OFFLOAD = BIT(0)
TX Checksum offloading supported for all of IPv4, UDP, TCP.

denumerator ETHERNET_HW_RX_CHKSUM_OFFLOAD = BIT(1)
RX Checksum offloading supported for all of IPv4, UDP, TCP.

denumerator ETHERNET_HW_VLAN = BIT(2)
VLAN supported.

denumerator ETHERNET_AUTO_NEGOTIATION_SET = BIT(3)
Enabling/disabling auto negotiation supported.

denumerator ETHERNET_LINK_10BASE_T = BIT(4)
10 Mbits link supported

denumerator ETHERNET_LINK_100BASE_T = BIT(5)
100 Mbits link supported
enumerator ETHERNET_LINK_1000BASE_T = BIT(6)
    1 Gbits link supported

enumerator ETHERNET_DUPLEX_SET = BIT(7)
    Changing duplex (half/full) supported.

enumerator ETHERNET_PTP = BIT(8)
    IEEE 802.1AS (gPTP) clock supported.

enumerator ETHERNET_QAV = BIT(9)
    IEEE 802.1Qav (credit-based shaping) supported.

enumerator ETHERNET_PROMISC_MODE = BIT(10)
    Promiscuous mode supported.

enumerator ETHERNET_PRIORITY_QUEUES = BIT(11)
    Priority queues available.

enumerator ETHERNET_HW_FILTERING = BIT(12)
    MAC address filtering supported.

enumerator ETHERNET_LLDP = BIT(13)
    Link Layer Discovery Protocol supported.

enumerator ETHERNET_HW_VLAN_TAG_STRIP = BIT(14)
    VLAN Tag stripping.

enumerator ETHERNET_DSA_SLAVE_PORT = BIT(15)
    DSA switch.

enumerator ETHERNET_DSA_MASTER_PORT = BIT(16)

enumerator ETHERNET_QBV = BIT(17)
    IEEE 802.1Qbv (scheduled traffic) supported.

enumerator ETHERNET_QBU = BIT(18)
    IEEE 802.1Qbu (frame preemption) supported.

enumerator ETHERNET_TXTIME = BIT(19)
    TXTIME supported.

enumerator ETHERNET_TXINJECTION_MODE = BIT(20)
    TX-Injection supported.

enum ethernet_if_types
    Types of Ethernet L2.

Values:
enumerator L2_ETH_IF_TYPE_ETHERNET
IEEE 802.3 Ethernet (default)

enumerator L2_ETH_IF_TYPE_WIFI
IEEE 802.11 Wi-Fi.

enum ethernet_flags
Values:

enumerator ETH_CARRIER_UP

Functions

void ethernet_init(struct net_if *iface)
Initialize Ethernet L2 stack for a given interface.

Parameters
• iface – A valid pointer to a network interface

void net_eth_ipv4_mcast_to_mac_addr(const struct in_addr *ipv4_addr, struct net_eth_addr *mac_addr)
Convert IPv4 multicast address to Ethernet address.

Parameters
• ipv4_addr – IPv4 multicast address
• mac_addr – Output buffer for Ethernet address

void net_eth_ipv6_mcast_to_mac_addr(const struct in6_addr *ipv6_addr, struct net_eth_addr *mac_addr)
Convert IPv6 multicast address to Ethernet address.

Parameters
• ipv6_addr – IPv6 multicast address
• mac_addr – Output buffer for Ethernet address

static inline enum ethernet_hw_caps net_eth_get_hw_capabilities(struct net_if *iface)
Return ethernet device hardware capability information.

Parameters
• iface – Network interface

Returns
Hardware capabilities

static inline int net_eth_vlan_enable(struct net_if *iface, uint16_t tag)
Add VLAN tag to the interface.

Parameters
• iface – Interface to use.
• tag – VLAN tag to add

Returns
0 if ok, <0 if error
static inline int net_eth_vlan_disable(struct net_if *iface, uint16_t tag)
    Remove VLAN tag from the interface.

    Parameters
    • iface – Interface to use.
    • tag – VLAN tag to remove

    Returns
    0 if ok, <0 if error

static inline uint16_t net_eth_get_vlan_tag(struct net_if *iface)
    Return VLAN tag specified to network interface.

    Parameters
    • iface – Network interface.

    Returns
    VLAN tag for this interface or NET_VLAN_TAG_UNSPEC if VLAN is not configured for that interface.

static inline struct net_if *net_eth_get_vlan_iface(struct net_if *iface, uint16_t tag)
    Return network interface related to this VLAN tag.

    Parameters
    • iface – Master network interface. This is used to get the pointer to ethernet L2 context
    • tag – VLAN tag

    Returns
    Network interface related to this tag or NULL if no such interface exists.

static inline bool net_eth_is_vlan_enabled(struct ethernet_context *ctx, struct net_if *iface)
    Check if VLAN is enabled for a specific network interface.

    Parameters
    • ctx – Ethernet context
    • iface – Network interface

    Returns
    True if VLAN is enabled for this network interface, false if not.

static inline bool net_eth_get_vlan_status(struct net_if *iface)
    Get VLAN status for a given network interface (enabled or not).

    Parameters
    • iface – Network interface

    Returns
    True if VLAN is enabled for this network interface, false if not.

void net_eth_carrier_on(struct net_if *iface)
    Inform ethernet L2 driver that ethernet carrier is detected.
    This happens when cable is connected.

    Parameters
    • iface – Network interface
void net_eth_carrier_off(struct net_if *iface)
  Inform ethernet L2 driver that ethernet carrier was lost.
  This happens when cable is disconnected.

Parameters
• iface – Network interface

int net_eth_promisc_mode(struct net_if *iface, bool enable)
  Set promiscuous mode either ON or OFF.

Parameters
• iface – Network interface
• enable – on (true) or off (false)

Returns
  0 if mode set or unset was successful, <0 otherwise.

int net_eth_txinjection_mode(struct net_if *iface, bool enable)
  Set TX-Injection mode either ON or OFF.

Parameters
• iface – Network interface
• enable – on (true) or off (false)

Returns
  0 if mode set or unset was successful, <0 otherwise.

static inline const struct device *net_eth_get_ptp_clock(struct net_if *iface)
  Return PTP clock that is tied to this ethernet network interface.

Parameters
• iface – Network interface

Returns
  Pointer to PTP clock if found, NULL if not found or if this ethernet interface
does not support PTP.

const struct device *net_eth_get_ptp_clock_by_index(int index)
  Return PTP clock that is tied to this ethernet network interface index.

Parameters
• index – Network interface index

Returns
  Pointer to PTP clock if found, NULL if not found or if this ethernet interface
index does not support PTP.

static inline int net_eth_get_ptp_port(struct net_if *iface)
  Return PTP port number attached to this interface.

Parameters
• iface – Network interface

Returns
  Port number, no such port if < 0

static inline void net_eth_set_ptp_port(struct net_if *iface, int port)
  Set PTP port number attached to this interface.

Parameters
• **iface** – Network interface
• **port** – Port number to set

```c
static inline bool net_eth_type_is_wifi(struct net_if *iface)
Check if the Ethernet L2 network interface can perform Wi-Fi.
```

**Parameters**
• **iface** – Pointer to network interface

**Returns**
True if interface supports Wi-Fi, False otherwise.

```c
struct ethernet_t1s_param
#include <ethernet.h>
```

**Public Members**

```c
enum ethernet_t1s_param_type type
    Type of T1S parameter.

bool enable
    T1S PLCA enabled.

uint8_t node_id
    T1S PLCA node id range: 0 to 254.

uint8_t node_count
    T1S PLCA node count range: 1 to 255.

uint8_t burst_count
    T1S PLCA burst count range: 0x0 to 0xFF.

uint8_t burst_timer
    T1S PLCA burst timer.

uint8_t to_timer
    T1S PLCA TO value.
```

```c
struct ethernet_qav_param
#include <ethernet.h>
```

**Public Members**

```c
int queue_id
    ID of the priority queue to use.

enum ethernet_qav_param_type type
    Type of Qav parameter.
```
bool enabled
   True if Qav is enabled for queue.

unsigned int delta_bandwidth
   Delta Bandwidth (percentage of bandwidth)

unsigned int idle_slope
   Idle Slope (bits per second)

unsigned int oper_idle_slope
   Oper Idle Slope (bits per second)

unsigned int traffic_class
   Traffic class the queue is bound to.

struct ethernet_qbv_param
   #include <ethernet.h>

Public Members

int port_id
   Port id.

enum ethernet_qbv_param_type type
   Type of Qbv parameter.

enum ethernet_qbv_state_type state
   What state (Admin/Oper) parameters are these.

bool enabled
   True if Qbv is enabled or not.

bool gate_status[NET_TC_TX_COUNT]
   True = open, False = closed.

enum ethernet_gate_state_operation operation
   GateState operation.

uint32_t time_interval
   Time interval ticks (nanoseconds)

uint16_t row
   Gate control list row.

uint32_t gate_control_list_len
   Number of entries in gate control list.
struct *net_ptp_extended_time* base_time
   Base time.

struct *net_ptp_time* cycle_time
   Cycle time.

uint32_t extension_time
   Extension time (nanoseconds)

struct ethernet_qbu_param
   #include <ethernet.h>

**Public Members**

int port_id
   Port id.

denum ethernet_qbu_param_type type
   Type of Qbu parameter.

uint32_t hold_advance
   Hold advance (nanoseconds)

uint32_t release_advance
   Release advance (nanoseconds)

denum ethernet_qbu_preempt_status frame_preempt_statuses[NET_TC_TX_COUNT]
   sequence of framePreemptionAdminStatus values.

bool enabled
   True if Qbu is enabled or not.

bool link_partner_status
   Link partner status (from Qbr)

uint8_t additional_fragment_size
   Additional fragment size (from Qbr).
   The minimum non-final fragment size is (additional_fragment_size + 1) * 64 octets

struct ethernet_filter
   #include <ethernet.h>

**Public Members**

denum ethernet_filter_type type
   Type of filter.
struct net_eth_addr mac_address
    MAC address to filter.

bool set
    Set (true) or unset (false) the filter.

struct ethernet_txtime_param
    #include <ethernet.h>

Public Members

enum ethernet_txtime_param_type type
    Type of TXTIME parameter.

int queue_id
    Queue number for configuring TXTIME.

bool enable_txtime
    Enable or disable TXTIME per queue.

struct ethernet_api
    #include <ethernet.h>

Public Members

struct net_if_api iface_api
    The net_if_api must be placed in first position in this struct so that we are compatible with network interface API.

int (*start)(const struct device *dev)
    Start the device.

int (*stop)(const struct device *dev)
    Stop the device.

enum ethernet_hw_caps (*get_capabilities)(const struct device *dev)
    Get the device capabilities.

int (*set_config)(const struct device *dev, enum ethernet_config_type type, const struct ethernet_config *config)
    Set specific hardware configuration.

int (*get_config)(const struct device *dev, enum ethernet_config_type type, struct ethernet_config *config)
    Get hardware specific configuration.
int (*send)(const struct device *dev, struct net_pkt *pkt)
   Send a network packet.

struct ethernet_context
#include <ethernet.h> Ethernet L2 context that is needed for VLAN.

Public Members

atomic_t flags
   Flags representing ethernet state, which are accessed from multiple threads.

struct k_work carrier_work
   Carrier ON/OFF handler worker.
   This is used to create network interface UP/DOWN event when ethernet L2 driver
   notices carrier ON/OFF situation. We must not create another network manage-
   ment event from inside management handler thus we use worker thread to trigger
   the UP/DOWN event.

struct net_if *iface
   Network interface.

enum net_l2_flags ethernet_l2_flags
   This tells what L2 features does ethernet support.

bool is_net_carrier_up
   Is network carrier up.

bool is_init
   Is this context already initialized.

enum ethernet_if_types eth_if_type
   Types of Ethernet network interfaces.

group ethernet_mii
   Ethernet MII (media independent interface) functions.

Defines

MII_BMCR
   Basic Mode Control Register.

MII_BMSR
   Basic Mode Status Register.

MII_PHYID1R
   PHY ID 1 Register.
MII_PHYID2R
PHY ID 2 Register.

MII_ANAR
Auto-Negotiation Advertisement Register.

MII_ANLPAR
Auto-Negotiation Link Partner Ability Reg.

MII_ANER
Auto-Negotiation Expansion Register.

MII_ANNPTR
Auto-Negotiation Next Page Transmit Register.

MII_ANLPRNPR
Auto-Negotiation Link Partner Received Next Page Reg.

MII_1KTCR
1000BASE-T Control Register

MII_1KSTSR
1000BASE-T Status Register

MII_MMD_ACR
MMD Access Control Register.

MII_MMD_AADR
MMD Access Address Data Register.

MII_ESTAT
Extended Status Register.

MII_BMCR_RESET
PHY reset.

MII_BMCR_LOOPBACK
enable loopback mode

MII_BMCR_SPEED_LSB
10=1000Mbps 01=100Mbps; 00=10Mbps

MII_BMCR_AUTONEG_ENABLE
Auto-Negotiation enable.

MII_BMCR_POWER_DOWN
power down mode
MII_BMCR_ISOLATE
   isolate electrically PHY from MII

MII_BMCR_AUTONEG_RESTART
   restart auto-negotiation

MII_BMCR_DUPLEX_MODE
   full duplex mode

MII_BMCR_SPEED_MSB
   10=1000Mbps 01=100Mbps; 00=10Mbps

MII_BMCR_SPEED_MASK
   Link Speed Field.

MII_BMCR_SPEED_10
   select speed 10 Mb/s

MII_BMCR_SPEED_100
   select speed 100 Mb/s

MII_BMCR_SPEED_1000
   select speed 1000 Mb/s

MII_BMSR_100BASE_T4
   100BASE-T4 capable

MII_BMSR_100BASE_X_FULL
   100BASE-X full duplex capable

MII_BMSR_100BASE_X_HALF
   100BASE-X half duplex capable

MII_BMSR_10_FULL
   10 Mb/s full duplex capable

MII_BMSR_10_HALF
   10 Mb/s half duplex capable

MII_BMSR_100BASE_T2_FULL
   100BASE-T2 full duplex capable

MII_BMSR_100BASE_T2_HALF
   100BASE-T2 half duplex capable

MII_BMSR_EXTEND_STATUS
   extend status information in reg 15

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MII_BMSR_MF_PREAMB_SUPPR
PHY accepts management frames with preamble suppressed.

MII_BMSR_AUTONEG_COMPLETE
Auto-negotiation process completed.

MII_BMSR_REMOTE_FAULT
remote fault detected

MII_BMSR_AUTONEG_ABILITY
PHY is able to perform Auto-Negotiation.

MII_BMSR_LINK_STATUS
link is up

MII_BMSR_JABBER_DETECT
jabber condition detected

MII_BMSR_EXTEND_CAPAB
extended register capabilities

MII_ADVERTISE_NEXT_PAGE
next page

MII_ADVERTISE_LPACK
link partner acknowledge response

MII_ADVERTISE_REMOTE_FAULT
remote fault

MII_ADVERTISEASYM_PAUSE
try for asymmetric pause

MII_ADVERTISE_PAUSE
try for pause

MII_ADVERTISE_100BASE_T4
try for 100BASE-T4 support

MII_ADVERTISE_100_FULL
try for 100BASE-X full duplex support

MII_ADVERTISE_100_HALF
try for 100BASE-X support

MII_ADVERTISE_10_FULL
try for 10 Mb/s full duplex support
IEEE 802.15.4

**Introduction**  IEEE 802.15.4 is a technical standard which defines the operation of low-rate wireless personal area networks (LR-WPANs). For a more detailed overview of this standard, see the IEEE 802.15.4 Wikipedia article.

The most recent version of the standard is accessible through the IEEE GET Program. You need to create a free IEEE account and can then downloading it.

We're currently following the IEEE 802.15.4-2020 specification. This version is backwards compatible with IEEE 802.15.4-2015, parts of which are contained in the Thread protocol stack. The
2020 version also includes prior extensions that were accepted into the standard, namely IEEE 802.15.4g (SUN FSK) and IEEE 802.15.4e (TSCH) which are of relevance to industrial IoT and automation. For recent developments in UWB ranging technology, see IEEE 802.15.4z which is not yet integrated into the standard's mainline.

Whenever sections from the standard are cited in the documentation, they refer to IEEE 802.15.4-2020 section, table and figure numbering - unless otherwise specified.

Zephyr supports both, native IEEE 802.15.4 and Thread, with 6LoWPAN. Zephyr’s Thread protocol implementation is based on OpenThread. The IPv6 header compression in 6LoWPAN is shared among native IEEE 802.15.4 and the Bluetooth IPSP (IP support profile).

API Reference

IEEE 802.15.4 API Overview  Gives an introduction and overview over the whole IEEE 802.15.4 subsystem and all of its APIs, configuration and user interfaces for all audiences.

Related code samples

802.15.4 "serial-radio"  Implement a slip-radio device for Contiki-based border routers.

802.15.4 USB  Implement a device that exposes an IEEE 802.15.4 radio over USB.

group ieee802154
IEEE 802.15.4 native and OpenThread L2, configuration, management and driver APIs.

The IEEE 802.15.4 and Thread subsystems comprise the OpenThread L2 subsystem, the native IEEE 802.15.4 L2 subsystem (“Soft” MAC), a mostly vendor and protocol agnostic driver API shared between the OpenThread and native L2 stacks (“Hard” MAC and PHY) as well as several APIs to configure the subsystem (shell, net management, Kconfig, devicetree, etc.).

The OpenThread subsystem API integrates the external OpenThread stack into Zephyr. It builds upon Zephyr’s native IEEE 802.15.4 driver API.

The native IEEE 802.15.4 subsystem APIs are exposed at different levels and address several audiences:

• shell (end users, application developers):
  – a set of IEEE 802.15.4 shell commands (see shell> ieee802154 help)

• application API (application developers):
  – IPv6, DGRAM and RAW sockets for actual peer-to-peer, multicast and broadcast data exchange between nodes including connection specific configuration (sample coming soon, see https://github.com/linux-wpan/wpan-tools/tree/master/examples for now which inspired our API and therefore has a similar socket API),
  – Kconfig and devicetree configuration options (net config library extension, subsystem-wide MAC and PHY Kconfig/DT options, driver/vendor specific Kconfig/DT options, watch out for options prefixed with IEEE802154/ieee802154),
  – Network Management: runtime configuration of the IEEE 802.15.4 protocols stack at the MAC (L2) and PHY (L1) levels (see IEEE 802.15.4 Net Management),

• L2 integration (subsystem contributors):
  – see IEEE 802.15.4 L2
– implementation of Zephyr’s internal L2-level socket and network context abstractions (context/socket operations, see Network L2 Abstraction Layer),
– protocol-specific extension to the interface structure (see Network Interface abstraction layer)
– protocol-specific extensions to the network packet structure (see Network Packet Library),

• OpenThread and native IEEE 802.15.4 share a common driver API (driver maintainers/contributors):
  – see IEEE 802.15.4 Drivers
  – a basic, mostly PHY-level driver API to be implemented by all drivers,
  – several “hard MAC” (hardware/firmware offloading) extension points for performance critical or timing sensitive aspects of the protocol

IEEE 802.15.4 Management API  This is the main subsystem-specific API of interest to IEEE 802.15.4 application developers as it allows to configure the IEEE 802.15.4 subsystem at runtime. Other relevant interfaces for application developers are the typical shell, socket, Kconfig and devicetree APIs that can be accessed through Zephyr’s generic subsystem-independent documentation. Look out for IEEE802154/ieee802154 prefixes there.

```
group ieee802154_mgmt
  
  IEEE 802.15.4 net management library.
  
  The IEEE 802.15.4 net management library provides runtime configuration features that applications can interface with directly.
  
  Most of these commands are also accessible via shell commands. See the shell’s help feature (shell> ieee802154 help).
```

Note: All section, table and figure references are to the IEEE 802.15.4-2020 standard.

Command Macros

IEEE 802.15.4 net management commands.

These IEEE 802.15.4 subsystem net management commands can be called by applications via Network Management macro.

All attributes and parameters are given in CPU byte order (scalars) or big endian (byte arrays) unless otherwise specified.

The following IEEE 802.15.4 MAC management service primitives are referenced in this enumeration:

• MLME-ASSOCIATE.request, see section 8.2.3
• MLME-DISASSOCIATE.request, see section 8.2.4
• MLME-SET/GET.request, see section 8.2.6
• MLME-SCAN.request, see section 8.2.11

The following IEEE 802.15.4 MAC data service primitives are referenced in this enumeration:

• MLME-DATA.request, see section 8.3.2
MAC PIB attributes (mac.../sec...): see sections 8.4.3 and 9.5. PHY PIB attributes (phy...): see section 11.3. Both are accessed through MLME-SET/GET primitives.

- **NET_REQUEST_IEEE802154_SET_ACK**
  
  Sets AckTx for all subsequent MLME-DATA (aka TX) requests.

- **NET_REQUEST_IEEE802154_UNSET_ACK**
  
  Unsets AckTx for all subsequent MLME-DATA requests.

- **NET_REQUEST_IEEE802154_PASSIVE_SCAN**
  
  MLME-SCAN(PASSIVE, ...) request.
  
  See [ieee802154_req_params](#) for associated command parameters.

- **NET_REQUEST_IEEE802154_ACTIVE_SCAN**
  
  MLME-SCAN(ACTIVE, ...) request.
  
  See [ieee802154_req_params](#) for associated command parameters.

- **NET_REQUEST_IEEE802154_CANCEL_SCAN**
  
  Cancels an ongoing MLME-SCAN(...) command (non-standard).

- **NET_REQUEST_IEEE802154_ASSOCIATE**
  
  MLME-ASSOCIATE(...) request.

- **NET_REQUEST_IEEE802154_DISASSOCIATE**
  
  MLME-DISASSOCIATE(...) request.

- **NET_REQUEST_IEEE802154_SET_CHANNEL**
  
  MLME-SET(phyCurrentChannel) request.

- **NET_REQUEST_IEEE802154_GET_CHANNEL**
  
  MLME-GET(phyCurrentChannel) request.

- **NET_REQUEST_IEEE802154_SET_PAN_ID**
  
  MLME-SET(macPanId) request.

- **NET_REQUEST_IEEE802154_GET_PAN_ID**
  
  MLME-GET(macPanId) request.

- **NET_REQUEST_IEEE802154_SET_EXT_ADDR**
  
  Sets the extended interface address (non-standard), see sections 7.1 and 8.4.3.1, in big endian byte order.

- **NET_REQUEST_IEEE802154_GET_EXT_ADDR**
  
  like MLME-GET(macExtendedAddress) but in big endian byte order

- **NET_REQUEST_IEEE802154_SET_SHORT_ADDR**
  
  MLME-SET(macShortAddress) request, only allowed for co-ordinators.
NET_REQUEST_IEEE802154_GET_SHORT_ADDR
MLME-GET(macShortAddress) request.

NET_REQUEST_IEEE802154_GET_TX_POWER
MLME-SET(phyUnicastTxPower/phyBroadcastTxPower) request (currently not distin-
guished)

NET_REQUEST_IEEE802154_SET_TX_POWER
MLME-GET(phyUnicastTxPower/phyBroadcastTxPower) request.

NET_REQUEST_IEEE802154_SET_SECURITY_SETTINGS
Configures basic sec* MAC PIB attributes, implies macSecurityEnabled=true.
See ieee802154_security_params for associated command parameters.

NET_REQUEST_IEEE802154_GET_SECURITY_SETTINGS
Gets the configured sec* attributes.
See ieee802154_security_params for associated command parameters.

Event Macros

IEEE 802.15.4 net management events.
These IEEE 802.15.4 subsystem net management events can be subscribed to by
applications via net_mgmt_init_event_callback, net_mgmt_add_event_callback and
net_mgmt_del_event_callback.

NET_EVENT_IEEE802154_SCAN_RESULT
Signals the result of the NET_REQUEST_IEEE802154_ACTIVE_SCAN or
NET_REQUEST_IEEE802154_PASSIVE_SCAN net management commands.
See ieee802154_req_params for associated event parameters.

struct ieee802154_req_params
#include <ieee802154_mgmt.h> Scanning parameters.
Used to request a scan and get results as well, see section 8.2.11.2

Public Members

uint32_t channel_set
The set of channels to scan, use above macros to manage it.

uint32_t duration
Duration of scan, per-channel, in milliseconds.

uint16_t channel
Current channel in use as a result.
uint16_t pan_id
   Current pan_id in use as a result.

union ieee802154_req_params
   Result address.

uint8_t len
   length of address

uint8_t lqi
   Link quality information, between 0 and 255.

struct ieee802154_security_params
   #include <ieee802154_mgmt.h> Security parameters.
   Used to setup the link-layer security settings, see tables 9-9 and 9-10 in section 9.5.

IEEE 802.15.4 Driver API  This is the main API of interest to IEEE 802.15.4 driver developers.

group ieee802154_driver
   IEEE 802.15.4 driver API.

   This API provides a common representation of vendor-specific hardware and firmware to
   the native IEEE 802.15.4 L2 and OpenThread stacks. Application developers should never
   interface directly with this API. It is of interest to driver maintainers only.

   The IEEE 802.15.4 driver API consists of two separate parts:
   • a basic, mostly PHY-level driver API to be implemented by all drivers,
   • several optional MAC-level extension points to offload performance critical or timing
     sensitive aspects at MAC level to the driver hardware or firmware (“hard” MAC).

   Implementing the basic driver API will ensure integration with the native L2 stack as well as
   basic support for OpenThread. Depending on the hardware, offloading to vendor-specific
   hardware or firmware features may be required to achieve full compliance with the Thread
   protocol or IEEE 802.15.4 subprotocols (e.g. fast enough ACK packages, precise timing of
   timed TX/RX in the TSCH or CSL subprotocols).

   Whether or not MAC-level offloading extension points need to be implemented is to be de-
   cided by individual driver maintainers. Upper layers SHOULD provide a “soft” MAC fall-
   back whenever possible.

   Note: All section, table and figure references are to the IEEE 802.15.4-2020 standard.

IEEE 802.15.4, section 7.4.2: MAC header information elements

eenum ieee802154_ie_type
   Information Element Types.
   See sections 7.4.2.1 and 7.4.3.1.
   Values:
enumerator IEEE802154_IE_TYPE_HEADER = 0x0
enumerator IEEE802154_IE_TYPE_PAYLOAD

enum ieee802154_header_ie_element_id
    Header Information Element IDs.
    See section 7.4.2.1, table 7-7, partial list, only IEs actually used are implemented.
    Values:

enumerator IEEE802154_HEADER_IE_ELEMENT_ID_VENDOR_SPECIFIC_IE = 0x00
enumerator IEEE802154_HEADER_IE_ELEMENT_ID_CSL_IE = 0x1a
enumerator IEEE802154_HEADER_IE_ELEMENT_ID_RIT_IE = 0x1b
enumerator IEEE802154_HEADER_IE_ELEMENT_ID_RENDEZVOUS_TIME_IE = 0x1d
enumerator IEEE802154_HEADER_IE_ELEMENT_ID_TIME_CORRECTION_IE = 0x1e
enumerator IEEE802154_HEADER_IE_ELEMENT_ID_HEADER_TERMINATION_1 = 0x7e
enumerator IEEE802154_HEADER_IE_ELEMENT_ID_HEADER_TERMINATION_2 = 0x7f

static inline int16_t ieee802154_header_ie_get_time_correction_us(struct ieee802154_header_ie_time_correction *ie)
    Retrieve the time correction value in microseconds from a Time Correction IE, see section 7.4.2.7.
    Parameters
    • ie – [in] pointer to the Time Correction IE structure
    Returns
    The time correction value in microseconds.

static inline void ieee802154_header_ie_set_element_id(struct ieee802154_header_ie *ie, uint8_t element_id)
    Set the element ID of a header IE.
    Parameters
    • ie – [in] pointer to a header IE
    • element_id – [in] IE element id in CPU byte order

static inline uint8_t ieee802154_header_ie_get_element_id(struct ieee802154_header_ie *ie)
    Get the element ID of a header IE.
    Parameters
    • ie – [in] pointer to a header IE
    Returns
    header IE element id in CPU byte order
IEEE802154_HEADER_IE_HEADER_LENGTH

The header IE's header length (2 bytes).

IEEE802154_DEFINE_HEADER_IE_VENDOR_SPECIFIC(_vendor_oui, _vendor_specific_info, _vendor_specific_info_len)

Define a vendor specific header IE, see section 7.4.2.3.
Example usage (all parameters in little endian):

```c
uint8_t vendor_specific_info[] = {...some vendor specific IE content...};
struct ieee802154_header_ie header_ie = IEEE802154_DEFINE_HEADER_IE_VENDOR_SPECIFIC(
    {0x9b, 0xb8, 0xea}, vendor_specific_info, sizeof(vendor_specific_info));
```

Parameters

- _vendor_oui – an initializer for a 3 byte vendor oui array in little endian
- _vendor_specific_info – pointer to a variable length uint8_t array with the vendor specific IE content
- _vendor_specific_info_len – the length of the vendor specific IE content (in bytes)

IEEE802154_DEFINE_HEADER_IE_CSL_REDUCED(_csl_phase, _csl_period)

Define a reduced CSL IE, see section 7.4.2.3.
Example usage (all parameters in CPU byte order):

```c
uint16_t csl_phase = ...;
uint16_t csl_period = ...;
struct ieee802154_header_ie header_ie = IEEE802154_DEFINE_HEADER_IE_CSL_REDUCED(csl_phase, csl_period);
```

Parameters

- _csl_phase – CSL phase in CPU byte order
- _csl_period – CSL period in CPU byte order

IEEE802154_DEFINE_HEADER_IE_CSL_FULL(_csl_phase, _csl_period, _csl_rendezvous_time)

Define a full CSL IE, see section 7.4.2.3.
Example usage (all parameters in CPU byte order):

```c
uint16_t csl_phase = ...;
uint16_t csl_period = ...;
uint16_t csl_rendezvous_time = ...;
struct ieee802154_header_ie header_ie = IEEE802154_DEFINE_HEADER_IE_CSL_REDUCED(csl_phase, csl_period, csl_rendezvous_time);
```

Parameters

- _csl_phase – CSL phase in CPU byte order
- _csl_period – CSL period in CPU byte order
- _csl_rendezvous_time – CSL rendezvous time in CPU byte order
IEEE802154_DEFINE_HEADER_IE_TIME_CORRECTION(_ack, _time_correction_us)

Define a Time Correction IE, see section 7.4.2.7.

Example usage (parameter in CPU byte order):

```c
uint16_t time_sync_info = ...;
structieee802154_header_ie header_ie =
IEEE802154_DEFINE_HEADER_IE_TIME_CORRECTION(true, time_sync_info);
```

Parameters

- _ack – whether or not the enhanced ACK frame that receives this IE is an
  ACK (true) or NACK (false)
- _time_correction_us – the positive or negative deviation from expected
  RX time in microseconds

IEEE802154_TIME_CORRECTION_HEADER_IE_LEN

The length in bytes of a “Time Correction” header IE.

IEEE802154_HEADER_TERMINATION_1_HEADER_IE_LEN

The length in bytes of a “Header Termination 1” header IE.

IEEE 802.15.4-2020, Section 10: General PHY requirements

enum ieee802154_phy_channel_page

PHY channel pages, see section 10.1.3.

A device driver must support the mandatory channel pages, frequency bands and
channels of at least one IEEE 802.15.4 PHY.

Channel page and number assignments have developed over several versions of the
standard and are not particularly well documented. Therefore some notes about pe-
culiarities of channel pages and channel numbering:

- The 2006 version of the standard had a read-only phyChannelsSupported PHY PIB
  attribute that represented channel page/number combinations as a bitmap. This
  attribute was removed in later versions of the standard as the number of channels
  increased beyond what could be represented by a bit map. That's the reason why
  it was decided to represent supported channels as a combination of channel pages
  and ranges instead.

- In the 2020 version of the standard, 13 channel pages are explicitly defined, but
  up to 32 pages could in principle be supported. This was a hard requirement in
  the 2006 standard. In later standards it is implicit from field specifications, e.g. the
  MAC PIB attribute macChannelPage (section 8.4.3.4, table 8-100) or channel page
  fields used in the SRM protocol (see section 8.2.26.5).

- ASK PHY (channel page one) was deprecated in the 2015 version of the standard.
  The 2020 version of the standard is a bit ambivalent whether channel page one
  disappeared as well or should be interpreted as O-QPSK now (see section 10.1.3.3).
  In Zephyr this ambivalence is resolved by deprecating channel page one.

- For some PHYS the standard doesn’t clearly specify a channel page, namely the
  GFSK, RS-GFSK, CMB and TASK PHYS. These are all rather new and left out in our
  list as long as no driver wants to implement them.
Warning: The bit numbers are not arbitrary but represent the channel page numbers as defined by the standard. Therefore do not change the bit numbering.

Values:

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_ZERO_OQPSK_2450_BPSK_868_915 = BIT(0)
  Channel page zero supports the 2.4G channels of the O-QPSK PHY and all channels from the BPSK PHYs initially defined in the 2003 editions of the standard.
  For channel page zero, 16 channels are available in the 2450 MHz band (channels 11-26, O-QPSK), 10 in the 915 MHz band (channels 1-10, BPSK), and 1 in the 868 MHz band (channel 0, BPSK).
  You can retrieve the channels supported by a specific driver on this page via IEEE802154_ATTR_PHY_SUPPORTED_CHANNEL_RANGES attribute.
  see section 10.1.3.3

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_ONE_DEPRECATED = BIT(1)
  Formerly ASK PHY - deprecated in IEEE 802.15.4-2015.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_TWO_OQPSK_868_915 = BIT(2)
  O-QPSK PHY - 868 MHz and 915 MHz bands, see section 10.1.3.3.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_THREE_CSS = BIT(3)
  CSS PHY - 2450 MHz band, see section 10.1.3.4.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_FOUR_HRP_UWB = BIT(4)
  UWB PHY - SubG, low and high bands, see section 10.1.3.5.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_FIVE_OQPSK_780 = BIT(5)
  O-QPSK PHY - 780 MHz band, see section 10.1.3.2.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_SIX_RESERVED = BIT(6)
  reserved - not currently assigned

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_SEVEN_MSK = BIT(7)
  MSK PHY - 780 MHz and 2450 MHz bands, see sections 10.1.3.6, 10.1.3.7.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_EIGHT_LRP_UWB = BIT(8)
  LRP UWB PHY, see sections 10.1.3.8.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_NINE_SUN_PREDEFINED = BIT(9)
  SUN FSK/OFDM/O-QPSK PHYs - predefined bands, operating modes and channels, see sections 10.1.3.9.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_TEN_SUN_FSK_GENERIC = BIT(10)
  SUN FSK/OFDM/O-QPSK PHYs - generic modulation and channel description, see sections 10.1.3.9, 7.4.4.11.
enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_ELEVEN_OQPSK_2380 = BIT(11)
O-QPSK PHY - 2380 MHz band, see section 10.1.3.10.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_TWELVE_LECIM = BIT(12)
LECIM DSSS/FSK PHYs, see section 10.1.3.11.

enumerator IEEE802154_ATTR_PHY_CHANNEL_PAGE_THIRTEEN_RCC = BIT(13)
RCC PHY, see section 10.1.3.12.

IEEE802154_DEFINE_PHY_SUPPORTED_CHANNELS(drv_attr, from, to)
Allocate memory for the supported channels driver attribute with a single channel range constant across all driver instances.
This is what most IEEE 802.15.4 drivers need.
Example usage:

IEEE802154_DEFINE_PHY_SUPPORTED_CHANNELS(drv_attr, 11, 26);

The attribute may then be referenced like this:

... &drv_attr.phy_supported_channels ...

See ieee802154_attr_get_channel_page_and_range() for a further shortcut that can be combined with this macro.

Parameters

- drv_attr – name of the local static variable to be declared for the local attributes structure
- from – the first channel to be supported
- to – the last channel to be supported

IEEE 802.15.4-2020, Section 15: HRP UWB PHY

For HRP UWB the symbol period is derived from the preamble symbol period (T_psym), see section 11.3, table 11-1 and section 15.2.5, table 15-4 (confirmed in IEEE 802.15.4z, section 15.1). Choosing among those periods cannot be done based on channel page and channel alone. The mean pulse repetition frequency must also be known, see the ‘UwbPrf’ parameter of the MCPS-DATA.request primitive (section 8.3.2, table 8-88) and the preamble parameters for HRP-ERDEV length 91 codes (IEEE 802.15.4z, section 15.2.6.2, table 15-7b).

enum ieee802154_phy_hrp_uwb_nominal_prf

represents the nominal pulse rate frequency of an HRP UWB PHY

Values:

eenumerator IEEE802154_PHY_HRP_UWB_PRF_OFF = 0
standard modes, see section 8.3.2, table 8-88.

eenumerator IEEE802154_PHY_HRP_UWB_NOMINAL_4_M = BIT(0)

enumerator IEEE802154_PHY_HRP_UWB_NOMINAL_16_M = BIT(1)
enumerator IEEE802154_PHY_HRP_UWB_NOMINAL_64_M = BIT(2)

enumerator IEEE802154_PHY_HRP_UWB_NOMINAL_64_M_BPRF = BIT(3)
    enhanced ranging device (ERDEV) modes not specified in table 8-88, see IEEE 802.15.4z, section 15.1, section 15.2.6.2, table 15-7b, section 15.3.4.2 and section 15.3.4.3.

enumerator IEEE802154_PHY_HRP_UWB_NOMINAL_128_M_HPRF = BIT(4)

enumerator IEEE802154_PHY_HRP_UWB_NOMINAL_256_M_HPRF = BIT(5)

IEEE802154_PHY_HRP_UWB_PRF4_TPSYM_SYMBOL_PERIOD_NS
    Nominal PRF 4MHz symbol period.

IEEE802154_PHY_HRP_UWB_PRF16_TPSYM_SYMBOL_PERIOD_NS
    Nominal PRF 16MHz symbol period.

IEEE802154_PHY_HRP_UWB_PRF64_TPSYM_SYMBOL_PERIOD_NS
    Nominal PRF 64MHz symbol period.

IEEE802154_PHY_HRP_UWB_ERDEV_TPSYM_SYMBOL_PERIOD_NS
    ERDEV symbol period.

IEEE802154_PHY_HRP_UWB_RDEV
    RDEV device mask.

IEEE802154_PHY_HRP_UWB_ERDEV
    ERDEV device mask.

IEEE 802.15.4 Driver API

enum iee802154_hw_caps
    IEEE 802.15.4 driver capabilities.
    Any driver properties that can be represented in binary form should be modeled as capabilities. These are called “hardware” capabilities for historical reasons but may also represent driver firmware capabilities (e.g. MAC offloading features).
    Values:

enumerator IEEE802154_HW_ENERGY_SCAN = BIT(0)
    Energy detection (ED) supported (optional)

enumerator IEEE802154_HW_FCS = BIT(1)
    Frame checksum verification supported.

enumerator IEEE802154_HW_FILTER = BIT(2)
    Filtering of PAN ID, extended and short address supported.
enumerator IEEE802154_HW_PROMISC = BIT(3)
   Promiscuous mode supported.

enumerator IEEE802154_HW_CSMA = BIT(4)
   CSMA-CA procedure supported on TX.

enumerator IEEE802154_HW_TX_RX_ACK = BIT(5)
   Waits for ACK on TX if AR bit is set in TX pkt.

enumerator IEEE802154_HW_RETRANSMISSION = BIT(6)
   Supports retransmission on TX ACK timeout.

enumerator IEEE802154_HW_RX_TX_ACK = BIT(7)
   Sends ACK on RX if AR bit is set in RX pkt.

enumerator IEEE802154_HW_TXTIME = BIT(8)
   TX at specified time supported.

enumerator IEEE802154_HW_SLEEP_TO_TX = BIT(9)
   TX directly from sleep supported.

@note This HW capability does not conform to the requirements
specified in #61227 as it closely couples the driver to OpenThread's
capability and device model which is different from Zephyr's:
- "Sleeping" is a well defined term in Zephyr related to internal
  power and thread management and different from "RX off" as
  defined in OT.
- Currently all OT-capable drivers have the "sleep to TX" capability
  anyway plus we expect future drivers to implement it ootb as well,
  so no information is actually conveyed by this capability.
- The `start()`/`stop()` API of a net device controls the
  interface's operational state. Drivers MUST respond with
  -ENETDOWN when calling `tx()` while their operational state is
  "DOWN", only devices in the "UP" state MAY transmit packets (RFC
  2863).
- A migration path has been defined in #63670 for actual removal of
  this capability in favor of a standard compliant
  `configure(rx_on/rx_off)` call, see there for details.

@deprecated Drivers and L2 SHALL not introduce additional references
to this capability and remove existing ones as outlined in #63670.

enumerator IEEE802154_HW_RXTIME = BIT(10)
   Timed RX window scheduling supported.

enumerator IEEE802154_HW_TXSEC = BIT(11)
   TX security supported (key management, encryption and authentication)

enumerator IEEE802154_RX_ON_WHEN_IDLE = BIT(12)
   RxOnWhenIdle handling supported.

enum ieee802154_filter_type
Filter type, see ieee802154_radio_api::filter.

**Values:**

- enumerator IEEE802154_FILTER_TYPE_IEEE_ADDR
- enumerator IEEE802154_FILTER_TYPE_SHORT_ADDR
- enumerator IEEE802154_FILTER_TYPE_PAN_ID
- enumerator IEEE802154_FILTER_TYPE_SRC_IEEE_ADDR
- enumerator IEEE802154_FILTER_TYPE_SRC_SHORT_ADDR

```c
enum ieee802154_event
```

Driver events, see IEEE802154_CONFIG_EVENT_HANDLER.

**Values:**

- enumerator IEEE802154_EVENT_TX_STARTED
  - Data transmission started.
- enumerator IEEE802154_EVENT_RX_FAILED
  - Data reception failed.
- enumerator IEEE802154_EVENT_RX_OFF
  - An RX slot ended, requires IEEE802154_HW_RXTIME.

**Note:** This event SHALL not be triggered by drivers when RX is synchronously
switched off due to a call to stop() or an RX slot being configured.

```c
enum ieee802154_rx_fail_reason
```

RX failed event reasons, see IEEE802154_EVENT_RX_FAILED.

**Values:**

- enumerator IEEE802154_RX_FAIL_NOT_RECEIVED
  - Nothing received.
- enumerator IEEE802154_RX_FAIL_INVALID_FCS
  - Frame had invalid checksum.
- enumerator IEEE802154_RX_FAIL_ADDR_FILTERED
  - Address did not match.
- enumerator IEEE802154_RX_FAIL_OTHER
  - General reason.
enum ieee802154_tx_mode
IEEE 802.15.4 Transmission mode.

Values:

enumerator IEEE802154_TX_MODE_DIRECT
Transmit packet immediately, no CCA.

enumerator IEEE802154_TX_MODE_CCA
Perform CCA before packet transmission.

enumerator IEEE802154_TX_MODE_CSMA_CA
Perform full CSMA/CA procedure before packet transmission.

Note: requires IEEE802154_HW_CSMA capability.

enumerator IEEE802154_TX_MODE_TXTIME
Transmit packet in the future, at the specified time, no CCA.

Note: requires IEEE802154_HW_TXTIME capability.

enumerator IEEE802154_TX_MODE_TXTIME_CCA
Transmit packet in the future, perform CCA before transmission.

Note: requires IEEE802154_HW_TXTIME capability.

Note: Required for Thread 1.2 Coordinated Sampled Listening feature (see Thread specification 1.2.0, ch. 3.2.6.3).

enumerator IEEE802154_TX_MODE_COMMON_COUNT
Number of modes defined in ieee802154_tx_mode.

enumerator IEEE802154_TX_MODE_PRIV_START = IEEE802154_TX_MODE_COMMON_COUNT
This and higher values are specific to the protocol- or driver-specific extensions.

enum ieee802154_fpb_mode
IEEE 802.15.4 Frame Pending Bit table address matching mode.

Values:

enumerator IEEE802154_FPB_ADDR_MATCH_THREAD
The pending bit shall be set only for addresses found in the list.

enumerator IEEE802154_FPB_ADDR_MATCH_ZIGBEE
The pending bit shall be cleared for short addresses found in the list.
enum ieee802154_config_type
IEEE 802.15.4 driver configuration types.

Values:

enumerator IEEE802154_CONFIG_AUTO_ACK_FPB
Indicates how the driver should set the Frame Pending bit in ACK responses for Data Requests.
If enabled, the driver should determine whether to set the bit or not based on the information provided with IEEE802154_CONFIG_ACK_FPB config and FPB address matching mode specified. Otherwise, Frame Pending bit should be set to 1 (see section 6.7.3).

Note: requires IEEE802154_HW_TX_RX_ACK capability and is available in any interface operational state.

enumerator IEEE802154_CONFIG_ACK_FPB
Indicates whether to set ACK Frame Pending bit for specific address or not.
Disabling the Frame Pending bit with no address provided (NULL pointer) should disable it for all enabled addresses.

Note: requires IEEE802154_HW_TX_RX_ACK capability and is available in any interface operational state.

enumerator IEEE802154_CONFIG_PAN_COORDINATOR
Indicates whether the device is a PAN coordinator.
This influences packet filtering.

Note: Available in any interface operational state.

enumerator IEEE802154_CONFIG_PROMISCUOUS
Enable/disable promiscuous mode.

Note: Available in any interface operational state.

enumerator IEEE802154_CONFIG_EVENT_HANDLER
Specifies new IEEE 802.15.4 driver event handler.
Specifying NULL as a handler will disable events notification.

Note: Available in any interface operational state.

enumerator IEEE802154_CONFIG_MAC_KEYS
Updates MAC keys, key index and the per-key frame counter for drivers supporting transmit security offloading, see section 9.5, tables 9-9 and 9-10.
The key configuration SHALL NOT be accepted if the frame counter (in case frame counter per key is true) is not strictly larger than the current frame counter associated with the same key, see sections 8.2.2, 9.2.4 g/h) and 9.4.3.

**Note:** Requires `IEEE802154_HW_TX_SEC` capability and is available in any interface operational state.

enumerator `IEEE802154_CONFIG_FRAME_COUNTER`

Sets the current MAC frame counter value associated with the interface for drivers supporting transmit security offloading, see section 9.5, table 9-8, secFrameCounter.

**Note:** Requires `IEEE802154_HW_TX_SEC` capability and is available in any interface operational state.

**Warning:** The frame counter MUST NOT be accepted if it is not strictly greater than the current frame counter associated with the interface, see sections 8.2.2, 9.2.4 g/h) and 9.4.3. Otherwise the replay protection provided by the frame counter may be compromised. Drivers SHALL return -EINVAL in case the configured frame counter does not conform to this requirement.

enumerator `IEEE802154_CONFIG_FRAME_COUNTER_IF_LARGER`

Sets the current MAC frame counter value if the provided value is greater than the current one.

**Note:** Requires `IEEE802154_HW_TX_SEC` capability and is available in any interface operational state.

**Warning:** This configuration option does not conform to the requirements specified in #61227 as it is redundant with `IEEE802154_CONFIG_FRAME_COUNTER`, and will therefore be deprecated in the future.

enumerator `IEEE802154_CONFIG_RX_SLOT`

Set or unset a radio reception window (RX slot).

This can be used for any scheduled reception, e.g.: Zigbee GP device, CSL, TSCH, etc.

The start and duration parameters of the RX slot are relative to the network subsystem's local clock. If the start parameter of the RX slot is -1 then any previously configured RX slot SHALL be canceled immediately. If the start parameter is any value in the past (including 0) or the duration parameter is zero then the receiver SHALL remain off forever until the RX slot has either been removed or re-configured to point to a future start time. If an RX slot is configured while the previous RX slot is still scheduled, then the previous slot SHALL be cancelled and the new slot scheduled instead.

RX slots MAY be programmed while the driver is “DOWN”. If any past or future RX slot is configured when calling `start()` then the interface SHALL be placed in “UP” state.
state but the receiver SHALL not be started.

The driver SHALL take care to start/stop the receiver autonomously, asynchronously and automatically around the RX slot. The driver SHALL resume power just before the RX slot and suspend it again after the slot unless another programmed event forces the driver not to suspend. The driver SHALL switch to the programmed channel before the RX slot and back to the channel set with set_channel() after the RX slot. If the driver interface is “DOWN” when the start time of an RX slot arrives, then the RX slot SHALL not be observed and the receiver SHALL remain off.

If the driver is “UP” while configuring an RX slot, the driver SHALL turn off the receiver immediately and (possibly asynchronously) put the driver into the lowest possible power saving mode until the start of the RX slot. If the driver is “UP” while the RX slot is deleted, then the driver SHALL enable the receiver immediately. The receiver MUST be ready to receive packets before returning from the configure() operation in this case.

This behavior means that setting an RX slot implicitly sets the MAC PIB attribute macRxOnWhenIdle (see section 8.4.3.1, table 8-94) to “false” while deleting the RX slot implicitly sets macRxOnWhenIdle to “true”.

**Note:** requires \textit{IEEE802154_HW_RXTIME} capability and is available in any interface operational state.

**Note:** Required for Thread 1.2 Coordinated Sampled Listening feature (see Thread specification 1.2.0, ch. 3.2.6.3).

enumerator \textit{IEEE802154_CONFIG_CSL_PERIOD}

Enables or disables a device as a CSL receiver and configures its CSL period.

Configures the CSL period in units of 10 symbol periods. Values greater than zero enable CSL if the driver supports it and the device starts to operate as a CSL receiver. Setting this to zero disables CSL on the device. If the driver does not support CSL, the configuration call SHALL return -ENOTSUP.

See section 7.4.2.3 and section 8.4.3.6, table 8-104, macCslPeriod.

To offload CSL receiver timing to the driver the upper layer SHALL combine several configuration options in the following way:

i. Use \textit{IEEE802154_CONFIG_ENH_ACK_HEADER_IE} once with an appropriate pre-filled CSL IE and the CSL phase set to an arbitrary value or left uninitialized. The CSL phase SHALL be injected on-the-fly by the driver at runtime as outlined in 2. below. Adding a short and extended address will inform the driver of the specific CSL receiver to which it SHALL inject CSL IEs. If no addresses are given then the CSL IE will be injected into all enhanced ACK frames as soon as CSL is enabled. This configuration SHALL be done before enabling CSL by setting a CSL period greater than zero.

ii. Configure \textit{IEEE802154_CONFIG_EXPECTED_RX_TIME} immediately followed by \textit{IEEE802154_CONFIG_CSL_PERIOD}. To prevent race conditions, the upper layer SHALL ensure that the receiver is not enabled during or between the two calls (e.g. by a previously configured RX slot) nor SHALL a frame be transmitted concurrently.
The expected RX time SHALL point to the end of SFD of an ideally timed RX frame in an arbitrary past or future CSL channel sample, i.e. whose “end of SFD” arrives exactly at the locally predicted time inside the CSL channel sample.

The driver SHALL derive CSL anchor points and the CSL phase from the given expected RX time as follows:

\[
\text{cslAnchorPointNs} = \text{last expected RX time} + \text{PHY-specific PHR duration in ns}
\]

\[
\text{startOfMhrNs} = \text{start of MHR of the frame containing the CSL IE relative to the local network clock}
\]

\[
\text{cslPhase} = (\text{startOfMhrNs} - \text{cslAnchorPointNs}) / (10 \times \text{PHY specific symbol period in ns}) \mod \text{cslPeriod}
\]

The driver SHALL set the CSL phase in the IE configured in 1. and inject that IE on-the-fly into outgoing enhanced ACK frames if the destination address conforms to the IE’s address filter.

iii. Use IEEE802154_CONFIG_RX_SLOT periodically to schedule each CSL channel sample early enough before its start time. The size of the CSL channel sample SHALL take relative clock drift and scheduling uncertainties with respect to CSL transmitters into account as specified by the standard such that at least the full SHR of a legitimate RX frame is guaranteed to land inside the channel sample.

To this avail, the last configured expected RX time plus an integer number of CSL periods SHALL point to a fixed offset of the RX slot (not necessarily its center):

\[
\text{expectedRxTimeNs}_N = \text{last expected RX time} + N \times (\text{cslPeriod} \times 10 \times \text{PHY-specific symbol period in ns})
\]

\[
\text{expectedRxTimeNs}_N - \text{rxSlot}_N.\text{start} = \text{const for all } N
\]

While the configured CSL period is greater than zero, drivers SHOULD validate the offset of the expected RX time inside each RX slot accordingly. If the driver finds that the offset varies from slot to slot, drivers SHOULD log the difference but SHALL nevertheless accept and schedule the RX slot with a zero success value to work around minor implementation or rounding errors in upper layers.

Configure and start a CSL receiver:

Configure and start a CSL receiver:

Configure and start a CSL receiver:

Disable CSL on the receiver:

(continues on next page)
Update the CSL period to a new value:

```
| v
| ---------------------
| | 
| v | v
v v v
```

Note:
Confusingly the standard calls the CSL receiver “CSL coordinator” (i.e. “coordinating the CSL protocol timing”, see section 6.12.2.2), although, typically, a CSL coordinator is NOT also an IEEE 802.15.4 FFD coordinator or PAN coodinator but a simple RFD end device (compare the device roles outlined in sections 5.1, 5.3, 5.5 and 6.1). To avoid confusion we therefore prefer calling CSL coordinators (typically an RFD end device) “CSL receivers” and CSL peer devices (typically FFD coordinators or PAN coordinators) “CSL transmitters”. Also note that at this time, we do NOT support unsynchronized transmission with CSL wake up frames as specified in section 6.12.2.4.4.

Note:  Available in any interface operational state.

Note:  Required for Thread 1.2 Coordinated Sampled Listening feature (see Thread specification 1.2.0, ch. 3.2.6.3).

**enumerator** IEEE802154_CONFIGEXPECTED_RX_TIME

Configure a timepoint at which an RX frame is expected to arrive.

Configure the nanosecond resolution timepoint relative to the network subsystem's local clock at which an RX frame's end of SFD (i.e. equivalently its end of SHR, start of PHR, or in the case of PHYs with RDEV or ERDEV capability the RMARKER) is expected to arrive at the local antenna assuming perfectly synchronized local and remote network clocks and zero distance between antennas.

This parameter MAY be used to offload parts of timing sensitive TDMA (e.g. TSCH, beacon-enabled PAN including DSME), low-energy (e.g. CSL, RIT) or ranging (TDoA) protocols to the driver. In these protocols, medium access is tightly controlled such that the expected arrival time of a frame can be predicted within a well-defined time window. This feature will typically be combined with IEEE802154_CONFIG_RX SLOT although this is not a hard requirement.

The “expected RX time” MAY be interpreted slightly differently depending on the protocol context:

- CSL phase (i.e. time to the next expected CSL transmission) or anchor time (i.e. any arbitrary timepoint with “zero CSL phase”) SHALL be derived by adding the PHY header duration to the expected RX time to calculate the “start of MHR”
(“first symbol of MAC”, see section 6.12.2.1) required by the CSL protocol, compare IEEE802154_CONFIG_CSL_PERIOD.

- In TSCH the expected RX time MAY be set to macTsRxOffset + macTsRxWait / 2. Then the time correction SHALL be calculated as the expected RX time minus actual arrival timestamp, see section 6.5.4.3.
- In ranging applications, time difference of arrival (TDOA) MAY be calculated inside the driver comparing actual RMARKER timestamps against the assumed synchronized time at which the ranging frame was sent, see IEEE 802.15.4z. In case of periodic protocols (e.g. CSL channel samples, periodic beacons of a single PAN, periodic ranging “blinks”), a single timestamp at any time in the past or in the future may be given from which other expected timestamps can be derived by adding or subtracting multiples of the RX period. See e.g. the CSL documentation in this API.

Additionally this parameter MAY be used by drivers to discipline their local representation of a distributed network clock by deriving synchronization instants related to a remote representation of the same clock (as in PTP).

**Note:** Available in any interface operational state.

**Note:** Required for Thread 1.2 Coordinated Sampled Listening feature (see Thread specification 1.2.0, ch. 3.2.6.3).

**enumerator** IEEE802154_CONFIG_ENH_ACK_HEADER_IE

Adds a header information element (IE) to be injected into enhanced ACK frames generated by the driver if the given destination address filter matches.

Drivers implementing the IEEE802154_HW_RX_TX_ACK capability generate ACK frames autonomously. Setting this configuration will ask the driver to inject the given preconfigured header IE when generating enhanced ACK frames where appropriate by the standard. IEs for all other frame types SHALL be provided by L2.

The driver shall return -ENOTSUP in the following cases:
- It does not support the IEEE802154_HW_RX_TX_ACK,
- It does not support header IE injection,
- It cannot inject the runtime fields on-the-fly required for the given IE element ID (see list below).

Enhanced ACK header IEs (element IDs in parentheses) that either need to be rejected or explicitly supported and parsed by the driver because they require on-the-fly timing information injection are:
- CSL IE (0x1a)
- Rendezvous Time IE (0x1d)
- Time Correction IE (0x1e)

Drivers accepting this configuration option SHALL check the list of configured IEs for each outgoing enhanced ACK frame, select the ones appropriate for the received frame based on their element ID, inject any required runtime information on-the-fly and include the selected IEs into the enhanced ACK frame's MAC header.

Drivers supporting enhanced ACK header IE injection SHALL autonomously inject header termination IEs as required by the standard.

A destination short address and extended address MAY be given by L2 to filter the devices to which the given IE is included. Setting the short address to the broadcast address and the extended address to NULL will inject the given IE into all ACK frames unless a more specific filter is also present for any given destination device
(fallback configuration). L2 SHALL take care to either set both address fields to valid device addresses or none.

This configuration type may be called several times with distinct element IDs and/or addresses. The driver SHALL either store all configured IE/address combinations or return -ENOMEM if no additional configuration can be stored.

Configuring a header IE with a previously configured element ID and address filter SHALL override the previous configuration. This implies that repetition of the same header IE/address combination is NOT supported.

Configuring an existing element ID/address filter combination with the header IE's length field set to zero SHALL remove that configuration. SHALL remove the fallback configuration if no address is given.

Configuring a header IE for an address filter with the header IE pointer set to NULL SHALL remove all header IE's for that address filter. SHALL remove ALL header IE configuration (including but not limited to fallbacks) if no address is given.

If any of the deleted configurations didn’t previously exist, then the call SHALL be ignored. Whenever the length field is set to zero, the content fields MUST NOT be accessed by the driver.

L2 SHALL minimize the space required to keep IE configuration inside the driver by consolidating address filters and by removing configuration that is no longer required.

**Note:** requires IEEE802154_HW_RX_TX_ACK capability and is available in any interface operational state. Currently we only support header IEs but that may change in the future.

**Note:** Required for Thread 1.2 Coordinated Sampled Listening feature (see Thread specification 1.2.0, ch. 3.2.6.3).

**Note:** Required for Thread 1.2 Link Metrics feature (see Thread specification 1.2.0, ch. 4.11.3.3).

enumerator IEEE802154_CONFIG_RX_ON_WHEN_IDLE

Enable/disable RxOnWhenIdle MAC PIB attribute (Table 8-94).

Since there is no clear guidance in IEEE 802.15.4 specification about the definition of an “idle period”, this implementation expects that drivers use the RxOnWhenIdle attribute to determine next radio state (false -> off, true -> receive) in the following scenarios:

- Finalization of a regular frame reception task, provided that:
  - The frame is received without errors and passes the filtering and it's not an spurious ACK.
  - ACK is not requested or transmission of ACK is not possible due to internal conditions.
- Finalization of a frame transmission or transmission of an ACK frame, when ACK is not requested in the transmitted frame.
- Finalization of the reception operation of a requested ACK due to:
  - ACK timeout expiration.
  - Reception of an invalid ACK or not an ACK frame.
  - Reception of the proper ACK, unless the transmitted frame was a Data Request Command and the frame pending bit on the received ACK is set to true.
In this case the radio platform implementation SHOULD keep the receiver on until a determined timeout which triggers an idle period start.

- Finalization of a stand alone CCA task.
- Finalization of a CCA operation with busy result during CSMA/CA procedure.
- Finalization of an Energy Detection task.
- Finalization of a scheduled radio reception window (see `IEEE802154_CONFIG_RX_SLOT`).

enumerator `IEEE802154_CONFIG_COMMON_COUNT`  
Number of types defined in ieee802154_config_type.

enumerator `IEEE802154_CONFIG_PRIV_START = IEEE802154_CONFIG_COMMON_COUNT`  
This and higher values are specific to the protocol- or driver-specific extensions.

enum `ieee802154_attr`  
IEEE 80.15.4 driver attributes.

See `ieee802154_attr_value` and `ieee802154_radio_api` for usage details.

Values:

enumerator `IEEE802154_ATTR_PHY_SUPPORTED_CHANNEL_PAGES`  
Retrieves a bit field with supported channel pages.

This attribute SHALL be implemented by all drivers.

enumerator `IEEE802154_ATTR_PHY_SUPPORTED_CHANNEL_RANGES`  
Retrieves a pointer to the array of supported channel ranges within the currently configured channel page.

This attribute SHALL be implemented by all drivers.

enumerator `IEEE802154_ATTR_PHY_HRP_UWB_SUPPORTED_PRFS`  
Retrieves a bit field with supported HRP UWB nominal pulse repetition frequencies.

This attribute SHALL be implemented by all devices that support channel page four (HRP UWB).

enumerator `IEEE802154_ATTR_COMMON_COUNT`  
Number of attributes defined in ieee802154_attr.

enumerator `IEEE802154_ATTR_PRIV_START = IEEE802154_ATTR_COMMON_COUNT`  
This and higher values are specific to the protocol- or driver-specific extensions.

typedef void (*energy_scan_done_cb_t)(const struct `device` *dev, int16_t max_ed)  
Energy scan callback.

typedef void (*ieee802154_event_cb_t)(const struct `device` *dev, enum `ieee802154_event` evt, void *event_params)  
Driver event callback.
static inline int ieee802154_attr_get_channel_page_and_range(enum ieee802154_attr attr, const enum ieee802154_phy_channel_page phy_supported_channel_page, const struct ieee802154_phy_supported_channels *phy_supported_channels, struct ieee802154_attr_value *value)

Helper function to handle channel page and range to be called from drivers' attr_get() implementation.

This only applies to drivers with a single channel page.

**Parameters**
- **attr** – The attribute to be retrieved.
- **phy_supported_channel_page** – The driver's unique channel page.
- **phy_supported_channels** – Pointer to the structure that contains the driver's channel range or ranges.
- **value** – The pointer to the value struct provided by the user.

**Return values**
- 0 – if the attribute could be resolved
- -ENOENT – if the attribute could not be resolved

IEEE802154_HW_CAPS_BITS_COMMON_COUNT
Number of bits used by ieee802154_hw_caps type.

IEEE802154_HW_CAPS_BITS_PRIV_START
This and higher values are specific to the protocol- or driver-specific extensions.

IEEE802154_CONFIG_RX_SLOT_NONE
Configuring an RX slot with the start parameter set to this value will cancel and delete any previously configured RX slot.

IEEE802154_CONFIG_RX_SLOT_OFF
Configuring an RX slot with this start parameter while the driver is “down”, will keep RX off when the driver is being started.

Configuring an RX slot with this start value while the driver is “up” will immediately switch RX off until either the slot is deleted, see IEEE802154_CONFIG_RX_SLOT_NONE or a slot with a future start parameter is configured and that start time arrives.

IEEE 802.15.4 driver utils

static inline bool ieee802154_is_ar_flag_set(struct net_buf *frag)
Check if the AR flag is set on the frame inside the given Network Packet Library.

**Parameters**
- **frag** – A valid pointer on a net_buf structure, must not be NULL, and its length should be at least 1 byte (ImmAck frames are the shortest supported frames with 3 bytes excluding FCS).
IEEE 802.15.4 driver callbacks

enum net_verdict ieee802154_handle_ack(struct net_if *iface, struct net_pkt *pkt)

IEEE 802.15.4 driver ACK handling callback into L2 that drivers must call when receiving an ACK package.

The IEEE 802.15.4 standard prescribes generic procedures for ACK handling on L2 (MAC) level. L2 stacks therefore have to provide a fast and re-usable generic implementation of this callback for drivers to call when receiving an ACK packet.

Note: This function is part of Zephyr’s 802.15.4 stack driver -> L2 “inversion-of-control” adaptation API and must be implemented by all IEEE 802.15.4 L2 stacks.

**Warning:** Deviating from other functions in the net stack returning net_verdict, this function will not unref the package even if it returns NET_OK.

Parameters

- **iface** – A valid pointer on a network interface that received the packet
- **pkt** – A valid pointer on a packet to check

Returns

NET_OK if L2 handles the ACK package, NET_CONTINUE or NET_DROP otherwise.

void ieee802154_init(struct net_if *iface)

IEEE 802.15.4 driver initialization callback into L2 called by drivers to initialize the active L2 stack for a given interface.

Drivers must call this function as part of their own initialization routine.

Note: This function is part of Zephyr’s 802.15.4 stack driver -> L2 “inversion-of-control” adaptation API and must be implemented by all IEEE 802.15.4 L2 stacks.

Parameters

- **iface** – A valid pointer on a network interface

IEEE 802.15.4-2020, Section 6: MAC functional description

IEEE802154_PHY_SYMBOLS_PER_SECOND(symbol_period_ns)

The symbol period (and therefore symbol rate) is defined in section 6.1: “Some of the timing parameters in definition of the MAC are in units of PHY symbols.

For PHYs that have multiple symbol periods, the duration to be used for the MAC parameters is defined in that PHY clause.”

This is not necessarily the true physical symbol period, so take care to use this macro only when either the symbol period used for MAC timing is the same as the physical symbol period or if you actually mean the MAC timing symbol period.

PHY specific symbol periods are defined in PHY specific sections below.
IEEE 802.15.4-2020, Section 8: MAC services

**IEEE802154_MAC_A_BASE_SLOT_DURATION**
The number of PHY symbols forming a superframe slot when the superframe order is equal to zero, see sections 8.4.2, table 8-93, aBaseSlotDuration and section 6.2.1.

**IEEE802154_MAC_A_NUM_SUPERFRAME_SLOTS**
The number of slots contained in any superframe, see section 8.4.2, table 8-93, aNumSuperframeSlots.

**IEEE802154_MAC_A_BASE_SUPERFRAME_DURATION**
The number of PHY symbols forming a superframe when the superframe order is equal to zero, see section 8.4.2, table 8-93, aBaseSuperframeDuration.

**IEEE802154_MAC_A_UNIT_BACKOFF_PERIOD** *(turnaround_time)*
MAC PIB attribute aUnitBackoffPeriod, see section 8.4.2, table 8-93, in symbol periods, valid for all PHYs except SUN PHY in the 920 MHz band.

**IEEE802154_MAC_RESPONSE_WAIT_TIME_DEFAULT**
Default macResponseWaitTime in multiples of aBaseSuperframeDuration as defined in section 8.4.3.1, table 8-94.

IEEE 802.15.4-2020, Section 11: PHY services

**IEEE802154_PHY_A_TURNAROUND_TIME_DEFAULT**
Default PHY PIB attribute aTurnaroundTime, in PHY symbols, see section 11.3, table 11-1.

**IEEE802154_PHY_A_TURNAROUND_TIME_1MS**(symbol_periodNs)
PHY PIB attribute aTurnaroundTime for SUN, RS-GFSK, TVWS, and LECIM FSK PHY, in PHY symbols, see section 11.3, table 11-1.

**IEEE802154_PHY_A_CCA_TIME**
PHY PIB attribute aCcaTime, in PHY symbols, all PHYs except for SUN O-QPSK, see section 11.3, table 11-1.

IEEE 802.15.4-2020, Section 12: O-QPSK PHY

**IEEE802154_PHY_OQPSK_868MHZ_SYMBOL_PERIOD_NS**
O-QPSK 868Mhz band symbol period, see section 12.3.3.

**IEEE802154_PHY_OQPSK_780_TO_2450MHZ_SYMBOL_PERIOD_NS**
O-QPSK 780MHz, 915MHz, 2380MHz and 2450MHz bands symbol period, see section 12.3.3.

IEEE 802.15.4-2020, Section 13: BPSK PHY
IEEE802154_PHY_BPSK_868MHZ_SYMBOL_PERIOD_NS
BPSK 868MHz band symbol period, see section 13.3.3.

IEEE802154_PHY_BPSK_915MHZ_SYMBOL_PERIOD_NS
BPSK 915MHz band symbol period, see section 13.3.3.

IEEE 802.15.4-2020, Section 19: SUN FSK PHY

IEEE802154_PHY_SUN_FSK_863MHZ_915MHZ_SYMBOL_PERIOD_NS
SUN FSK 863Mhz and 915MHz band symbol periods, see section 19.1, table 19-1.

IEEE802154_PHY_SUN_FSK_PHR_LEN
SUN FSK PHY header length, in bytes, see section 19.2.4.

struct ieee802154_header_ie_vendor_specific
#include <ieee802154_ie.h> Vendor Specific Header IE, see section 7.4.2.3.

struct ieee802154_header_ie_csl_full
#include <ieee802154_ie.h> Full CSL IE, see section 7.4.2.3.

struct ieee802154_header_ie_csl_reduced
#include <ieee802154_ie.h> Reduced CSL IE, see section 7.4.2.3.

struct ieee802154_header_ie_csl
#include <ieee802154_ie.h> Generic CSL IE, see section 7.4.2.3.

struct ieee802154_header_ie_rit
#include <ieee802154_ie.h> RIT IE, see section 7.4.2.4.

struct ieee802154_header_ie_rendezvous_time_full
#include <ieee802154_ie.h> Full Rendezvous Time IE, see section 7.4.2.6 (macCslInterval is nonzero).

struct ieee802154_header_ie_rendezvous_time_reduced
#include <ieee802154_ie.h> Reduced Rendezvous Time IE, see section 7.4.2.6 (macCslInterval is zero).

struct ieee802154_header_ie_rendezvous_time
#include <ieee802154_ie.h> Rendezvous Time IE, see section 7.4.2.6.

struct ieee802154_header_ie_time_correction
#include <ieee802154_ie.h> Time Correction IE, see section 7.4.2.7.

struct ieee802154_header_ie
#include <ieee802154_ie.h>
struct ieee802154_phy_channel_range
   
   #include <ieee802154_radio.h> Represents a supported channel range, see ieee802154_phy_supported_channels.

struct ieee802154_phy_supported_channels
   
   #include <ieee802154_radio.h> Represents a list of channels supported by a driver for a given interface, see IEEE802154_ATTR_PHY_SUPPORTED_CHANNEL_RANGES.

Public Members

const struct ieee802154_phy_channel_range *const ranges
   Pointer to an array of channel range structures.

Warning: The pointer must be valid and constant throughout the life of the interface.

const uint8_t num_ranges
   The number of currently available channel ranges.

struct ieee802154_filter
   
   #include <ieee802154_radio.h> Filter value, see ieee802154_radio_api::filter.

Public Members

uint8_t *ieee_addr
   Extended address, in little endian.

uint16_t short_addr
   Short address, in CPU byte order.

uint16_t pan_id
   PAN ID, in CPU byte order.

struct ieee802154_key
   
   #include <ieee802154_radio.h> Key configuration for transmit security offloading, see IEEE802154_CONFIG_MAC_KEYS.

Public Members

uint8_t *key_value
   Key material.

uint32_t key_frame_counter
   Initial value of frame counter associated with the key, see section 9.4.3.
bool frame_counter_per_key
   Indicates if per-key frame counter should be used, see section 9.4.3.

uint8_t key_id_mode
   Key Identifier Mode, see section 9.4.2.3, Table 9-7.

uint8_t *key_id
   Key Identifier, see section 9.4.4.

struct ieee802154_config
#include <ieee802154_radio.h> IEEE 802.15.4 driver configuration data.

Public Members

struct ieee802154_config auto_ack_fpb
   see IEEE802154_CONFIG_AUTO_ACK_FPB

struct ieee802154_config ack_fpb
   see IEEE802154_CONFIG_ACK_FPB

bool pan_coordinator
   see IEEE802154_CONFIG_PAN_COORDINATOR

bool promiscuous
   see IEEE802154_CONFIG_PROMISCUOUS

bool rx_on_when_idle
   see IEEE802154_CONFIG_RX_ON_WHEN_IDLE

ieee802154_event_cb_t event_handler
   see IEEE802154_CONFIG_EVENT_HANDLER

struct ieee802154_key *mac_keys
   see IEEE802154_CONFIG_MAC_KEYS
   Pointer to an array containing a list of keys used for MAC encryption. Refer to secKeyIdLookupDescriptor and secKeyDescriptor in IEEE 802.15.4
   The key_value field points to a buffer containing the 16 byte key. The buffer SHALL be copied by the driver before returning from the call.
   The variable length array is terminated by key_value field set to NULL.

uint32_t frame_counter
   see IEEE802154_CONFIG_FRAME_COUNTER

net_time_t start
   Nanosecond resolution timestamp relative to the network subsystem’s local clock defining the start of the RX window during which the receiver is expected to be listening (i.e.
not including any driver startup times).

Configuring an rx_slot with the start attribute set to -1 will cancel and delete any previously active rx slot.

- **net_time_t duration**
  Nanosecond resolution duration of the RX window relative to the above RX window start time during which the receiver is expected to be listening (i.e. not including any shutdown times). Only positive values larger than or equal zero are allowed.
  Setting the duration to zero will disable the receiver, no matter what the start parameter.

- **struct ieee802154_config rx_slot**
  see IEEE802154_CONFIG_RX_SLOT

- **uint32_t csl_period**
  see IEEE802154_CONFIG_CSL_PERIOD
  in CPU byte order

- **net_time_t expected_rx_time**
  see IEEE802154_CONFIG_EXPECTED_RX_TIME

- **struct ieee802154_header_ie *header_ie**
  Pointer to the header IE, see section 7.4.2.1, figure 7-21.
  Certain header IEs may be incomplete if they require timing information to be injected at runtime on-the-fly, see the list in IEEE802154_CONFIG_ENH_ACK_HEADER_IE.

- **const uint8_t *ext_addr**
  Filters the devices that will receive this IE by extended address.
  MAY be set to NULL to configure a fallback for all devices (implies that short_addr MUST also be set to IEEE802154_BROADCAST_ADDRESS).
  in big endian

- **uint16_t short_addr**
  Filters the devices that will receive this IE by short address.
  MAY be set to IEEE802154_BROADCAST_ADDRESS to configure a fallback for all devices (implies that ext_addr MUST also set to NULL in this case).
  in CPU byte order

- **bool purge_ie**
  Flag for purging enh ACK header IEs.
  When flag is set to true, driver should remove all existing header IEs, and all other entries in config should be ignored. This means that purging current header IEs and configuring a new one in the same call is not allowed.

- **struct ieee802154_config ack_ie**
  see IEEE802154_CONFIG_ENH_ACK_HEADER_IE
union ieee802154_config
    Configuration data.

struct ieee802154_attr_value
    #include <ieee802154_radio.h> IEEE 802.15.4 driver attribute values.
    This structure is reserved to scalar and structured attributes that originate in the driver
    implementation and can neither be implemented as boolean ieee802154_hw_caps nor
    be derived directly or indirectly by the MAC (L2) layer. In particular this structure
    MUST NOT be used to return configuration data that originate from L2.

    Note: To keep this union reasonably small, any attribute requiring a large memory
    area, SHALL be provided pointing to static memory allocated by the driver and valid
    throughout the lifetime of the driver instance.

Public Members

uint32_t phy_supported_channel_pages
    A bit field that represents the supported channel pages, see
    ieee802154_phy_channel_page.

    Note: To keep the API extensible as required by the standard, supported pages
    are modeled as a bitmap to support drivers that implement runtime switching be-
    tween multiple channel pages.

    Note: Currently none of the Zephyr drivers implements more than one channel
    page at runtime, therefore only one bit will be set and the current channel page
    (see the PHY PIB attribute phyCurrentPage, section 11.3, table 11-2) is considered
    to be read-only, fixed and “well known” via the supported channel pages attribute.

const struct ieee802154_phy_supported_channels *phy_supported_channels
    Pointer to a structure representing channel ranges currently available on the se-
    lected channel page.

    The selected channel page corresponds to the phyCurrentPage PHY PIB attribute,
    see the description of phy_supported_channel_pages above. Currently it can be re-
    trieved via the IEEE802154_ATTR_PHY_SUPPORTED_CHANNEL_PAGES attribute.

    Most drivers will expose a single channel page with a single, often zero-based, fixed
    channel range.

    Some notable exceptions:
    • The legacy channel page (zero) exposes ranges in different bands and even
      PHYs that are usually not implemented by a single driver.
    • SUN and LECIM PHYs specify a large number of bands and operating modes
      on a single page with overlapping channel ranges each. Some of these ranges
      are not zero-based or contain “holes”. This explains why several ranges may
      be necessary to represent all available channels.
    • UWB PHYs often support partial channel ranges on the same channel page de-
      pending on the supported bands.
In these cases, drivers may expose custom configuration attributes (Kconfig, device-tree, runtime, ...) that allow switching between sub-ranges within the same channel page (e.g. switching between SubG and 2.4G bands on channel page zero or switching between multiple operating modes in the SUN or LECIM PHYs.

**Warning:** The pointer must be valid and constant throughout the life of the interface.

```c
uint32_t phy_hrp_uwb_supported_nominal_prfs
```

A bit field representing supported HRP UWB pulse repetition frequencies (PRF), see enum ieee802154_phy_hrp_uwb_nominal_prf.

**Note:** Currently none of the Zephyr HRP UWB drivers implements more than one nominal PRF at runtime, therefore only one bit will be set and the current PRF (UwbPrf, MCPS-DATA.request, section 8.3.2, table 8-88) is considered to be read-only, fixed and “well known” via the supported PRF attribute.

```c
struct ieee802154_radio_api
```

#include `<ieee802154_radio.h>` IEEE 802.15.4 driver interface API.

While L1-level driver features are exclusively implemented by drivers and MAY be mandatory to support certain application requirements, L2 features SHOULD be optional by default and only need to be implemented for performance optimization or precise timing as deemed necessary by driver maintainers. Fallback implementations (“Soft MAC”) SHOULD be provided in the driver-independent L2 layer for all L2/MAC features especially if these features are not implemented in vendor hardware/firmware by a majority of existing in-tree drivers. If, however, a driver offers offloading opportunities then L2 implementations SHALL delegate performance critical or resource intensive tasks to the driver.

All drivers SHALL support two externally observable interface operational states: “UP” and “DOWN”. Drivers MAY additionally support a “TESTING” interface state (see continuous_carrier()).

The following rules apply:

- An interface is considered “UP” when it is able to transmit and receive packets, “DOWN” otherwise (see precise definitions of the corresponding ifOperStatus values in RFC 2863, section 3.1.14, net_if_oper_state and the continuous_carrier() exception below). A device that has its receiver temporarily disabled during “UP” state due to an active receive window configuration is still considered “UP”.

- Upper layers will assume that the interface managed by the driver is “UP” after a call to start() returned zero or -EALREADY. Upper layers assume that the interface is “DOWN” after calling stop() returned zero or -EALREADY.

- The driver SHALL block start()/stop() calls until the interface fully transitioned to the new state (e.g. the receiver is operational, ongoing transmissions were finished, etc.). Drivers SHOULD yield the calling thread (i.e. “sleep”) if waiting for the new state without CPU interaction is possible.

- Drivers are responsible of guaranteeing atomicity of state changes. Appropriate means of synchronization SHALL be implemented (locking, atomic flags, ...).

- While the interface is “DOWN”, the driver SHALL be placed in the lowest possible power state. The driver MAY return from a call to stop() before it reaches the
lowest possible power state, i.e. manage power asynchronously. While the interface is “UP”, the driver SHOULD autonomously and asynchronously transition to lower power states whenever possible. If the driver claims to support timed RX/TX capabilities and the upper layers configure an RX slot, then the driver SHALL immediately transition (asynchronously) to the lowest possible power state until the start of the RX slot or until a scheduled packet needs to be transmitted.

• The driver SHALL NOT change the interface’s “UP”/“DOWN” state on its own. Initially, the interface SHALL be in the “DOWN” state.

• Drivers that implement the optional continuous_carrier() operation will be considered to be in the RFC 2863 “testing” ifOperStatus state if that operation returns zero. This state is active until either start() or stop() is called. If continuous_carrier() returns a non-zero value then the previous state is assumed by upper layers.

• If calls to start()/stop() return any other value than zero or -EALREADY, upper layers will consider the interface to be in a “lowerLayerDown” state as defined in RFC 2863.

• The RFC 2863 “dormant”, “unknown” and “notPresent” ifOperStatus states are currently not supported. The “lowerLevelUp” state.

• The ed_scan(), cca() and tx() operations SHALL only be supported in the “UP” state and return -ENETDOWN in any other state. See the function-level API documentation below for further details.

Note: This structure is called “radio” API for backwards compatibility. A better name would be “IEEE 802.15.4 driver API” as typical drivers will not only implement L1/radio (PHY) features but also L2 (MAC) features if the vendor-specific driver hardware or firmware offers offloading opportunities.

Note: In case of devices that support timed RX/TX, the “UP” state is not equal to “receiver enabled”. If a receive window (i.e. RX slot, see IEEE802154_CONFIG_RX_SLOT) is configured before calling start() then the receiver will not be enabled when transitioning to the “UP” state. Configuring a receive window while the interface is “UP” will cause the receiver to be disabled immediately until the configured reception time has arrived.

Public Members

struct net_if_api iface_api

network interface API

Note: Network devices must extend the network interface API. It is therefore mandatory to place it at the top of the driver API struct so that it can be cast to a network interface.

enum ieee802154_hw_caps (*get_capabilities)(const struct device *dev)

Get the device driver capabilities.

Note: Implementations SHALL be isr-ok and MUST NOT sleep. MAY be called in
any interface state once the driver is fully initialized ("ready").

**Param dev**  
pointer to IEEE 802.15.4 driver device

**Return**  
Bit field with all supported device driver capabilities.

```c
int (*cca)(const struct device *dev)
```

Clear Channel Assessment - Check channel's activity.

**Note:** Implementations SHALL be **isr-ok** and MAY **sleep**. SHALL return **-ENETDOWN** unless the interface is “UP”.

**Param dev**  
pointer to IEEE 802.15.4 driver device

**Retval 0**  
the channel is available

**Retval -EBUSY**  
The channel is busy.

**Retval -EWOULDBLOCK**  
The operation is called from ISR context but temporarily cannot be executed without blocking.

**Retval -ENETDOWN**  
The interface is not “UP”.

**Retval -ENOTSUP**  
CCA is not supported by this driver.

**Retval -EIO**  
The CCA procedure could not be executed.

```c
int (*set_channel)(const struct device *dev, uint16_t channel)
```

Set current channel.

**Note:** Implementations SHALL be **isr-ok** and MAY **sleep**. SHALL return **-EIO** unless the interface is either “UP” or “DOWN”.

**Param dev**  
pointer to IEEE 802.15.4 driver device

**Param channel**  
the number of the channel to be set in CPU byte order

**Retval 0**  
channel was successfully set

**Retval -EALREADY**  
The previous channel is the same as the requested channel.

**Retval -EINVAL**  
The given channel is not within the range of valid channels of the driver's current channel page, see the IEEE802154_ATTR_PHY_SUPPORTED_CHANNEL_RANGES driver attribute.

**Retval -EWOULDBLOCK**  
The operation is called from ISR context but temporarily cannot be executed without blocking.

**Retval -ENOTSUP**  
The given channel is within the range of valid channels of the driver's current channel page but unsupported by the current driver.
int (*filter)(const struct device *dev, bool set, enum ieee802154_filter_type type, const struct ieee802154_filter *filter)
Set/Unset PAN ID, extended or short address filters.

Note: requires IEEE802154_HW_FILTER capability.

Note: Implementations SHALL be isr-ok and MAY sleep. SHALL return -EIO unless the interface is either “UP” or “DOWN”.

Param dev
pointer to IEEE 802.15.4 driver device
Param set
true to set the filter, false to remove it
Param type
the type of entity to be added/removed from the filter list (a PAN ID or a source/destination address)
Param filter
the entity to be added/removed from the filter list
Retval 0
The filter was successfully added/removed.
Retval -EINVAL
The given filter entity or filter entity type was not valid.
Retval -EWOULDBLOCK
The operation is called from ISR context but temporarily cannot be executed without blocking.
Retval -ENOMEM
Setting/removing this filter or filter type is not supported by this driver.
Retval -EIO
Error while setting/removing the filter.

int (*set_txpower)(const struct device *dev, int16_t dbm)
Set TX power level in dbm.

Note: Implementations SHALL be isr-ok and MAY sleep. SHALL return -EIO unless the interface is either “UP” or “DOWN”.

Param dev
pointer to IEEE 802.15.4 driver device
Param dbm
TX power in dbm
Retval 0
The TX power was successfully set.
Retval -EINVAL
The given dbm value is invalid or not supported by the driver.
Retval -EWOULDBLOCK
The operation is called from ISR context but temporarily cannot be executed without blocking.
Retval -EIO
The TX power could not be set.
int (*tx)(const struct device *dev, enum ieee802154_tx_mode mode, struct net_pkt *pkt, struct net_buf *frag)

Transmit a packet fragment as a single frame.

Depending on the level of offloading features supported by the driver, the frame MAY not be fully encrypted/authenticated or it MAY not contain an FCS. It is the responsibility of L2 implementations to prepare the frame according to the offloading capabilities announced by the driver and to decide whether CCA, CSMA/CA, ACK or retransmission procedures need to be executed outside (“soft MAC”) or inside (“hard MAC”) the driver.

All frames originating from L2 SHALL have all required IEs pre-allocated and pre-filled such that the driver does not have to parse and manipulate IEs at all. This includes ACK packets if the driver does not have the IEEE802154_HW_RX_TX_ACK capability. Also see IEEE802154_CONFIG_ENH_ACK_HEADER_IE for drivers that have the IEEE802154_HW_RX_TX_ACK capability.

IEs that cannot be prepared by L2 unless the TX time is known (e.g. CSL IE, Rendezvous Time IE, Time Correction IE, ...) SHALL be sent in any of the timed TX modes with appropriate timing information pre-filled in the IE such that drivers do not have to parse and manipulate IEs at all unless the frame is generated by the driver itself.

In case any of the timed TX modes is supported and used (see ieee802154_hw_caps and ieee802154_tx_mode), the driver SHALL take responsibility of scheduling and sending the packet at the precise programmed time autonomously without further interaction by upper layers. The call to tx() will block until the package has either been sent successfully (possibly including channel acquisition and packet acknowledgment) or a terminal transmission error occurred. The driver SHALL sleep and keep power consumption to the lowest possible level until the scheduled transmission time arrives or during any other idle waiting time.

Note: Implementations MAY sleep and will usually NOT be isr-ok - especially when timed TX, CSMA/CA, retransmissions, auto-ACK or any other offloading feature is supported that implies considerable idle waiting time. SHALL return -ENETDOWN unless the interface is “UP”.

Warning: The driver SHALL NOT take ownership of the given network packet and frame (fragment) buffer. Any data required by the driver including the actual frame content must be read synchronously and copied internally if needed at a later time (e.g. the contents of IEs required for protocol configuration, states of frame counters, sequence numbers, etc). Both, the packet and the buffer MAY be re-used or released by upper layers immediately after the function returns.

Param dev
pointer to IEEE 802.15.4 driver device

Param mode
the transmission mode, some of which require specific offloading capabilities.

Param pkt
pointer to the network packet to be transmitted.

Param frag
pointer to a network buffer containing a single fragment with the frame data to be transmitted

Retval 0
The frame was successfully sent or scheduled. If the driver supports
ACK offloading and the frame requested acknowledge (AR bit set), this means that the packet was successfully acknowledged by its peer.

Retval -EINVAL
Invalid packet (e.g. an expected IE is missing or the encryption/authentication state is not as expected).

Retval -EBUSY
The frame could not be sent because the medium was busy (CSMA/CA or CCA offloading feature only).

Retval -ENOMSG
The frame was not confirmed by an ACK packet (TX ACK offloading feature only).

Retval -ENOBUFFS
The frame could not be scheduled due to missing internal resources (timed TX offloading feature only).

Retval -ENETDOWN
The interface is not “UP”.

Retval -ENOTSUP
The given TX mode is not supported.

Retval -EIO
The frame could not be sent due to some unspecified driver error (e.g. the driver being busy).

int (*start)(const struct device *dev)
Start the device.

Upper layers will assume the interface is “UP” if this operation returns with zero or -EALREADY. The interface is placed in receive mode before returning from this operation unless an RX slot has been configured (even if it lies in the past, see IEEE802154_CONFIG_RX_SLOT).

Note: Implementations SHALL be isr-ok and MAY sleep. MAY be called in any interface state once the driver is fully initialized (“ready”).

Param dev
pointer to IEEE 802.15.4 driver device

Retval 0
The driver was successfully started.

Retval -EALREADY
The driver was already “UP”.

Retval -EWOULD_BLOCK
The operation is called from ISR context but temporarily cannot be executed without blocking.

Retval -EIO
The driver could not be started.

int (*stop)(const struct device *dev)
Stop the device.

Upper layers will assume the interface is “DOWN” if this operation returns with zero or -EALREADY. The driver switches off the receiver before returning if it was previously on. The driver enters the lowest possible power mode after this operation is called. This MAY happen asynchronously (i.e. after the operation already returned control).

Note: Implementations SHALL be isr-ok and MAY sleep. MAY be called in any interface state once the driver is fully initialized (“ready”).
**Param dev**  
pointer to IEEE 802.15.4 driver device  

**Retval 0**  
The driver was successfully stopped.

**Retval -EWOULDBLOCK**  
The operation is called from ISR context but temporarily cannot be executed without blocking.

**Retval -EALREADY**  
The driver was already “DOWN”.

**Retval -EIO**  
The driver could not be stopped.

```c
int (*continuous_carrier)(const struct device *dev)
```
Start continuous carrier wave transmission.

The method blocks until the interface has started to emit a continuous carrier. To leave this mode, `start()` or `stop()` should be called, which will put the driver back into the “UP” or “DOWN” states, respectively.

**Note:** Implementations MAY sleep and will usually NOT be isr-ok. MAY be called in any interface state once the driver is fully initialized (“ready”).

**Param dev**  
pointer to IEEE 802.15.4 driver device  

**Retval 0**  
continuous carrier wave transmission started

**Retval -EALREADY**  
The driver was already in “TESTING” state and emitting a continuous carrier.

**Retval -EIO**  
not started

```c
int (*configure)(const struct device *dev, enum ieee802154_config_type type, const struct ieee802154_config *config)
```
Set or update driver configuration.

The method blocks until the interface has been reconfigured atomically with respect to ongoing package reception, transmission or any other ongoing driver operation.

**Note:** Implementations SHALL be isr-ok and MAY sleep. MAY be called in any interface state once the driver is fully initialized (“ready”). Some configuration options may not be supported in all interface operational states, see the detailed specifications in `ieee802154_config_type`. In this case the operation returns -EACCES.

**Param dev**  
pointer to IEEE 802.15.4 driver device

**Param type**  
the configuration type to be set

**Param config**  
the configuration parameters to be set for the given configuration type

**Retval 0**  
configuration successful

**Retval -EINVAL**  
The configuration parameters are invalid for the given configuration type.
Retval -ENOTSUP
The given configuration type is not supported by this driver.

Retval -EACCES
The given configuration type is supported by this driver but cannot be configured in the current interface operational state.

Retval -ENOMEM
The configuration cannot be saved due to missing memory resources.

Retval -ENOENT
The resource referenced in the configuration parameters cannot be found in the configuration.

Retval -EWOULDBLOCK
The operation is called from ISR context but temporarily cannot be executed without blocking.

Retval -EIO
An internal error occurred while trying to configure the given configuration parameter.

```c
int (*ed_scan)(const struct device *dev, uint16_t duration, energy_scan_done_cb_t done_cb)
```

Run an energy detection scan.

**Note:** requires IEEE802154_HW_ENERGY_SCAN capability

**Note:** The radio channel must be set prior to calling this function.

**Note:** Implementations SHALL be **isr-ok** and MAY **sleep**. SHALL return -ENETDOWN unless the interface is “UP”.

- **Param dev**
  pointer to IEEE 802.15.4 driver device
- **Param duration**
  duration of energy scan in ms
- **Param done_cb**
  function called when the energy scan has finished
- **Retval 0**
  the energy detection scan was successfully scheduled
- **Retval -EBUSY**
  the energy detection scan could not be scheduled at this time
- **Retval -EALREADY**
  a previous energy detection scan has not finished yet.
- **Retval -ENETDOWN**
  The interface is not “UP”.
- **Retval -ENOTSUP**
  This driver does not support energy scans.
- **Retval -EIO**
  The energy detection procedure could not be executed.

```c
net_time_t (*get_time)(const struct device *dev)
```

Get the current time in nanoseconds relative to the network subsystem’s local uptime clock as represented by this network interface.

See **net_time_t** for semantic details.
Note: requires IEEE802154_HW_TXTIME and/or IEEE802154_HW_RXTIME capabilities. Implementations SHALL be isr-ok and MUST NOT sleep. MAY be called in any interface state once the driver is fully initialized (“ready”).

**Param dev**
pointer to IEEE 802.15.4 driver device

**Return**
nanoseconds relative to the network subsystem’s local clock, -1 if an error occurred or the operation is not supported

```c
uint8_t (*get_sch_acc)(const struct device *dev)
```

Get the current estimated worst case accuracy (maximum ± deviation from the nominal frequency) of the network subsystem’s local clock used to calculate tolerances and guard times when scheduling delayed receive or transmit radio operations.

The deviation is given in units of PPM (parts per million).

Note: requires IEEE802154_HW_TXTIME and/or IEEE802154_HW_RXTIME capabilities.

**Note:** Implementations may estimate this value based on current operating conditions (e.g. temperature). Implementations SHALL be isr-ok and MUST NOT sleep. MAY be called in any interface state once the driver is fully initialized (“ready”).

**Param dev**
pointer to IEEE 802.15.4 driver device

**Return**
current estimated clock accuracy in PPM

```c
int (*attr_get)(const struct device *dev, enum ieee802154_attr attr, struct ieee802154_attr_value *value)
```

Get the value of a driver specific attribute.

Note: This function SHALL NOT return any values configurable by the MAC (L2) layer. It is reserved to non-boolean (i.e. scalar or structured) attributes that originate from the driver implementation and cannot be directly or indirectly derived by L2. Boolean attributes SHALL be implemented as ieee802154_hw_caps.

**Note:** Implementations SHALL be isr-ok and MUST NOT sleep. MAY be called in any interface state once the driver is fully initialized (“ready”).

**Retval 0**
The requested attribute is supported by the driver and the value can be retrieved from the corresponding ieee802154_attr_value member.

**Retval -ENOENT**
The driver does not provide the requested attribute. The value structure has not been updated with attribute data. The content of the value attribute is undefined.
IEEE 802.15.4 L2 / Native Stack API  This documents the IEEE 802.15.4 L2 native stack, which neither applications nor drivers will ever access directly. It is called internally by Zephyr’s upper network layers (L3+), its socket and network context abstractions. This API is therefore of interest to IEEE 802.15.4 subsystem contributors only.

**group ieee802154_l2**

IEEE 802.15.4 L2 APIs.

This API provides integration with Zephyr’s sockets and network contexts. **Application and driver developers should never interface directly with this API.** It is of interest to subsystem maintainers only.

The API implements and extends the following structures:

- implements Zephyr’s internal L2-level socket and network context abstractions (context/socket operations, see *Network L2 Abstraction Layer*),
- protocol-specific extension to the interface structure (see *Network Interface abstraction layer*)
- protocol-specific extensions to the network packet structure (see *Network Packet Library*),

**Note:** All section, table and figure references are to the IEEE 802.15.4-2020 standard.

**Defines**

IEEE802154_MAX_PHY_PACKET_SIZE

Represents the PHY constant aMaxPhyPacketSize, see section 11.3.

**Note:** Currently only 127 byte sized packets are supported although some PHYs (e.g. SUN, MSK, LECIM, …) support larger packet sizes. Needs to be changed once those PHYs should be fully supported.

IEEE802154_FCS_LENGTH

Represents the frame check sequence length, see section 7.2.1.1.

**Note:** Currently only a 2 byte FCS is supported although some PHYs (e.g. SUN, TVWS, …) optionally support a 4 byte FCS. Needs to be changed once those PHYs should be fully supported.

IEEE802154_MTU

IEEE 802.15.4 “hardware” MTU (not to be confused with L3/IP MTU), i.e. the actual payload available to the next higher layer.

This is equivalent to the IEEE 802.15.4 MAC frame length minus checksum bytes which is again equivalent to the PHY payload aka PSDU length minus checksum bytes. This definition exists for compatibility with the same concept in Linux and Zephyr’s L3. It is not a concept from the IEEE 802.15.4 standard.

6.3. Networking 2515
IEEE802154_SHORT_ADDR_LENGTH
IEEE 802.15.4 short address length.

IEEE802154_EXT_ADDR_LENGTH
IEEE 802.15.4 extended address length.

IEEE802154_MAX_ADDR_LENGTH
IEEE 802.15.4 maximum address length.

IEEE802154_NO_CHANNEL
A special channel value that symbolizes “all” channels or “any” channel - depending on context.

IEEE802154_BROADCAST_ADDRESS
Represents the IEEE 802.15.4 broadcast short address, see sections 6.1 and 8.4.3, table 8-94, macShortAddress.

IEEE802154_NO_SHORT_ADDRESS_ASSIGNED
Represents a special IEEE 802.15.4 short address that indicates that a device has been associated with a coordinator but did not receive a short address, see sections 6.4.1 and 8.4.3, table 8-94, macShortAddress.

IEEE802154_BROADCAST_PAN_ID
Represents the IEEE 802.15.4 broadcast PAN ID, see section 6.1.

IEEE802154_SHORT_ADDRESS_NOT_ASSOCIATED
Represents a special value of the macShortAddress MAC PIB attribute, while the device is not associated, see section 8.4.3, table 8-94.

IEEE802154_PAN_ID_NOT_ASSOCIATED
Represents a special value of the macPanId MAC PIB attribute, while the device is not associated, see section 8.4.3, table 8-94.

Enums

enum ieee802154_device_role

Values:

enumerator IEEE802154_DEVICE_ROLE_ENDDEVICE
enumerator IEEE802154_DEVICE_ROLE_COORDINATOR
enumerator IEEE802154_DEVICE_ROLE_PAN_COORDINATOR
struct ieee802154_security_ctx

#include <ieee802154.h> Interface-level security attributes, see section 9.5.

Public Members

uint32_t frame_counter

Interface-level outgoing frame counter, section 9.5, table 9-8, secFrameCounter.
Only used when the driver does not implement key-specific frame counters.

uint8_t key[16]

Interface-level frame encryption security key material.
Currently native L2 only supports a single secKeySource, see section 9.5, table 9-9, in combination with secKeyMode zero (implicit key mode), see section 9.4.2.3, table 9-7.

Warning: This is no longer in accordance with the 2015+ versions of the standard and needs to be extended in the future for full security procedure compliance.

uint8_t key_len

Length in bytes of the interface-level security key material.

uint8_t level

Frame security level, possible values are defined in section 9.4.2.2, table 9-6.

Warning: Currently native L2 allows to configure one common security level for all frame types, commands and information elements. This is no longer in accordance with the 2015+ versions of the standard and needs to be extended in the future for full security procedure compliance.

uint8_t key_mode

Frame security key mode.
Currently only implicit key mode is partially supported, see section 9.4.2.3, table 9-7, secKeyMode.

Warning: This is no longer in accordance with the 2015+ versions of the standard and needs to be extended in the future for full security procedure compliance.

struct ieee802154_context

#include <ieee802154.h> IEEE 802.15.4 L2 context.

Public Members
uint16_t pan_id
PAN ID.
The identifier of the PAN on which the device is operating. If this value is 0xffff, the device is not associated. See section 8.4.3.1, table 8-94, macPanId.
in CPU byte order

uint16_t channel
Channel Number.
The RF channel to use for all transmissions and receptions, see section 11.3, table 11-2, phyCurrentChannel. The allowable range of values is PHY dependent as defined in section 10.1.3.
in CPU byte order

uint16_t short_addr
Short Address (in CPU byte order)
Range:
• 0x0000–0xffff: associated, short address was assigned
• 0xfffe: associated but no short address assigned
• 0xffff: not associated (default),
See section 6.4.1, table 6-4 (Usage of the shart address) and section 8.4.3.1, table 8-94, macShortAddress.

uint8_t ext_addr[8]
Extended Address (in little endian)
The extended address is device specific, usually permanently stored on the device and immutable.
See section 8.4.3.1, table 8-94, macExtendedAddress.

struct net_linkaddr_storage linkaddr
Link layer address (in big endian)

struct ieee802154_security_ctx sec_ctx
Security context.

struct ieee802154_req_params *scan_ctx
Pointer to scanning parameters and results, guarded by scan_ctx_lock.

struct k_sem scan_ctx_lock
Used to maintain integrity of data for all fields in this struct unless otherwise documented on field level.

uint8_t coord_ext_addr[8]
Coordinator extended address.
see section 8.4.3.1, table 8-94, macCoordExtendedAddress, the address of the coordinator through which the device is associated.
A value of zero indicates that a coordinator extended address is unknown (default).
in little endian
uint16_t coord_short_addr
Coordinator short address.
see section 8.4.3.1, table 8-94, macCoordShortAddress, the short address assigned
to the coordinator through which the device is associated.
A value of 0xfffe indicates that the coordinator is only using its extended address.
A value of 0xffffff indicates that this value is unknown.
in CPU byte order

int16_t tx_power
Transmission power in dBm.

enum net_l2_flags flags
L2 flags.

uint8_t sequence
Data sequence number.
The sequence number added to the transmitted Data frame or MAC command, see
section 8.4.3.1, table 8-94, macDsn.

uint8_t device_role
Device Role.
See section 6.1: A device may be operating as end device (0), coordinator (1), or
PAN coordinator (2). If no device role is explicitly configured then the device will
be treated as an end device.
A value of 3 is undefined.
Can be read/set via ieee802154_device_role.

uint8_t ack_requested
ACK requested flag, guarded by ack_lock.

uint8_t ack_seq
ACK expected sequence number, guarded by ack_lock.

struct k_sem ack_lock
ACK lock, guards ack_* fields.

struct k_sem ctx_lock
Context lock.
This lock guards all mutable context attributes unless otherwise mentioned on at-
tribute level.

OpenThread L2 Adaptation Layer API  Zephyr’s OpenThread L2 platform adaptation layer
glues the external OpenThread stack together with Zephyr’s IEEE 802.15.4 protocol agnostic
driver API. This API is of interest to OpenThread L2 subsystem contributors only.
The OpenThread API is part of the Thread protocol subsystem and documented there.
Thread protocol

- Overview
- Internet connectivity
- Sample usage
- Thread related APIs
  - OpenThread Driver API
  - OpenThread L2 Adaptation Layer API

Overview  
Thread is a low-power mesh networking technology, designed specifically for home automation applications. It is an IPv6-based standard, which uses 6LoWPAN technology over IEEE 802.15.4 protocol. IP connectivity lets you easily connect a Thread mesh network to the internet with a Thread Border Router.

The Thread specification provides a high level of network security. Mesh networks built with Thread are secure - only authenticated devices can join the network and all communications within the mesh are encrypted. More information about Thread protocol can be found at [Thread Group website](https://www.threadgroup.org).

Zephyr integrates an open source Thread protocol implementation called OpenThread, documented on the [OpenThread website](https://openthread.io).

Internet connectivity  
A Thread Border Router is required to connect mesh network to the internet. An open source implementation of Thread Border Router is provided by the OpenThread community. See [OpenThread Border Router guide](https://openthread.io/developer/guides/border-router) for instructions on how to set up a Border Router.

Sample usage  
You can try using OpenThread with the Zephyr Echo server and Echo client samples, which provide out-of-the-box configuration for OpenThread. To enable OpenThread support in these samples, build them with `overlay-ot.conf` overlay config file. See [sockets-echo-server](https://github.com/zephyrproject-adoptium/zephyr/tree/main/samples/sockets-echo-server) and [sockets-echo-client](https://github.com/zephyrproject-adoptium/zephyr/tree/main/samples/sockets-echo-client) samples for details.

Thread related APIs

OpenThread Driver API  
OpenThread L2 uses Zephyr’s protocol agnostic IEEE 802.15.4 driver API internally. This API is of interest to [driver developers](https://zephyrproject.io) that want to support OpenThread. The driver API is part of the [IEEE 802.15.4 Driver API](https://zephyrproject.io/developer/guides/ieee-802-15-4-driver-api) subsystem and documented there.

OpenThread L2 Adaptation Layer API  
Zephyr’s OpenThread L2 platform adaptation layer glues the external OpenThread stack together with Zephyr’s IEEE 802.15.4 protocol agnostic driver API. This API is of interest to OpenThread L2 [subsystem contributors](https://zephyrproject.io) only.

Related code samples

OpenThread co-processor  
Build a Thread border-router using OpenThread’s co-processor designs.
**group** openthread

OpenThread Layer 2 abstraction layer.

**Defines**

`OPENTHREAD_L2_CTX_TYPE`

**Functions**

`int openthread_state_changed_cb_register(struct openthread_context *ot_context, struct openthread_state_changed_cb *cb)`

Registers callbacks which will be called when certain configuration or state changes occur within OpenThread.

**Parameters**
- `ot_context` – the OpenThread context to register the callback with.
- `cb` – callback struct to register.

`int openthread_state_changed_cb_unregister(struct openthread_context *ot_context, struct openthread_state_changed_cb *cb)`

Unregisters OpenThread configuration or state changed callbacks.

**Parameters**
- `ot_context` – the OpenThread context to unregister the callback from.
- `cb` – callback struct to unregister.

`void openthread_set_state_changed_cb(otStateChangedCallback cb)`

Sets function which will be called when certain configuration or state changes within OpenThread.

*Deprecated:* Use `openthread_state_changed_cb_register()` instead.

**Parameters**
- `cb` – function to call in callback procedure.

`k_tid_t openthread_thread_id_get(void)`

Get OpenThread thread identification.

`struct openthread_context *openthread_get_default_context(void)`

Get pointer to default OpenThread context.

**Return values**
- `!NULL` – On success.
- `NULL` – On failure.

`struct otInstance *openthread_get_default_instance(void)`

Get pointer to default OpenThread instance.

**Return values**
- `!NULL` – On success.
int openthread_start(struct openthread_context *ot_context)
Starts the OpenThread network.

Depends on active settings: it uses stored network configuration, start joining procedure or uses default network configuration. Additionally when the device is MTD, it sets the SED mode to properly attach the network.

Parameters

- ot_context –

void openthread_api_mutex_lock(struct openthread_context *ot_context)
Lock internal mutex before accessing OT API.

OpenThread API is not thread-safe, therefore before accessing any API function, it’s needed to lock the internal mutex, to prevent the OpenThread thread from preempting the API call.

Parameters

- ot_context – Context to lock.

int openthread_api_mutex_try_lock(struct openthread_context *ot_context)
Try to lock internal mutex before accessing OT API.

This function behaves like openthread_api_mutex_lock() provided that the internal mutex is unlocked. Otherwise, it exists immediately and returns a negative value.

Parameters

- ot_context – Context to lock.

Return values

- 0 – On success.
- <0 – On failure.

void openthread_api_mutex_unlock(struct openthread_context *ot_context)
Unlock internal mutex after accessing OT API.

Parameters

- ot_context – Context to unlock.

struct openthread_state_changed_cb

#include <openthread.h> OpenThread state change callback
OpenThread state change callback structure

Used to register a callback in the callback list. As many callbacks as needed can be added as long as each of them are unique pointers of struct openthread_state_changed_cb. Beware such structure should not be allocated on stack.

Public Members

void (*state_changed_cb)(otChangedFlags flags, struct openthread_context *ot_context, void *user_data)
Callback for notifying configuration or state changes.
**Param flags**
as per OpenThread otStateChangedCallback() aFlags parameter. See https://openthread.io/reference/group/api-instance#otstatechangedcallback

**Param ot_context**
the OpenThread context the callback is registered with.

**Param user_data**
Data to pass to the callback.

```c
void *user_data
User data if required.
```

```c
sys_snodo_t node
Internally used field for list handling.
```

- user must not directly modify

**Point-to-Point Protocol (PPP) Support**

**Overview**
Point-to-Point Protocol (PPP) is a data link layer (layer 2) communications protocol used to establish a direct connection between two nodes. PPP is used over many types of serial links since IP packets cannot be transmitted over a modem line on their own, without some data link protocol.

In Zephyr, each individual PPP link is modelled as a network interface. This is similar to how Linux implements PPP.

PPP support must be enabled at compile time by setting option `CONFIG_NET_L2_PPP`. The PPP implementation supports only these protocols:

- LCP (Link Control Protocol, RFC1661)
- HDLC (High-level data link control, RFC1662)
- IPCP (IP Control Protocol, RFC1332)
- IPV6CP (IPv6 Control Protocol, RFC5072)

For using PPP with a cellular modem, see cellular-modem sample for additional information.

**Testing**
See the net-tools README file for more details on how to test the Zephyr PPP against pppd running in Linux.

**Wi-Fi Management**

**Overview**
The Wi-Fi management API is used to manage Wi-Fi networks. It supports below modes:

- IEEE802.11 Station (STA)
- IEEE802.11 Access Point (AP)
Only personal mode security is supported with below types:

- Open
- WPA2-PSK
- WPA3-PSK-256
- WPA3-SAE

The Wi-Fi management API is implemented in the `wifi_mgmt` module as a part of the networking L2 stack. Currently, two types of Wi-Fi drivers are supported:

- Networking or socket offloaded drivers
- Native L2 Ethernet drivers

**API Reference**

*group wifi_mgmt*

Wi-Fi Management API.

**Wi-Fi utility functions.**

Utility functions for the Wi-Fi subsystem.

`int wifi_utils_parse_scan_bands(char *scan_bands_str, uint8_t *band_map)`

Convert a band specification string to a bitmap representing the bands.

The function will parse a string which specifies Wi-Fi frequency band values as a comma separated string and convert it to a bitmap. The string can use the following characters to represent the bands:

- 2: 2.4 GHz
- 5: 5 GHz
- 6: 6 GHz

For the bitmap generated refer to `wifi_frequency_bands` for bit position of each band.

E.g. a string “2,5,6” will be converted to a bitmap value of 0x7

**Parameters**

- `scan_bands_str` – String which spe.
- `band_map` – Pointer to the bitmap variable to be updated.

**Return values**

- 0 – on success.
- -errno – value in case of failure.

`int wifi_utils_parse_scan_ssids(char *scan_ssids_str, const char *ssids[], uint8_t num_ssids)`

Append a string containing an SSID to an array of SSID strings.

**Parameters**

- `scan_ssids_str` – string to be appended in the list of scanned SSIDs.
- `ssids` – Pointer to an array where the SSIDs pointers are to be stored.
- `num_ssids` – Maximum number of SSIDs that can be stored.
Return values

- 0 – on success.
- -errno – value in case of failure.

```c
int wifi_utils_parse_scan_chan(char *scan_chan_str, struct wifi_band_channel *chan,
                               uint8_t max_channels)
```

Convert a string containing a specification of scan channels to an array.

The function will parse a string which specifies channels to be scanned as a string and convert it to an array.

The channel string has to be formatted using the colon (:), comma(,), hyphen (-) and underscore (_) delimiters as follows:

- A colon identifies the value preceding it as a band. A band value (2: 2.4 GHz, 5: 5 GHz 6: 6 GHz) has to precede the channels in that band (e.g. 2: etc)
- Hyphens (-) are used to identify channel ranges (e.g. 2-7, 32-48 etc)
- Commas are used to separate channel values within a band. Channels can be specified as individual values (2,6,48 etc) or channel ranges using hyphens (1-14, 32-48 etc)
- Underscores (_) are used to specify multiple band-channel sets (e.g. 2:1,2_5:36,40 etc)
- No spaces should be used anywhere, i.e. before/after commas, before/after hyphens etc.

An example channel specification specifying channels in the 2.4 GHz and 5 GHz bands is as below: 2:1,5,7,9-11_5:36-48,100,163-167

Parameters

- `scan_chan_str` – List of channels expressed in the format described above.
- `chan` – Pointer to an array where the parsed channels are to be stored.
- `max_channels` – Maximum number of channels to store

Return values

- 0 – on success.
- -errno – value in case of failure.

```c
bool wifi_utils_validate_chan(uint16_t chan)
```

Validate a channel against a band.

Parameters

- `band` – Band to validate the channel against.
- `chan` – Channel to validate.

Return values

- true – if the channel is valid for the band.
- false – if the channel is not valid for the band.

```c
bool wifi_utils_validate_chan_2g(uint16_t chan)
```

Validate a channel against the 2.4 GHz band.

Parameters

- `chan` – Channel to validate.

Return values

6.3. Networking
bool wifi_utils_validate_chan_5g(uint16_t chan)
Validate a channel against the 5 GHz band.

Parameters
• chan – Channel to validate.

Return values
• true – if the channel is valid for the band.
• false – if the channel is not valid for the band.

bool wifi_utils_validate_chan_6g(uint16_t chan)
Validate a channel against the 6 GHz band.

Parameters
• chan – Channel to validate.

Return values
• true – if the channel is valid for the band.
• false – if the channel is not valid for the band.

WIFI_UTILS_MAX_BAND_STR_LEN
WIFI_UTILS_MAX_CHAN_STR_LEN

Defines

WIFI_COUNTRY_CODE_LEN
WIFI_LISTEN_INTERVAL_MIN
WIFI_LISTEN_INTERVAL_MAX
WIFI_SSID_MAX_LEN
WIFI_PSK_MIN_LEN
WIFI_PSK_MAX_LEN
WIFI_SAE_PSWD_MAX_LEN
WIFI_MAC_ADDR_LEN
WIFI_CHANNEL_MIN
WIFI_CHANNEL_MAX
WIFI_CHANNEL_ANY
WIFIINTERFACE_INDEX_MIN
WIFIINTERFACE_INDEX_MAX
WIFIMGMT_SCAN_SSID_FILT_MAX
WIFIMGMT_SCAN_CHAN_MAX_MANUAL
WIFIMGMT_BAND_STR_SIZE_MAX
NET_REQUEST_WIFI_SCAN
NET_REQUEST_WIFI_CONNECT
NET_REQUEST_WIFI_DISCONNECT
NET_REQUEST_WIFI_AP_ENABLE
NET_REQUEST_WIFI_AP_DISABLE
NET_REQUEST_WIFI_IFACE_STATUS
NET_REQUEST_WIFI_PS
NET_REQUEST_WIFI_PS_MODE
NET_REQUEST_WIFI_TWT
NET_REQUEST_WIFI_PS_CONFIG
NET_REQUEST_WIFI_REG_DOMAIN
NET_REQUEST_WIFI_PS_TIMEOUT
NET_REQUEST_WIFI_MODE
NET_REQUEST_WIFI_PACKET_FILTER
NET_REQUEST_WIFI_CHANNEL
NET_REQUEST_WIFI_AP_STA_DISCONNECT
NET_REQUEST_WIFI_VERSION
NET_EVENT_WIFI_SCAN_RESULT
NET_EVENT_WIFI_SCAN_DONE
NET_EVENT_WIFI_CONNECT_RESULT
NET_EVENT_WIFI_DISCONNECT_RESULT
NET_EVENT_WIFI_IFACE_STATUS
NET_EVENT_WIFI_TWT
NET_EVENT_WIFI_TWT_SLEEP_STATE
NET_EVENT_WIFI_RAW_SCAN_RESULT
NET_EVENT_WIFI_DISCONNECT_COMPLETE
NET_EVENT_WIFI_AP_ENABLE_RESULT
NET_EVENT_WIFI_AP_DISABLE_RESULT
NET_EVENT_WIFI_AP_STA_CONNECTED
NET_EVENT_WIFI_AP_STA_DISCONNECTED
WIFI_MAX_TWT_FLOWS
WIFI_MAX_TWT_INTERVAL_US
WIFI_MAX_TWT_WAKE_INTERVAL_US
WIFI_MAX_TWT_WAKE_AHEAD_DURATION_US
MAX_REG_CHAN_NUM

**Typedefs**

typedef void (*scan_result_cb_t)(struct net_if *iface, int status, struct wifi_scan_result *entry)

Scan result callback.

**Param iface**
Network interface

**Param status**
Scan result status
**Enums**

enum wifi_security_type
IEEE 802.11 security types.

*Values:*

enumerator WIFI_SECURITY_TYPE_NONE = 0
No security.

enumerator WIFI_SECURITY_TYPE_PSK
WPA2-PSK security.

enumerator WIFI_SECURITY_TYPE_PSK_SHA256
WPA2-PSK-SHA256 security.

enumerator WIFI_SECURITY_TYPE_SAE
WPA3-SAE security.

enumerator WIFI_SECURITY_TYPE_WAPI
GB 15629.11-2003 WAPI security.

enumerator WIFI_SECURITY_TYPE_EAP
EAP security - Enterprise.

enumerator WIFI_SECURITY_TYPE_WEP
WEP security.

enumerator WIFI_SECURITY_TYPE_WPA_PSK
WPA-PSK security.

enumerator WiFi_SECURITY_TYPE_UNKNOWN

enumerator WIFI_SECURITY_TYPE_MAX = WiFi_SECURITY_TYPE_UNKNOWN.wifi_security_type_MAX

enum wifi_mfp_options
IEEE 802.11w - Management frame protection.

*Values:*

enumerator WIFI_MFP_DISABLE = 0
MFP disabled.

enumerator WIFI_MFP_OPTIONAL
MFP optional.
enumerator WIFI_MFP_REQUIRED
   MFP required.

enumerator __WIFI_MFP_AFTER_LAST

enumerator WIFI_MFP_MAX = __WIFI_MFP_AFTER_LAST - 1

enumerator WIFI_MFP_UNKNOWN

enum wifi_frequency_bands
   IEEE 802.11 operational frequency bands (not exhaustive).
   Values:

   enumerator WIFI_FREQ_BAND_2_4_GHZ = 0
      2.4 GHz band.

   enumerator WIFI_FREQ_BAND_5_GHZ
      5 GHz band.

   enumerator WIFI_FREQ_BAND_6_GHZ
      6 GHz band (Wi-Fi 6E, also extends to 7GHz).

   enumerator __WIFI_FREQ_BAND_AFTER_LAST
      Number of frequency bands available.

   enumerator WIFI_FREQ_BAND_MAX = __WIFI_FREQ_BAND_AFTER_LAST - 1
      Highest frequency band available.

   enumerator WIFI_FREQ_BAND_UNKNOWN
      Invalid frequency band.

enum wifi_iface_state
   Wi-Fi interface states.
   Based on https://w1.fi/wpa_supplicant/devel/defs_8h.html#a4aeb27c1e4abd046df3064ea9756f0bc
   Values:

   enumerator WIFI_STATE_DISCONNECTED = 0
      Interface is disconnected.

   enumerator WIFI_STATE_INTERFACE_DISABLED
      Interface is disabled (administratively).

   enumerator WIFI_STATE_INACTIVE
      No enabled networks in the configuration.

   enumerator WIFI_STATE_SCANNING
      Interface is scanning for networks.
enumerator WIFI_STATE_AUTHENTICATING
    Authentication with a network is in progress.

enumerator WIFI_STATE_ASSOCIATING
    Association with a network is in progress.

enumerator WIFI_STATE_ASSOCIATED
    Association with a network completed.

enumerator WIFI_STATE_4WAY_HANDSHAKE
    4-way handshake with a network is in progress.

enumerator WIFI_STATE_GROUP_HANDSHAKE
    Group Key exchange with a network is in progress.

enumerator WIFI_STATE_COMPLETED
    All authentication completed, ready to pass data.

enumerator __WIFI_STATE_AFTER_LAST

enumerator WIFI_STATE_MAX = __WIFI_STATE_AFTER_LAST - 1

enumerator WIFI_STATE_UNKNOWN

enum wifi_iface_mode
    Wi-Fi interface modes.

Based on https://w1.fi/wpa_supplicant/devel/defs_8h.html#a4aeb27c1e4abd046df3064ea9756f0bc

Values:

enumerator WIFI_MODE_INFRA = 0
    Infrastructure station mode.

enumerator WIFI_MODE_IBSS = 1
    IBSS (ad-hoc) station mode.

enumerator WIFI_MODE_AP = 2
    AP mode.

enumerator WIFI_MODE_P2P_GO = 3
    P2P group owner mode.

enumerator WIFI_MODE_P2P_GROUPFORMATION = 4
    P2P group formation mode.

enumerator WIFI_MODE_MESH = 5
    802.11s Mesh mode.
enumerator __WIFI_MODE_AFTER_LAST

eumerator WIFI_MODE_MAX = __WIFI_MODE_AFTER_LAST - 1

enumerator WIFI_MODE_UNKNOWN

enum wifi_link_mode
    Wi-Fi link operating modes.
    As per https://en.wikipedia.org/wiki/Wi-Fi#Versions_and_generations.
    Values:

    enumerator WIFI_0 = 0
        802.11 (legacy).

    enumerator WIFI_1
        802.11b.

    enumerator WIFI_2
        802.11a.

    enumerator WIFI_3
        802.11g.

    enumerator WIFI_4
        802.11n.

    enumerator WIFI_5
        802.11ac.

    enumerator WIFI_6
        802.11ax.

    enumerator WIFI_6E
        802.11ax 6GHz.

    enumerator WIFI_7
        802.11be.

enumerator __WIFI_LINK_MODE_AFTER_LAST

eenumerator WIFI_LINK_MODE_MAX = __WIFI_LINK_MODE_AFTER_LAST - 1

enumerator WIFI_LINK_MODE_UNKNOWN

enum wifi_scan_type
    Wi-Fi scanning types.
    Values:
enumerator WIFI_SCAN_TYPE_ACTIVE = 0
    Active scanning (default).

eumerator WIFI_SCAN_TYPE_PASSIVE
    Passive scanning.

enum wifi_ps
    Wi-Fi power save states.
    Values:

eenumerator WIFI_PS_DISABLED = 0
    Power save disabled.

eenumerator WIFI_PS_ENABLED
    Power save enabled.

e enumerator wifi_ps_mode
    Wi-Fi power save modes.
    Values:

eenumerator WIFI_PS_MODE_LEGACY = 0
    Legacy power save mode.

eenumerator WIFI_PS_MODE_WMM
    WMM power save mode.

enum wifi_operational_modes
    Wifi operational mode.
    Values:

eenumerator WIFI_STA_MODE = BIT(0)
    STA mode setting enable.

eenumerator WIFI_MONITOR_MODE = BIT(1)
    Monitor mode setting enable.

eenumerator WIFI_TX_INJECTION_MODE = BIT(2)
    TX injection mode setting enable.

eenumerator WIFI_PROMISCUOUS_MODE = BIT(3)
    Promiscuous mode setting enable.

eenumerator WIFI_AP_MODE = BIT(4)
    AP mode setting enable.

eenumerator WIFI_SOFTAP_MODE = BIT(5)
    Softap mode setting enable.
enum wifi_filter
   Mode filter settings.
   Values:

   enumerator WIFI_PACKET_FILTER_ALL = BIT(0)
      Support management, data and control packet sniffing.

   enumerator WIFI_PACKET_FILTER_MGMT = BIT(1)
      Support only sniffing of management packets.

   enumerator WIFI_PACKET_FILTER_DATA = BIT(2)
      Support only sniffing of data packets.

   enumerator WIFI_PACKET_FILTER_CTRL = BIT(3)
      Support only sniffing of control packets.

enum wifi_twt_operation
   Wi-Fi Target Wake Time (TWT) operations.
   Values:

   enumerator WIFI_TWT_SETUP = 0
      TWT setup operation.

   enumerator WIFI_TWT_TEARDOWN
      TWT teardown operation.

enum wifi_twt_negotiation_type
   Wi-Fi Target Wake Time (TWT) negotiation types.
   Values:

   enumerator WIFI_TWT_INDIVIDUAL = 0
      TWT individual negotiation.

   enumerator WIFI_TWT_BROADCAST
      TWT broadcast negotiation.

   enumerator WIFI_TWT_WAKE_TBTT
      TWT wake TBTT negotiation.

enum wifi_twt_setup_cmd
   Wi-Fi Target Wake Time (TWT) setup commands.
   Values:

   enumerator WIFI_TWT_SETUP_CMD_REQUEST = 0
      TWT setup request.

   enumerator WIFI_TWT_SETUP_CMD_SUGGEST
      TWT setup suggest (parameters can be changed by AP)
enumerator WIFI_TWT_SETUP_CMD_DEMAND
   TWT setup demand (parameters can not be changed by AP)

enumerator WIFI_TWT_SETUP_CMD_GROUPING
   TWT setup grouping (grouping of TWT flows)

enumerator WIFI_TWT_SETUP_CMD_ACCEPT
   TWT setup accept (parameters accepted by AP)

enumerator WIFI_TWT_SETUP_CMD_ALTERNATE
   TWT setup alternate (alternate parameters suggested by AP)

enumerator WIFI_TWT_SETUP_CMD_DICTATE
   TWT setup dictate (parameters dictated by AP)

enumerator WIFI_TWT_SETUP_CMD_REJECT
   TWT setup reject (parameters rejected by AP)

enum wifi_twt_setup_resp_status
   Wi-Fi Target Wake Time (TWT) negotiation status.

   Values:

   enumerator WIFI_TWT_RESP_RECEIVED = 0
      TWT response received for TWT request.

   enumerator WIFI_TWT_RESP_NOT_RECEIVED
      TWT response not received for TWT request.

enum wifi_twt_fail_reason
   Target Wake Time (TWT) error codes.

   Values:

   enumerator WIFI_TWT_FAIL_UNSPECIFIED
      Unspecified error.

   enumerator WIFI_TWT_FAIL_CMD_EXEC_FAIL
      Command execution failed.

   enumerator WIFI_TWT_FAIL_OPERATION_NOT_SUPPORTED
      Operation not supported.

   enumerator WIFI_TWT_FAIL_UNABLE_TO_GET_IFACE_STATUS
      Unable to get interface status.

   enumerator WIFI_TWT_FAIL_DEVICE_NOT_CONNECTED
      Device not connected to AP.
enumerator WIFI_TWT_FAIL_PEER_NOT_HE_CAPAB
   Peer not HE (802.11ax/Wi-Fi 6) capable.

enumerator WIFI_TWT_FAIL_PEER_NOT_TWT_CAPAB
   Peer not TWT capable.

enumerator WIFI_TWT_FAIL_OPERATION_IN_PROGRESS
   A TWT flow is already in progress.

enumerator WIFI_TWT_FAIL_INVALID_FLOW_ID
   Invalid negotiated flow id.

enumerator WIFI_TWT_FAIL_IP_NOT_ASSIGNED
   IP address not assigned or configured.

enumerator WIFI_TWT_FAIL_FLOW_ALREADY_EXISTS
   Flow already exists.

enum wifi_twt_teardown_status
   Wi-Fi Target Wake Time (TWT) teardown status.
   Values:

   enumerator WIFI_TWT_TEARDOWN_SUCCESS = 0
      TWT teardown success.

   enumerator WIFI_TWT_TEARDOWN_FAILED
      TWT teardown failure.

enum wifi_ps_param_type
   Wi-Fi power save parameters.
   Values:

   enumerator WIFI_PS_PARAM_STATE
      Power save state.

   enumerator WIFI_PS_PARAM_LISTEN_INTERVAL
      Power save listen interval.

   enumerator WIFI_PS_PARAM_WAKEUP_MODE
      Power save wakeup mode.

   enumerator WIFI_PS_PARAM_MODE
      Power save mode.

   enumerator WIFI_PS_PARAM_TIMEOUT
      Power save timeout.
enum wifi_ps_wakeup_mode
    Wi-Fi power save modes.
    Values:

    enumerator WIFI_PS_WAKEUP_MODE_DTIM = 0
        DTIM based wakeup.

    enumerator WIFI_PS_WAKEUP_MODE_LISTEN_INTERVAL
        Listen interval based wakeup.

enum wifi_config_ps_param_fail_reason
    Wi-Fi power save error codes.
    Values:

    enumerator WIFI_PS_PARAM_FAIL_UNSPECIFIED
        Unspecified error.

    enumerator WIFI_PS_PARAM_FAIL_CMD_EXEC_FAIL
        Command execution failed.

    enumerator WIFI_PS_PARAM_FAIL_OPERATION_NOT_SUPPORTED
        Parameter not supported.

    enumerator WIFI_PS_PARAM_FAIL_UNABLE_TO_GET_IFACE_STATUS
        Unable to get interface status.

    enumerator WIFI_PS_PARAM_FAIL_DEVICE_NOT_CONNECTED
        Device not connected to AP.

    enumerator WIFI_PS_PARAM_FAIL_DEVICE_CONNECTED
        Device already connected to AP.

    enumerator WIFI_PS_PARAM_LISTEN_INTERVAL_RANGE_INVALID
        Listen interval out of range.

enum net_request_wifi_cmd
    Wi-Fi management commands.
    Values:

    enumerator NET_REQUEST_WIFI_CMD_SCAN = 1
        Scan for Wi-Fi networks.

    enumerator NET_REQUEST_WIFI_CMD_CONNECT
        Connect to a Wi-Fi network.

    enumerator NET_REQUEST_WIFI_CMD_DISCONNECT
        Disconnect from a Wi-Fi network.
enumerator NET_REQUEST_WIFI_CMD_AP_ENABLE
    Enable AP mode.

enumerator NET_REQUEST_WIFI_CMD_AP_DISABLE
    Disable AP mode.

enumerator NET_REQUEST_WIFI_CMD_IFACE_STATUS
    Get interface status.

enumerator NET_REQUEST_WIFI_CMD_PS
    Set power save status.

enumerator NET_REQUEST_WIFI_CMD_PS_MODE
    Set power save mode.

enumerator NET_REQUEST_WIFI_CMD_TWT
    Setup or teardown TWT flow.

enumerator NET_REQUEST_WIFI_CMD_PS_CONFIG
    Get power save config.

enumerator NET_REQUEST_WIFI_CMD_REG_DOMAIN
    Set or get regulatory domain.

enumerator NET_REQUEST_WIFI_CMD_PS_TIMEOUT
    Set power save timeout.

enumerator NET_REQUEST_WIFI_CMD_MODE
    Set or get Mode of operation.

enumerator NET_REQUEST_WIFI_CMD_PACKET_FILTER
    Set or get packet filter setting for current mode.

enumerator NET_REQUEST_WIFI_CMD_CHANNEL
    Set or get Wi-Fi channel for Monitor or TX-Injection mode.

enumerator NET_REQUEST_WIFI_CMD_AP_STA_DISCONNECT
    Disconnect a STA from AP.

enumerator NET_REQUEST_WIFI_CMD_VERSION
    Get Wi-Fi driver and Firmware versions.

enumerator NET_REQUEST_WIFI_CMD_MAX

enum net_event_wifi_cmd
    Wi-Fi management events.
    
    Values:
enumerator NET_EVENT_WIFI_CMD_SCAN_RESULT = 1
Scan results available.

enumerator NET_EVENT_WIFI_CMD_SCAN_DONE
Scan done.

enumerator NET_EVENT_WIFI_CMD_CONNECT_RESULT
Connect result.

enumerator NET_EVENT_WIFI_CMD_DISCONNECT_RESULT
Disconnect result.

enumerator NET_EVENT_WIFI_CMD_IFACE_STATUS
Interface status.

enumerator NET_EVENT_WIFI_CMD_TWT
TWT events.

enumerator NET_EVENT_WIFI_CMD_TWT_SLEEP_STATE
TWT sleep status: awake or sleeping, can be used by application to determine if it can send data or not.

enumerator NET_EVENT_WIFI_CMD_RAW_SCAN_RESULT
Raw scan results available.

enumerator NET_EVENT_WIFI_CMD_DISCONNECT_COMPLETE
Disconnect complete.

enumerator NET_EVENT_WIFI_CMD_AP_ENABLE_RESULT
AP mode enable result.

enumerator NET_EVENT_WIFI_CMD_AP_DISABLE_RESULT
AP mode disable result.

enumerator NET_EVENT_WIFI_CMD_AP_STA_CONNECTED
STA connected to AP.

enumerator NET_EVENT_WIFI_CMD_AP_STA_DISCONNECTED
STA disconnected from AP.

enum wifi_conn_status
Wi-Fi connect result codes.
To be overlaid on top of wifi_status in the connect result event for detailed status.
Values:

enumerator WIFI_STATUS_CONN_SUCCESS = 0
Connection successful.
enumerator WIFI_STATUS_CONN_FAIL
    Connection failed - generic failure.

enumerator WIFI_STATUS_CONN_WRONG_PASSWORD
    Connection failed - wrong password.

enumerator WIFI_STATUS_CONN_TIMEOUT
    Connection timed out.

enumerator WIFI_STATUS_CONN_AP_NOT_FOUND
    Connection failed - AP not found.

e num wifi_disconn_reason
    Wi-Fi disconnect reason codes.
    To be overlaid on top of wifi_status in the disconnect result event for detailed reason.
    Values:

enumerator WIFI_REASON_DISCONN_UNSPECIFIED = 0
    Unspecified reason.

enumerator WIFI_REASON_DISCONN_USER_REQUEST
    Disconnected due to user request.

enumerator WIFI_REASON_DISCONN_AP_LEAVING
    Disconnected due to AP leaving.

enumerator WIFI_REASON_DISCONN_INACTIVITY
    Disconnected due to inactivity.

e num wifi_ap_status
    Wi-Fi AP mode result codes.
    To be overlaid on top of wifi_status in the AP mode enable or disable result event for detailed status.
    Values:

enumerator WIFI_STATUS_AP_SUCCESS = 0
    AP mode enable or disable successful.

enumerator WIFI_STATUS_AP_FAIL
    AP mode enable or disable failed - generic failure.

enumerator WIFI_STATUS_AP_CHANNEL_NOT_SUPPORTED
    AP mode enable failed - channel not supported.

enumerator WIFI_STATUS_AP_CHANNEL_NOT_ALLOWED
    AP mode enable failed - channel not allowed.
enumerator WIFI_STATUS_AP_SSID_NOT_ALLOWED
    AP mode enable failed - SSID not allowed.

denumerator WIFI_STATUS_AP_AUTH_TYPE_NOT_SUPPORTED
    AP mode enable failed - authentication type not supported.

denumerator WIFI_STATUS_AP_OP_NOT_SUPPORTED
    AP mode enable failed - operation not supported.

denumerator WIFI_STATUS_AP_OP_NOT_PERMITTED
    AP mode enable failed - operation not permitted.

d enum wifi_mgmt_op
    Generic get/set operation for any command.
    Values:

d enumerator WIFI_MGMT_GET = 0
    Get operation.

d enumerator WIFI_MGMT_SET = 1
    Set operation.

d enum wifi_twt_sleep_state
    Wi-Fi TWT sleep states.
    Values:

d enumerator WIFI_TWT_STATE_SLEEP = 0
    TWT sleep state: sleeping.

d enumerator WIFI_TWT_STATE_AWAKE = 1
    TWT sleep state: awake.

Functions

d const char *wifi_security_txt(enum wifi_security_type security)
    Helper function to get user-friendly security type name.

d const char *wifi_mfp_txt(enum wifi_mfp_options mfp)
    Helper function to get user-friendly MFP name.

d const char *wifi_band_txt(enum wifi_frequency_bands band)
    Helper function to get user-friendly frequency band name.

d const char *wifi_state_txt(enum wifi_iface_state state)
    Helper function to get user-friendly interface state name.

d const char *wifi_mode_txt(enum wifi_iface_mode mode)
    Helper function to get user-friendly interface mode name.

d const char *wifi_link_mode_txt(enum wifi_link_mode link_mode)
    Helper function to get user-friendly link mode name.
const char *wifi_ps_txt(enum wifi_ps ps_name)
  Helper function to get user-friendly ps name.
const char *wifi_ps_mode_txt(enum wifi_ps_mode ps_mode)
  Helper function to get user-friendly ps mode name.
const char *wifi_twt_operation_txt(enum wifi_twt_operation twt_operation)
  Helper function to get user-friendly twt operation name.
const char *wifi_twt_negotiation_type_txt(enum wifi_twt_negotiation_type
twt_negotiation)
  Helper function to get user-friendly twt negotiation type name.
const char *wifi_twt_setup_cmd_txt(enum wifi_twt_setup_cmd twt_setup)
  Helper function to get user-friendly twt setup cmd name.
static inline const char *wifi_twt_get_err_code_str(int16_t err_no)
  Helper function to get user-friendly TWT error code name.
const char *wifi_ps_wakeup_mode_txt(enum wifi_ps_wakeup_mode ps_wakeup_mode)
  Helper function to get user-friendly ps wakeup mode name.
static inline const char *wifi_ps_get_config_err_code_str(int16_t err_no)
  Helper function to get user-friendly power save error code name.
void wifi_mgmt_raise_connect_result_event(struct net_if *iface, int status)
  Wi-Fi management connect result event.

  Parameters
  • iface – Network interface
  • status – Connect result status
void wifi_mgmt_raise_disconnect_result_event(struct net_if *iface, int status)
  Wi-Fi management disconnect result event.

  Parameters
  • iface – Network interface
  • status – Disconnect result status
void wifi_mgmt_raise_iface_status_event(struct net_if *iface, struct wifi_iface_status *
iface_status)
  Wi-Fi management interface status event.

  Parameters
  • iface – Network interface
  • iface_status – Interface status
void wifi_mgmt_raise_twt_event(struct net_if *iface, struct wifi_twt_params *
twt_params)
  Wi-Fi management TWT event.

  Parameters
  • iface – Network interface
  • twt_params – TWT parameters
void wifi_mgmt_raise_twt_sleep_state(struct net_if *iface, int twt_sleep_state)
  Wi-Fi management TWT sleep state event.

  Parameters
• iface – Network interface
• twt_sleep_state – TWT sleep state

```c
void wifi_mgmt_raise_raw_scan_result_event(struct net_if *iface, struct wifi_raw_scan_result *raw_scan_info)
```

Wi-Fi management raw scan result event.

**Parameters**
- iface – Network interface
- raw_scan_info – Raw scan result

```c
void wifi_mgmt_raise_disconnect_complete_event(struct net_if *iface, int status)
```

Wi-Fi management disconnect complete event.

**Parameters**
- iface – Network interface
- status – Disconnect complete status

```c
void wifi_mgmt_raise_ap_enable_result_event(struct net_if *iface, enum wifi_ap_status status)
```

Wi-Fi management AP mode enable result event.

**Parameters**
- iface – Network interface
- status – AP mode enable result status

```c
void wifi_mgmt_raise_ap_disable_result_event(struct net_if *iface, enum wifi_ap_status status)
```

Wi-Fi management AP mode disable result event.

**Parameters**
- iface – Network interface
- status – AP mode disable result status

```c
void wifi_mgmt_raise_ap_sta_connected_event(struct net_if *iface, struct wifi_ap_sta_info *sta_info)
```

Wi-Fi management AP mode STA connected event.

**Parameters**
- iface – Network interface
- sta_info – STA information

```c
void wifi_mgmt_raise_ap_sta_disconnected_event(struct net_if *iface, struct wifi_ap_sta_info *sta_info)
```

Wi-Fi management AP mode STA disconnected event.

**Parameters**
- iface – Network interface
- sta_info – STA information

```
struct wifi_version
#include <wifi_mgmt.h> Wi-Fi version.
```
Public Members

const char *drv_version
Driver version.

const char *fw_version
Firmware version.

struct wifi_band_channel
#include <wifi_mgmt.h> Wi-Fi structure to uniquely identify a band-channel pair.

Public Members

uint8_t band
Frequency band.

uint8_t channel
Channel.

struct wifi_scan_params
#include <wifi_mgmt.h> Wi-Fi scan parameters structure.
Used to specify parameters which can control how the Wi-Fi scan is performed.

Public Members

enum wifi_scan_type scan_type
Scan type, see enum wifi_scan_type.
The scan_type is only a hint to the underlying Wi-Fi chip for the preferred mode of scan. The actual mode of scan can depend on factors such as the Wi-Fi chip implementation support, regulatory domain restrictions etc.

uint8_t bands
Bitmap of bands to be scanned.
Refer to wifi_frequency_bands for bit position of each band.

uint16_t dwell_time_active
Active scan dwell time (in ms) on a channel.

uint16_t dwell_time_passive
Passive scan dwell time (in ms) on a channel.

const char *ssids[1]
Array of SSID strings to scan.
uint16_t max_bss_cnt

Specifies the maximum number of scan results to return.

These results would be the BSSIDs with the best RSSI values, in all the scanned channels. This should only be used to limit the number of returned scan results, and cannot be counted upon to limit the scan time, since the underlying Wi-Fi chip might have to scan all the channels to find the max_bss_cnt number of APs with the best signal strengths. A value of 0 signifies that there is no restriction on the number of scan results to be returned.

struct wifi_band_channel band_chan[1]

Channel information array indexed on Wi-Fi frequency bands and channels within that band.

E.g. to scan channel 6 and 11 on the 2.4 GHz band, channel 36 on the 5 GHz band:

```c
chan[0] = {WIFI_FREQ_BAND_2_4_GHZ, 6};
chan[1] = {WIFI_FREQ_BAND_2_4_GHZ, 11};
chan[2] = {WIFI_FREQ_BAND_5_GHZ, 36};
```

This list specifies the channels to be considered for scan. The underlying Wi-Fi chip can silently omit some channels due to various reasons such as channels not conforming to regulatory restrictions etc. The invoker of the API should ensure that the channels specified follow regulatory rules.

struct wifi_scan_result

#include <wifi_mgmt.h> Wi-Fi scan result, each result is provided to the net_mgmt_event_callback via its info attribute (see net_mgmt.h)

Public Members

uint8_t ssid[WIFI_SSID_MAX_LEN]

SSID.

uint8_t ssid_length

SSID length.

uint8_t band

Frequency band.

uint8_t channel

Channel.

enum wifi_security_type security

Security type.

enum wifi_mfp_options mfp

MFP options.

int8_t rssi

RSSI.
uint8_t mac[WIFI_MAC_ADDR_LEN]
BSSID.

uint8_t mac_length
BSSID length.

struct wifi_connect_req_params
#include <wifi_mgmt.h> Wi-Fi connect request parameters.

Public Members

const uint8_t *ssid
SSID.

uint8_t ssid_length
SSID length.

const uint8_t *psk
Pre-shared key.

uint8_t psk_length
Pre-shared key length.

const uint8_t *sae_password
SAE password (same as PSK but with no length restrictions), optional.

uint8_t sae_password_length
SAE password length.

uint8_t band
Frequency band.

uint8_t channel
Channel.

denum wifi_security_type security
Security type.

denum wifi_mfp_options mfp
MFP options.

int timeout
Connect timeout in seconds, SYS_FOREVER_MS for no timeout.

struct wifi_status
#include <wifi_mgmt.h> Generic Wi-Fi status for commands and events.

struct wifi_iface_status
#include <wifi_mgmt.h> Wi-Fi interface status.
Public Members

int state
    Interface state, see enum wifi_iface_state.

unsigned int ssid_len
    SSID length.

char ssid[WIFI_SSID_MAX_LEN]
    SSID.

char bssid[WIFI_MAC_ADDR_LEN]
    BSSID.

denum wifi_frequency_bands band
    Frequency band.

unsigned int channel
    Channel.

denum wifi_iface_mode iface_mode
    Interface mode, see enum wifi_iface_mode.

denum wifi_link_mode link_mode
    Link mode, see enum wifi_link_mode.

denum wifi_security_type security
    Security type, see enum wifi_security_type.

denum wifi_mfp_options mfp
    MFP options, see enum wifi_mfp_options.

int rssi
    RSSI.

unsigned char dtim_period
    DTIM period.

unsigned short beacon_interval
    Beacon interval.

bool twt_capable
    is TWT capable?

struct wifi_ps_params
    #include <wifi_mgmt.h> Wi-Fi power save parameters.
Public Members

enum wifi_ps_wakeup_mode wakeup_mode
    Wi-Fi power save wakeup mode.

enum wifi_ps_mode mode
    Wi-Fi power save mode.

unsigned int timeout_ms
    Wi-Fi power save timeout.
    This is the time out to wait after sending a TX packet before going back to power
    save (in ms) to receive any replies from the AP. Zero means this feature is disabled.
    It's a tradeoff between power consumption and latency.

enum wifi_ps_param_type type
    Wi-Fi power save type.

enum wifi_config_ps_param_fail_reason fail_reason
    Wi-Fi power save fail reason.

struct wifi_twt_params
    #include <wifi_mgmt.h> Wi-Fi TWT parameters.

Public Members

enum wifi_twt_operation operation
    TWT operation, see enum wifi_twt_operation.

enum wifi_twt_negotiation_type negotiation_type
    TWT negotiation type, see enum wifi_twt_negotiation_type.

enum wifi_twt_setup_cmd setup_cmd
    TWT setup command, see enum wifi_twt_setup_cmd.

enum wifi_twt_setup_resp_status resp_status
    TWT setup response status, see enum wifi_twt_setup_resp_status.

enum wifi_twt_teardown_status teardown_status
    TWT teardown cmd status, see enum wifi_twt_teardown_status.

uint8_t dialog_token
    Dialog token, used to map requests to responses.

uint8_t flow_id
    Flow ID, used to map setup with teardown.
uint64_t twt_interval
    Interval = Wake up time + Sleeping time.

bool responder
    Requestor or responder.

bool trigger
    Trigger enabled or disabled.

bool implicit
    Implicit or explicit.

bool announce
    Announced or unannounced.

uint32_t twt_wake_interval
    Wake up time.

struct wifi_twt_params setup
    Setup specific parameters.

bool teardown_all
    Teardown all flows.

struct wifi_twt_params teardown
    Teardown specific parameters.

enum wifi_twt_fail_reason fail_reason
    TWT fail reason, see enum wifi_twt_fail_reason.

struct wifi_twt_flow_info
    #include <wifi_mgmt.h> Wi-Fi TWT flow information.

Public Members

uint64_t twt_interval
    Interval = Wake up time + Sleeping time.

uint8_t dialog_token
    Dialog token, used to map requests to responses.

uint8_t flow_id
    Flow ID, used to map setup with teardown.

enum wifi_twt_negotiation_type negotiation_type
    TWT negotiation type, see enum wifi_twt_negotiation_type.
bool responder
  Requestor or responder.

bool trigger
  Trigger enabled or disabled.

bool implicit
  Implicit or explicit.

bool announce
  Announced or unannounced.

uint32_t twt_wake_interval
  Wake up time.

struct wifi_ps_config
  #include <wifi_mgmt.h> Wi-Fi power save configuration.

Public Members

cchar num_twt_flows
  Number of TWT flows.

struct wifi_twt_flow_info twt_flows[8]
  TWT flow details.

struct wifi_ps_params ps_params
  Power save configuration.

struct wifi_reg_chan_info
  #include <wifi_mgmt.h> Per-channel regulatory attributes.

Public Members

unsigned short center_frequency
  Center frequency in MHz.

unsigned short max_power
  Maximum transmission power (in dBm)

unsigned short supported
  Is channel supported or not.

unsigned short passive_only
  Passive transmissions only.
unsigned short dfs
   Is a DFS channel.

struct wifi_reg_domain
   #include <wifi_mgmt.h> Regulatory domain information or configuration.

Public Members

bool force
   Ignore all other regulatory hints over this one.

uint8_t country_code[WIFI_COUNTRY_CODE_LEN]

unsigned int num_channels
   Number of channels supported.

struct wifi_reg_chan_info *chan_info
   Channels information.

struct wifi_raw_scan_result
   #include <wifi_mgmt.h> Wi-Fi raw scan result.

Public Members

int8_t rssi
   RSSI.

int frame_length
   Frame length.

unsigned short frequency
   Frequency.

uint8_t data[NUM_WIFI_MGMT_RAW_SCAN_RESULT_LENGTH]
   Raw scan data.

struct wifi_ap_sta_info
   #include <wifi_mgmt.h> AP mode - connected STA details.

Public Members

enum wifi_link_mode link_mode
   Link mode, see enum wifi_link_mode.
uint8_t mac[WIFI_MAC_ADDR_LEN]
    MAC address.

uint8_t mac_length
    MAC address length.

bool twt_capable
    is TWT capable?

union wifi_mgmt_events
    #include <wifi_mgmt.h>

Public Members

struct wifi_scan_result scan_result

struct wifi_status connect_status

struct wifi_iface_status iface_status

struct wifi_twt_params twt_params

struct wifi_ap_sta_info ap_sta_info

Public Members

struct wifi_mode_info
    #include <wifi_mgmt.h> Wi-Fi mode setup.

Public Members

uint8_t mode
    Mode setting for a specific mode of operation.

uint8_t if_index
    Interface index.

enum wifi_mgmt_op oper
    Get or set operation.

struct wifi_filter_info
    #include <wifi_mgmt.h> Wi-Fi filter setting for monitor, prmoiscuous, TX-injection modes.

Public Members
uint8_t filter
    Filter setting.

uint8_t if_index
    Interface index.

uint16_t buffer_size
    Filter buffer size.

denum wifi_mgmt_op oper
    Get or set operation.

struct wifi_channel_info
    #include <wifi_mgmt.h> Wi-Fi channel setting for monitor and TX-injection modes.

Public Members

uint16_t channel
    Channel value to set.

uint8_t if_index
    Interface index.

denum wifi_mgmt_op oper
    Get or set operation.

struct wifi_mgmt_ops
    #include <wifi_mgmt.h> Wi-Fi management API.

Public Members

int (*scan)(const struct device *dev, struct wifi_scan_params *params, scan_result_cb_t cb)
    Scan for Wi-Fi networks.

    **Param dev**
    Pointer to the device structure for the driver instance.

    **Param params**
    Scan parameters

    **Param cb**
    Callback to be called for each result cb parameter is the cb that should be called for each result by the driver. The wifi mgmt part will take care of raising the necessary event etc.

    **Return**
    0 if ok, < 0 if error

int (*connect)(const struct device *dev, struct wifi_connect_req_params *params)
    Connect to a Wi-Fi network.

    **Param dev**
    Pointer to the device structure for the driver instance.

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Param params
   Connect parameters
Return
   0 if ok, < 0 if error

int (*disconnect)(const struct device *dev)
Disconnect from a Wi-Fi network.
   Param dev
      Pointer to the device structure for the driver instance.
   Return
      0 if ok, < 0 if error

int (*ap_enable)(const struct device *dev, struct wifi_connect_req_params *params)
Enable AP mode.
   Param dev
      Pointer to the device structure for the driver instance.
   Param params
      AP mode parameters
   Return
      0 if ok, < 0 if error

int (*ap_disable)(const struct device *dev)
Disable AP mode.
   Param dev
      Pointer to the device structure for the driver instance.
   Return
      0 if ok, < 0 if error

int (*ap_sta_disconnect)(const struct device *dev, const uint8_t *mac)
Disconnect a STA from AP.
   Param dev
      Pointer to the device structure for the driver instance.
   Param mac
      MAC address of the STA to disconnect
   Return
      0 if ok, < 0 if error

int (*iface_status)(const struct device *dev, struct wifi_iface_status *status)
Get interface status.
   Param dev
      Pointer to the device structure for the driver instance.
   Param status
      Interface status
   Return
      0 if ok, < 0 if error

int (*get_stats)(const struct device *dev, struct net_stats_wifi *stats)
Get Wi-Fi statistics.
   Param dev
      Pointer to the device structure for the driver instance.
   Param stats
      Wi-Fi statistics
   Return
      0 if ok, < 0 if error
int (*set_power_save)(const struct device *dev, struct wifi_ps_params *params)
Set power save status.
  
  **Param dev**
  Pointer to the device structure for the driver instance.
  
  **Param params**
  Power save parameters
  
  **Return**
  0 if ok, < 0 if error

int (*set_twt)(const struct device *dev, struct wifi_twt_params *params)
Setup or teardown TWT flow.
  
  **Param dev**
  Pointer to the device structure for the driver instance.
  
  **Param params**
  TWT parameters
  
  **Return**
  0 if ok, < 0 if error

int (*get_power_save_config)(const struct device *dev, struct wifi_ps_config *config)
Get power save config.
  
  **Param dev**
  Pointer to the device structure for the driver instance.
  
  **Param config**
  Power save config
  
  **Return**
  0 if ok, < 0 if error

int (*reg_domain)(const struct device *dev, struct wifi_reg_domain *reg_domain)
Set or get regulatory domain.
  
  **Param dev**
  Pointer to the device structure for the driver instance.
  
  **Param reg_domain**
  Regulatory domain
  
  **Return**
  0 if ok, < 0 if error

int (*filter)(const struct device *dev, struct wifi_filter_info *filter)
Set or get packet filter settings for monitor and promiscuous modes.
  
  **Param dev**
  Pointer to the device structure for the driver instance.
  
  **Param packet**
  Filter settings
  
  **Return**
  0 if ok, < 0 if error

int (*mode)(const struct device *dev, struct wifi_mode_info *mode)
Set or get mode of operation.
  
  **Param dev**
  Pointer to the device structure for the driver instance.
  
  **Param mode**
  Settings
  
  **Return**
  0 if ok, < 0 if error

int (*channel)(const struct device *dev, struct wifi_channel_info *channel)
Set or get current channel of operation.

**Param dev**
- Pointer to the device structure for the driver instance.

**Param channel**
- settings

**Return**
- 0 if ok, < 0 if error

```c
int (*get_version)(const struct device *dev, struct wifi_version *params)
```

Get Version of WiFi driver and Firmware.

The driver that implements the `get_version` function must not use stack to allocate the version information pointers that are returned as `params` struct members. The version pointer parameters should point to a static memory either in ROM (preferred) or in RAM.

**Param dev**
- Pointer to the device structure for the driver instance

**Param params**
- Version parameters

**Return**
- 0 if ok, < 0 if error

```c
struct net_wifi_mgmt_offload
    #include <wifi_mgmt.h> Wi-Fi management offload API.
```

### Public Members

```c
struct ethernet_api wifi_iface
```

Mandatory to get in first position.

A network device should indeed provide a pointer on such `net_if_api` structure. So we make current structure pointer that can be casted to a `net_if_api` structure pointer. Ethernet API

```c
const struct wifi_mgmt_ops *const wifi_mgmt_api
```

Wi-Fi management API.

```c
void *wifi_drv_ops
```

Wi-Fi supplicant driver API.

### Protocols

#### CoAP

- **Overview**
- **Sample Usage**
  - CoAP Server
  - CoAP Client
- **Testing**
Overview  The Constrained Application Protocol (CoAP) is a specialized web transfer protocol for use with constrained nodes and constrained (e.g., low-power, lossy) networks. It provides a convenient API for RESTful Web services that support CoAP's features. For more information about the protocol itself, see IETF RFC7252 The Constrained Application Protocol.

Zephyr provides a CoAP library which supports client and server roles. The library can be enabled with CONFIG_COAP Kconfig option and is configurable as per user needs. The Zephyr CoAP library is implemented using plain buffers. Users of the API create sockets for communication and pass the buffer to the library for parsing and other purposes. The library itself doesn't create any sockets for users.

On top of CoAP, Zephyr has support for LWM2M “Lightweight Machine 2 Machine” protocol, a simple, low-cost remote management and service enablement mechanism. See Lightweight M2M (LWM2M) for more information.

Supported RFCs:
- RFC7252: The Constrained Application Protocol (CoAP)
- RFC6690: Constrained RESTful Environments (CoRE) Link Format
- RFC7959: Block-Wise Transfers in the Constrained Application Protocol (CoAP)
- RFC7641: Observing Resources in the Constrained Application Protocol (CoAP)

Note: Not all parts of these RFCs are supported. Features are supported based on Zephyr requirements.

Sample Usage

CoAP Server

Note: A CoAP server subsystem is available, the following is for creating a custom server implementation.

To create a CoAP server, resources for the server need to be defined. The .well-known/core resource should be added before all other resources that should be included in the responses of the .well-known/core resource.

```c
static struct coap_resource resources[] = {
    { .get = well_known_core_get,
      .path = COAP_WELL_KNOWN_CORE_PATH,
    },
    { .get = sample_get,
      .post = sample_post,
      .del = sample_del,
      .put = sample_put,
      .path = sample_path
    },
    { }
};
```
An application reads data from the socket and passes the buffer to the CoAP library to parse the message. If the CoAP message is proper, the library uses the buffer along with resources defined above to call the correct callback function to handle the CoAP request from the client. It's the callback function's responsibility to either reply or act according to CoAP request.

```c
coap_packet_parse(&request, data, data_len, options, opt_num);
```

```c
coap_handle_request(&request, resources, options, opt_num, client_addr, client_addr_len);
```

If `CONFIG_COAP_URI_WILDCARD` enabled, server may accept multiple resources using MQTT-like wildcard style:

- the plus symbol represents a single-level wild card in the path;
- the hash symbol represents the multi-level wild card in the path.

```c
static const char *const led_set[] = { "led","+","set", NULL }
static const char *const btn_get[] = { "button","#", NULL }
static const char *const no_wc[] = { "test","+1", NULL }
```

It accepts /led/0/set, led/1234/set, led/any/set, /button/door/1, /test/+1, but returns -ENOENT for /led/1, /test/21, /test/1.

This option is enabled by default, disable it to avoid unexpected behaviour with resource path like '/some_resource/+/#'.

### CoAP Client

**Note:** A CoAP client subsystem is available, the following is for creating a custom client implementation.

If the CoAP client knows about resources in the CoAP server, the client can start prepare CoAP requests and wait for responses. If the client doesn’t know about resources in the CoAP server, it can request resources through the .well-known/core CoAP message.

```c
/* Initialize the CoAP message */
char *path = "test";
struct coap_packet request;
uint8_t data[100];
uint8_t payload[20];

coap_packet_init(&request, data, sizeof(data),
                 1, COAP_TYPE_CON, 8, coap_next_token(),
                 COAP_METHOD_GET, coap_next_id());

/* Append options */
coap_packet_append_option(&request, COAP_OPTION_URI_PATH,
                          path, strlen(path));

/* Append Payload marker if you are going to add payload */
coap_packet_append_payload_marker(&request);

/* Append payload */
coap_packet_append_payload(&request, (uint8_t *)payload,
                           sizeof(payload) - 1);

/* send over sockets */
```

**Testing** There are various ways to test Zephyr CoAP library.
**libcoap**  libcoap implements a lightweight application-protocol for devices that are resource constrained, such as by computing power, RF range, memory, bandwidth, or network packet sizes. Sources can be found here libcoap. libcoap has a script (examples/etsi_coaptest.sh) to test coap-server functionality in Zephyr.

See the net-tools project for more details

The coap-server sample can be built and executed on QEMU as described in *Networking with QEMU*.

Use this command on the host to run the libcoap implementation of the ETSI test cases:

```
sudo ./libcoap/examples/etsi_coaptest.sh -i tap0 2001:db8::1
```

**TTCN3**  Eclipse has TTCN3 based tests to run against CoAP implementations.

Install eclipse-titan and set symbolic links for titan tools

```
sudo apt-get install eclipse-titan
cd /usr/share/titan
sudo ln -s /usr/bin bin
sudo ln /usr/bin/titanver bin
sudo ln -s /usr/bin/mctr_cli bin
sudo ln -s /usr/include/titan include
sudo ln -s /usr/lib/titan lib
export TTCN3_DIR=/usr/share/titan
git clone https://gitlab.eclipse.org/eclipse/titan/titan.misc.git
cd titan.misc
```

Follow the instruction to setup CoAP test suite from here:

- https://gitlab.eclipse.org/eclipse/titan/titan.misc

After the build is complete, the coap-server sample can be built and executed on QEMU as described in *Networking with QEMU*.

Change the client (test suite) and server (Zephyr coap-server sample) addresses in coap.cfg file as per your setup.

Execute the test cases with following command.

```
ttcn3_start coaptests coap.cfg
```

Sample output of ttcn3 tests looks like this.

```
Verdict statistics: 0 none (0.00 %), 10 pass (100.00 %), 0 inconc (0.00 %), 0 fail (0.00 %),
   0 error (0.00 %).
Test execution summary: 10 test cases were executed. Overall verdict: pass
```

**API Reference**

**Related code samples**

**CoAP client**  Use the CoAP library to implement a client that fetches a resource.

**CoAP service**  Use the CoAP server subsystem to register CoAP resources.

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group coap

COAP library.

Defines

COAP_REQUEST_MASK

COAP_VERSION_1

COAP_MAKE_RESPONSE_CODE(class, det)

Utility macro to create a CoAP response code.

Parameters

- **class** – Class of the response code (ex. 2, 4, 5, ...)
- **det** – Detail of the response code

Returns

Response code literal

COAP_CODE_EMPTY

COAP_TOKEN_MAX_LEN

GET_BLOCK_NUM(v)

GET_BLOCK_SIZE(v)

GET_MORE(v)

COAP_WELL_KNOWN_CORE_PATH

This resource should be added before all other resources that should be included in the responses of the .well-known/core resource if is to be used with coap_well_known_core_get.

Typedefs

typedef int (*coap_method_t)(struct coap_resource *resource, struct coap_packet *request, struct sockaddr *addr, socklen_t addr_len)

Type of the callback being called when a resource's method is invoked by the remote entity.

typedef void (*coap_notify_t)(struct coap_resource *resource, struct coap_observer *observer)

Type of the callback being called when a resource's has observers to be informed when an update happens.
typedef int (*coap_reply_t)(const struct coap_packet *response, struct coap_reply *reply, const struct sockaddr *from)

    Helper function to be called when a response matches the a pending request.

    When sending blocks, the callback is only executed when the reply of the last block is received. i.e. it is not called when the code of the reply is ‘continue’ (2.31).

Enums

define coap_option_num

    Set of CoAP packet options we are aware of.

    Users may add options other than these to their packets, provided they know how to format them correctly. The only restriction is that all options must be added to a packet in numeric order.

    Refer to RFC 7252, section 12.2 for more information.

    Values:

enumerator COAP_OPTION_IF_MATCH = 1
    If-Match.

elementer COAP_OPTION_URI_HOST = 3
    Uri-Host.

elementer COAP_OPTION_ETAG = 4
    ETag.

elementer COAP_OPTION_IF_NONE_MATCH = 5
    If-None-Match.

elementer COAP_OPTION_OBSERVE = 6
    Observe (RFC 7641)

elementer COAP_OPTION_URI_PORT = 7
    Uri-Port.

elementer COAP_OPTION_LOCATION_PATH = 8
    Location-Path.

elementer COAP_OPTION_URI_PATH = 11
    Uri-Path.

enumeraturer COAP_OPTION_CONTENT_FORMAT = 12
    Content-Format.

elementer COAP_OPTION_MAX_AGE = 14
    Max-Age.
enumerator COAP_OPTION_URI_QUERY = 15
   Uri-Query.

enumerator COAP_OPTION_ACCEPT = 17
   Accept.

enumerator COAP_OPTION_LOCATION_QUERY = 20
   Location-Query.

enumerator COAP_OPTION_BLOCK2 = 23
   Block2 (RFC 7959)

enumerator COAP_OPTION_BLOCK1 = 27
   Block1 (RFC 7959)

enumerator COAP_OPTION_SIZE2 = 28
   Size2 (RFC 7959)

enumerator COAP_OPTION_PROXY_URI = 35
   Proxy-Uri.

enumerator COAP_OPTION_PROXY_SCHEME = 39
   Proxy-Scheme.

enumerator COAP_OPTION_SIZE1 = 60
   Size1.

enumerator COAP_OPTION_ECHO = 252
   Echo (RFC 9175)

enumerator COAP_OPTION_REQUEST_TAG = 292
   Request-Tag (RFC 9175)

enum coap_method
   Available request methods.
   To be used when creating a request or a response.
   Values:

enumerator COAP_METHOD_GET = 1
   GET.

enumerator COAP_METHOD_POST = 2
   POST.

enumerator COAP_METHOD_PUT = 3
   PUT.
enumerator COAP_METHOD_DELETE = 4
    DELETE.

enumerator COAP_METHOD_FETCH = 5
    FETCH.

enumerator COAP_METHOD_PATCH = 6
    PATCH.

enumerator COAP_METHOD_IPATCH = 7
    IPATCH.

enum coap_msgtype
    CoAP packets may be of one of these types.
    Values:
    enumerator COAP_TYPE_CON = 0
        Confirmable message.
        The packet is a request or response the destination end-point must acknowledge.
    enumerator COAP_TYPE_NON_CON = 1
        Non-confirmable message.
        The packet is a request or response that doesn’t require acknowledgements.
    enumerator COAP_TYPE_ACK = 2
        Acknowledge.
        Response to a confirmable message.
    enumerator COAP_TYPE_RESET = 3
        Reset.
        Rejecting a packet for any reason is done by sending a message of this type.

enum coap_response_code
    Set of response codes available for a response packet.
    To be used when creating a response.
    Values:
    enumerator COAP_RESPONSE_CODE_OK = ((2 « 5) | (0))
        2.00 - OK
    enumerator COAP_RESPONSE_CODE.Created = ((2 « 5) | (1))
        2.01 - Created
    enumerator COAP_RESPONSE_CODE.DELETED = ((2 « 5) | (2))
        2.02 - Deleted
enumerator COAP_RESPONSE_CODE_VALID = ((2 « 5) | (3))
  2.03 - Valid

dentifier COAP_RESPONSE_CODE_CHANGED = ((2 « 5) | (4))
  2.04 - Changed

dentifier COAP_RESPONSE_CODE_CONTENT = ((2 « 5) | (5))
  2.05 - Content

dentifier COAP_RESPONSE_CODE_CONTINUE = ((2 « 5) | (31))
  2.31 - Continue

dentifier COAP_RESPONSE_CODE_BAD_REQUEST = ((4 « 5) | (0))
  4.00 - Bad Request

dentifier COAP_RESPONSE_CODE_UNAUTHORIZED = ((4 « 5) | (1))
  4.01 - Unauthorized

dentifier COAP_RESPONSE_CODE_BAD_OPTION = ((4 « 5) | (2))
  4.02 - Bad Option

dentifier COAP_RESPONSE_CODE_FORBIDDEN = ((4 « 5) | (3))
  4.03 - Forbidden

dentifier COAP_RESPONSE_CODE_NOT_FOUND = ((4 « 5) | (4))
  4.04 - Not Found

dentifier COAP_RESPONSE_CODE_NOT_ALLOWED = ((4 « 5) | (5))
  4.05 - Method Not Allowed

dentifier COAP_RESPONSE_CODE_NOT_ACCEPTABLE = ((4 « 5) | (6))
  4.06 - Not Acceptable

dentifier COAP_RESPONSE_CODE_INCOMPLETE = ((4 « 5) | (8))
  4.08 - Request Entity Incomplete

dentifier COAP_RESPONSE_CODE_CONFLICT = ((4 « 5) | (9))
  4.12 - Precondition Failed

dentifier COAP_RESPONSE_CODE_PRECONDITION_FAILED = ((4 « 5) | (12))
  4.12 - Precondition Failed

dentifier COAP_RESPONSE_CODE_REQUEST_TOO_LARGE = ((4 « 5) | (13))
  4.13 - Request Entity Too Large

dentifier COAP_RESPONSE_CODE_UNSUPPORTEDCONTENT_FORMAT = ((4 « 5) | (15))
  4.15 - Unsupported Content-Format
enumerator COAP_RESPONSE_CODE_UNPROCESSABLE_ENTITY = ((4 « 5) | (22))
    4.22 - Unprocessable Entity

evernemerator COAP_RESPONSE_CODE_TOO_MANY_REQUESTS = ((4 « 5) | (29))
    4.29 - Too Many Requests

evernemerator COAP_RESPONSE_CODE_INTERNAL_ERROR = ((5 « 5) | (0))
    5.00 - Internal Server Error

evernemerator COAP_RESPONSE_CODE_NOT_IMPLEMENTED = ((5 « 5) | (1))
    5.01 - Not Implemented

evernemerator COAP_RESPONSE_CODE_BAD_GATEWAY = ((5 « 5) | (2))
    5.02 - Bad Gateway

evernemerator COAP_RESPONSE_CODE_SERVICE_UNAVAILABLE = ((5 « 5) | (3))
    5.03 - Service Unavailable

evernemerator COAP_RESPONSE_CODE_GATEWAY_TIMEOUT = ((5 « 5) | (4))
    5.04 - Gateway Timeout

evernemerator COAP_RESPONSE_CODE_PROXYING_NOT_SUPPORTED = ((5 « 5) | (5))
    5.05 - Proxying Not Supported

class coap_content_format
    Set of Content-Format option values for CoAP.
    To be used when encoding or decoding a Content-Format option.
    Values:

    enumerator COAP_CONTENT_FORMAT_TEXT_PLAIN = 0
        text/plain; charset=utf-8

    enumerator COAP_CONTENT_FORMAT_APP_LINK_FORMAT = 40
        application/link-format

    enumerator COAP_CONTENT_FORMAT_APP_XML = 41
        application/xml

    enumerator COAP_CONTENT_FORMAT_APP_OCTET_STREAM = 42
        application/octet-stream

    enumerator COAP_CONTENT_FORMAT_APP_EXI = 47
        application/exi

    enumerator COAP_CONTENT_FORMAT_APP_JSON = 50
        application/json

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enumerator COAP_CONTENT_FORMAT_APP_JSON_PATCH_JSON = 51
    application/json-patch+json

enumerator COAP_CONTENT_FORMAT_APP_MERGE_PATCH_JSON = 52
    application/merge-patch+json

enumerator COAP_CONTENT_FORMAT_APP_CBOR = 60
    application/cbor

enum coap_block_size
    Represents the size of each block that will be transferred using block-wise transfers [RFC7959]:
    Each entry maps directly to the value that is used in the wire.
    Values:

enumerator COAP_BLOCK_16         16-byte block size
enumerator COAP_BLOCK_32         32-byte block size
enumerator COAP_BLOCK_64         64-byte block size
enumerator COAP_BLOCK_128        128-byte block size
enumerator COAP_BLOCK_256        256-byte block size
enumerator COAP_BLOCK_512        512-byte block size
enumerator COAP_BLOCK_1024       1024-byte block size

Functions

uint8_t coap_header_get_version(const struct coap_packet *cpkt)
    Returns the version present in a CoAP packet.

Parameters
    • cpkt – CoAP packet representation

Returns
    the CoAP version in packet
uint8_t coap_header_get_type(const struct coap_packet *cpkt)

Returns the type of the CoAP packet.

Parameters
- cpkt – CoAP packet representation

Returns
the type of the packet

uint8_t coap_header_get_token(const struct coap_packet *cpkt, uint8_t *token)

Returns the token (if any) in the CoAP packet.

Parameters
- cpkt – CoAP packet representation
- token – Where to store the token, must point to a buffer containing at least COAP_TOKEN_MAX_LEN bytes

Returns
Token length in the CoAP packet (0 - COAP_TOKEN_MAX_LEN).

uint8_t coap_header_get_code(const struct coap_packet *cpkt)

Returns the code of the CoAP packet.

Parameters
- cpkt – CoAP packet representation

Returns
the code present in the packet

int coap_header_set_code(const struct coap_packet *cpkt, uint8_t code)

Modifies the code of the CoAP packet.

Parameters
- cpkt – CoAP packet representation
- code – CoAP code

Returns
0 on success, -EINVAL on failure

uint16_t coap_header_get_id(const struct coap_packet *cpkt)

Returns the message id associated with the CoAP packet.

Parameters
- cpkt – CoAP packet representation

Returns
the message id present in the packet

const uint8_t *coap_packet_get_payload(const struct coap_packet *cpkt, uint16_t *len)

Returns the data pointer and length of the CoAP packet.

Parameters
- cpkt – CoAP packet representation
- len – Total length of CoAP payload

Returns
data pointer and length if payload exists NULL pointer and length set to 0 in case there is no payload

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bool coap_uri_path_match(const char *const *path, struct coap_option *options, uint8_t opt_num)

Verify if CoAP URI path matches with provided options.

Parameters

• path – Null-terminated array of strings.
• options – Parsed options from coap_packet_parse()
• opt_num – Number of options

Returns

true if the CoAP URI path matches, false otherwise.

int coap_packet_parse(struct coap_packet *cpkt, uint8_t *data, uint16_t len, struct coap_option *options, uint8_t opt_num)

Parses the CoAP packet in data, validating it and initializing cpkt. 

Data must remain valid while cpkt is used.

Parameters

• cpkt – Packet to be initialized from received data.
• data – Data containing a CoAP packet, its data pointer is positioned on the start of the CoAP packet.
• len – Length of the data
• options – Parse options and cache its details.
• opt_num – Number of options

Return values

• 0 – in case of success.
• -EINVAL – in case of invalid input args.
• -EBADMSG – in case of malformed coap packet header.
• -EILSEQ – in case of malformed coap options.

int coap_packet_set_path(struct coap_packet *cpkt, const char *path)

Parses provided coap path (with/without query) or query and appends that as options to the cpkt.

Parameters

• cpkt – Packet to append path and query options for.
• path – Null-terminated string of coap path, query or both.

Return values

0 – in case of success or negative in case of error.

int coap_packet_init(struct coap_packet *cpkt, uint8_t *data, uint16_t max_len, uint8_t ver, uint8_t type, uint8_t token_len, const uint8_t *token, uint8_t code, uint16_t id)

Creates a new CoAP Packet from input data.

Parameters

• cpkt – New packet to be initialized using the storage from data.
• data – Data that will contain a CoAP packet information
• max_len – Maximum allowable length of data
• ver – CoAP header version
- **type** – CoAP header type
- **token_len** – CoAP header token length
- **token** – CoAP header token
- **code** – CoAP header code
- **id** – CoAP header message id

**Returns**

0 in case of success or negative in case of error.

```c
int coap_ack_init(struct coap_packet *cpkt, const struct coap_packet *req, uint8_t *data, uint16_t max_len, uint8_t code)
```

Create a new CoAP Acknowledgment message for given request.

This function works like `coap_packet_init`, filling CoAP header type, CoAP header token, and CoAP header message id fields according to acknowledgment rules.

**Parameters**

- **cpkt** – New packet to be initialized using the storage from `data`.
- **req** – CoAP request packet that is being acknowledged
- **data** – Data that will contain a CoAP packet information
- **max_len** – Maximum allowable length of data
- **code** – CoAP header code

**Returns**

0 in case of success or negative in case of error.

```c
uint8_t *coap_next_token(void)
```

Returns a randomly generated array of 8 bytes, that can be used as a message's token.

**Returns**

a 8-byte pseudo-random token.

```c
uint16_t coap_next_id(void)
```

Helper to generate message ids.

**Returns**

a new message id

```c
int coap_find_options(const struct coap_packet *cpkt, uint16_t code, struct coap_option *options, uint16_t veclen)
```

Return the values associated with the option of value `code`.

**Parameters**

- **cpkt** – CoAP packet representation
- **code** – Option number to look for
- **options** – Array of `coap_option` where to store the value of the options found
- **veclen** – Number of elements in the options array

**Returns**

The number of options found in packet matching code, negative on error.

```c
int coap_packet_append_option(struct coap_packet *cpkt, uint16_t code, const uint8_t *value, uint16_t len)
```

Appends an option to the packet.
Note: options can be added out of numeric order of their codes. But it’s more efficient to add them in order.

**Parameters**

- `cpkt` – Packet to be updated
- `code` – Option code to add to the packet, see `coap_option_num`
- `value` – Pointer to the value of the option, will be copied to the packet
- `len` – Size of the data to be added

**Returns**

0 in case of success or negative in case of error.

```c
int coap_packet_remove_option(struct coap_packet *cpkt, uint16_t code)
```

Remove an option from the packet.

**Parameters**

- `cpkt` – Packet to be updated
- `code` – Option code to remove from the packet, see `coap_option_num`

**Returns**

0 in case of success or negative in case of error.

```c
unsigned int coap_option_value_to_int(const struct coap_option *option)
```

Converts an option to its integer representation.

Assumes that the number is encoded in the network byte order in the option.

**Parameters**

- `option` – Pointer to the option value, retrieved by `coap_find_options()`

**Returns**

The integer representation of the option

```c
int coap_append_option_int(struct coap_packet *cpkt, uint16_t code, unsigned int val)
```

Appends an integer value option to the packet.

The option must be added in numeric order of their codes, and the least amount of bytes will be used to encode the value.

**Parameters**

- `cpkt` – Packet to be updated
- `code` – Option code to add to the packet, see `coap_option_num`
- `val` – Integer value to be added

**Returns**

0 in case of success or negative in case of error.

```c
int coap_packet_append_payload_marker(struct coap_packet *cpkt)
```

Append payload marker to CoAP packet.

**Parameters**

- `cpkt` – Packet to append the payload marker (0xFF)

**Returns**

0 in case of success or negative in case of error.

```c
int coap_packet_append_payload(struct coap_packet *cpkt, const uint8_t *payload, uint16_t payload_len)
```

Append payload to CoAP packet.
Parameters

- `pkt` – Packet to append the payload
- `payload` – CoAP packet payload
- `payload_len` – CoAP packet payload len

Returns

0 in case of success or negative in case of error.

```c
bool coap_packet_is_request(const struct coap_packet *pkt);
```

Check if a CoAP packet is a CoAP request.

Parameters

- `pkt` – Packet to be checked.

Returns

true if the packet is a request, false otherwise.

```c
int coap_handle_request_len(struct coap_packet *pkt, struct coap_resource *resources, size_t resources_len, struct coap_option *options, uint8_t opt_num, struct sockaddr *addr, socklen_t addr_len);
```

When a request is received, call the appropriate methods of the matching resources.

Parameters

- `pkt` – Packet received
- `resources` – Array of known resources
- `resources_len` – Number of resources in the array
- `options` – Parsed options from `coap_packet_parse()`
- `opt_num` – Number of options
- `addr` – Peer address
- `addr_len` – Peer address length

Return values

- `>= 0` in case of success.
- `-ENOTSUP` – in case of invalid request code.
- `-EPERM` – in case resource handler is not implemented.
- `-ENOENT` – in case the resource is not found.

```c
int coap_handle_request(struct coap_packet *pkt, struct coap_resource *resources, coap_option *options, uint8_t opt_num, struct sockaddr *addr, socklen_t addr_len);
```

When a request is received, call the appropriate methods of the matching resources.

Parameters

- `pkt` – Packet received
- `resources` – Array of known resources (terminated with empty resource)
- `options` – Parsed options from `coap_packet_parse()`
- `opt_num` – Number of options
- `addr` – Peer address
- `addr_len` – Peer address length

Return values
• >= – 0 in case of success.
• -ENOTSUP – in case of invalid request code.
• -EPERM – in case resource handler is not implemented.
• -ENOENT – in case the resource is not found.

static inline uint16_t coap_block_size_to_bytes(enum coap_block_size block_size)

Helper for converting the enumeration to the size expressed in bytes.

Parameters
• block_size – The block size to be converted

Returns
The size in bytes that the block_size represents

int coap_block_transfer_init(struct coap_block_context *ctx, enum coap_block_size block_size, size_t total_size)

Initializes the context of a block-wise transfer.

Parameters
• ctx – The context to be initialized
• block_size – The size of the block
• total_size – The total size of the transfer, if known

Returns
0 in case of success or negative in case of error.

int coap_append_descriptive_block_option(struct coap_packet *cpkt, struct coap_block_context *ctx)

Append BLOCK1 or BLOCK2 option to the packet.
If the CoAP packet is a request then BLOCK1 is appended otherwise BLOCK2 is appended.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the block option

Returns
0 in case of success or negative in case of error.

bool coap_has_descriptive_block_option(struct coap_packet *cpkt)

Check if a descriptive block option is set in the packet.
If the CoAP packet is a request then an available BLOCK1 option would be checked otherwise a BLOCK2 option would be checked.

Parameters
• cpkt – Packet to be checked.

Returns
true if the corresponding block option is set, false otherwise.

int coap_remove_descriptive_block_option(struct coap_packet *cpkt)

Remove BLOCK1 or BLOCK2 option from the packet.
If the CoAP packet is a request then BLOCK1 is removed otherwise BLOCK2 is removed.

Parameters
• cpkt – Packet to be updated.
Returns
0 in case of success or negative in case of error.

int coap_append_block1_option(struct coap_packet *cpkt, struct coap_block_context *ctx)
Append BLOCK1 option to the packet.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the Block1 option

Returns
0 in case of success or negative in case of error.

int coap_append_block2_option(struct coap_packet *cpkt, struct coap_block_context *ctx)
Append BLOCK2 option to the packet.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the Block2 option

Returns
0 in case of success or negative in case of error.

int coap_append_size1_option(struct coap_packet *cpkt, struct coap_block_context *ctx)
Append SIZE1 option to the packet.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the Size1 option

Returns
0 in case of success or negative in case of error.

int coap_append_size2_option(struct coap_packet *cpkt, struct coap_block_context *ctx)
Append SIZE2 option to the packet.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the Size2 option

Returns
0 in case of success or negative in case of error.

int coap_get_option_int(const struct coap_packet *cpkt, uint16_t code)
Get the integer representation of a CoAP option.

Parameters
• cpkt – Packet to be inspected
• code – CoAP option code

Returns
Integer value >= 0 in case of success or negative in case of error.
int coap_get_block1_option(const struct coap_packet *cpkt, bool *has_more, uint8_t *block_number)

Get the block size, more flag and block number from the CoAP block1 option.

Parameters
• cpkt – Packet to be inspected
• has_more – Is set to the value of the more flag
• block_number – Is set to the number of the block

Returns
Integer value of the block size in case of success or negative in case of error.

int coap_get_block2_option(const struct coap_packet *cpkt, uint8_t *block_number)

Get values from CoAP block2 option.
Decode block number and block size from option. Ignore the has_more flag as it should always be zero on queries.

Parameters
• cpkt – Packet to be inspected
• block_number – Is set to the number of the block

Returns
Integer value of the block size in case of success or negative in case of error.

int coap_update_from_block(const struct coap_packet *cpkt, struct coap_block_context *ctx)

Retrieves BLOCK{1,2} and SIZE{1,2} from cpkt and updates ctx accordingly.

Parameters
• cpkt – Packet in which to look for block-wise transfers options
• ctx – Block context to be updated

Returns
0 in case of success or negative in case of error.

int coap_next_block_for_option(const struct coap_packet *cpkt, struct coap_block_context *ctx, enum coap_option_num option)

Updates ctx according to option set in cpkt so after this is called the current entry indicates the correct offset in the body of data being transferred.

Parameters
• cpkt – Packet in which to look for block-wise transfers options
• ctx – Block context to be updated
• option – Either COAP_OPTION_BLOCK1 or COAP_OPTION_BLOCK2

Returns
The offset in the block-wise transfer, 0 if the transfer has finished or a negative value in case of an error.

size_t coap_next_block(const struct coap_packet *cpkt, struct coap_block_context *ctx)

Updates ctx so after this is called the current entry indicates the correct offset in the body of data being transferred.

Parameters
• cpkt – Packet in which to look for block-wise transfers options
• ctx – Block context to be updated
Returns
The offset in the block-wise transfer, 0 if the transfer has finished.

```c
void coap_observer_init(struct coap_observer *observer, const struct coap_packet *request, const struct sockaddr *addr)
```

Indicates that the remote device referenced by `addr`, with `request`, wants to observe a resource.

**Parameters**
- `observer` – Observer to be initialized
- `request` – Request on which the observer will be based
- `addr` – Address of the remote device

```c
bool coap_register_observer(struct coap_resource *resource, struct coap_observer *observer)
```

After the observer is initialized, associate the observer with an resource.

**Parameters**
- `resource` – Resource to add an observer
- `observer` – Observer to be added

**Returns**
true if this is the first observer added to this resource.

```c
bool coap_remove_observer(struct coap_resource *resource, struct coap_observer *observer)
```

Remove this observer from the list of registered observers of that resource.

**Parameters**
- `resource` – Resource in which to remove the observer
- `observer` – Observer to be removed

**Returns**
true if the observer was found and removed.

```c
struct coap_observer *coap_find_observer(struct coap_observer *observers, size_t len, const struct sockaddr *addr, const uint8_t *token, uint8_t token_len)
```

Returns the observer that matches address `addr` and has token `token`.

**Parameters**
- `observers` – Pointer to the array of observers
- `len` – Size of the array of observers
- `addr` – Address of the endpoint observing a resource
- `token` – Pointer to the token
- `token_len` – Length of valid bytes in the token

**Returns**
A pointer to a observer if a match is found, NULL otherwise.

```c
struct coap_observer *coap_find_observer_by_addr(struct coap_observer *observers, size_t len, const struct sockaddr *addr)
```

Returns the observer that matches address `addr`. 

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Note: The function `coap_find_observer()` should be preferred if both the observer's address and token are known.

### Parameters
- `observers` – Pointer to the array of observers
- `len` – Size of the array of observers
- `addr` – Address of the endpoint observing a resource

### Returns
A pointer to a observer if a match is found, NULL otherwise.

```c
struct coap_observer *coap_find_observer_by_token(struct coap_observer *observers, size_t len, const uint8_t *token, uint8_t token_len)
```

Returns the observer that has token `token`.

Note: The function `coap_find_observer()` should be preferred if both the observer's address and token are known.

### Parameters
- `observers` – Pointer to the array of observers
- `len` – Size of the array of observers
- `token` – Pointer to the token
- `token_len` – Length of valid bytes in the token

### Returns
A pointer to a observer if a match is found, NULL otherwise.

```c
struct coap_observer *coap_observer_next_unused(struct coap_observer *observers, size_t len)
```

Returns the next available observer representation.

### Parameters
- `observers` – Pointer to the array of observers
- `len` – Size of the array of observers

### Returns
A pointer to a observer if there's an available observer, NULL otherwise.

```c
void coap_reply_init(struct coap_reply *reply, const struct coap_packet *request)
```

Indicates that a reply is expected for `request`.

### Parameters
- `reply` – Reply structure to be initialized
- `request` – Request from which `reply` will be based

```c
int coap_pending_init(struct coap_pending *pending, const struct coap_packet *request, const struct sockaddr *addr, const struct coap_transmission_parameters *params)
```
Initialize a pending request with a request.

The request's fields are copied into the pending struct, so request doesn't have to live
for as long as the pending struct lives, but “data” that needs to live for at least that long.

**Parameters**

- **pending** – Structure representing the waiting for a confirmation message,
  initialized with data from request
- **request** – Message waiting for confirmation
- **addr** – Address to send the retransmission
- **params** – Pointer to the CoAP transmission parameters struct, or NULL to
  use default values

**Returns**

0 in case of success or negative in case of error.

```c
struct coap_pending *coap_pending_next_unused(struct coap_pending *pendings, size_t len)
```

Returns the next available pending struct, that can be used to track the retransmission
status of a request.

**Parameters**

- **pendings** – Pointer to the array of coap_pending structures
- **len** – Size of the array of coap_pending structures

**Returns**

pointer to a free coap_pending structure, NULL in case none could be found.

```c
struct coap_reply *coap_reply_next_unused(struct coap_reply *replies, size_t len)
```

Returns the next available reply struct, so it can be used to track replies and notifications
received.

**Parameters**

- **replies** – Pointer to the array of coap_reply structures
- **len** – Size of the array of coap_reply structures

**Returns**

pointer to a free coap_reply structure, NULL in case none could be found.

```c
struct coap_pending *coap_pending_received(const struct coap_packet *response, struct coap_pending *pendings, size_t len)
```

After a response is received, returns if there is any matching pending request exits.

User has to clear all pending retransmissions related to that response by calling
coap_pending_clear().

**Parameters**

- **response** – The received response
- **pendings** – Pointer to the array of coap_reply structures
- **len** – Size of the array of coap_reply structures

**Returns**

pointer to the associated coap_pending structure, NULL in case none could
be found.
After a response is received, call coap_reply_t handler registered in coap_reply structure.

**Parameters**
- `response` – A response received
- `from` – Address from which the response was received
- `replies` – Pointer to the array of coap_reply structures
- `len` – Size of the array of coap_reply structures

**Returns**
Pointer to the reply matching the packet received, NULL if none could be found.

struct coap_pending *coap_pending_next_to_expire(struct coap_pending *pendings, size_t len)

Returns the next pending about to expire, pending->timeout informs how many ms to next expiration.

**Parameters**
- `pendings` – Pointer to the array of coap_pending structures
- `len` – Size of the array of coap_pending structures

**Returns**
The next coap_pending to expire, NULL if none is about to expire.

bool coap_pending_cycle(struct coap_pending *pending)

After a request is sent, user may want to cycle the pending retransmission so the timeout is updated.

**Parameters**
- `pending` – Pending representation to have its timeout updated

**Returns**
false if this is the last retransmission.

void coap_pending_clear(struct coap_pending *pending)

Cancels the pending retransmission, so it again becomes available.

**Parameters**
- `pending` – Pending representation to be canceled

void coap_pendings_clear(struct coap_pending *pendings, size_t len)

Cancels all pending retransmissions, so they become available again.

**Parameters**
- `pendings` – Pointer to the array of coap_pending structures
- `len` – Size of the array of coap_pending structures

size_t coap_pendings_count(struct coap_pending *pendings, size_t len)

Count number of pending requests.

**Parameters**
- `len` – Number of elements in array.
- `pendings` – Array of pending requests.
Returns
count of elements where timeout is not zero.

void coap_reply_clear(struct coap_reply *reply)
Cancels awaiting for this reply, so it becomes available again.
User responsibility to free the memory associated with data.

Parameters
• reply – The reply to be canceled

void coap_replies_clear(struct coap_reply *replies, size_t len)
Cancels all replies, so they become available again.

Parameters
• replies – Pointer to the array of coap_reply structures
• len – Size of the array of coap_reply structures

int coap_resource_notify(struct coap_resource *resource)
Indicates that this resource was updated and that the notify callback should be called for every registered observer.

Parameters
• resource – Resource that was updated

Returns
0 in case of success or negative in case of error.

bool coap_request_is_observe(const struct coap_packet *request)
Returns if this request is enabling observing a resource.

Parameters
• request – Request to be checked

Returns
True if the request is enabling observing a resource, False otherwise

struct coap_transmission_parameters coap_get_transmission_parameters(void)
Get currently active CoAP transmission parameters.

Returns
CoAP transmission parameters structure.

void coap_set_transmission_parameters(const struct coap_transmission_parameters *params)
Set CoAP transmission parameters.

Parameters
• params – Pointer to the transmission parameters structure.

int coap_well_known_core_get(struct coap_resource *resource, const struct coap_packet *request, struct coap_packet *response, uint8_t *data, uint16_t data_len)
Build a CoAP response for a .well-known/core CoAP request.

Parameters
• resource – Array of known resources, terminated with an empty resource
• request – A pointer to the .well-known/core CoAP request
• response – A pointer to a CoAP response, will be initialized
• **data** – A data pointer to be used to build the CoAP response
• **data_len** – The maximum length of the data buffer

**Returns**
0 in case of success or negative in case of error.

```c
int coap_well_known_core_get_len(struct coap_resource *resources, size_t resources_len, const struct coap_packet *request, struct coap_packet *response, uint8_t *data, uint16_t data_len)
```

Build a CoAP response for a `.well-known/core` CoAP request.

**Parameters**
• **resources** – Array of known resources
• **resources_len** – Number of resources in the array
• **request** – A pointer to the `.well-known/core` CoAP request
• **response** – A pointer to a CoAP response, will be initialized
• **data** – A data pointer to be used to build the CoAP response
• **data_len** – The maximum length of the data buffer

**Returns**
0 in case of success or negative in case of error.

```c
struct coap_resource
#include <coap.h> Description of CoAP resource.
CoAP servers often want to register resources, so that clients can act on them, by fetching their state or requesting updates to them.

**Public Members**

```c
coap_method_t get
```
Which function to be called for each CoAP method.

```c
struct coap_observer
#include <coap.h> Represents a remote device that is observing a local resource.
```

```c
struct coap_packet
#include <coap.h> Representation of a CoAP Packet.
```

**Public Members**

```c
uint8_t *data
User allocated buffer.
```

```c
uint16_t offset
CoAP lib maintains offset while adding data.
```

```c
uint16_t max_len
Max CoAP packet data length.
```
uint8_t hdr_len
    CoAP header length.

uint16_t opt_len
    Total options length (delta + len + value)

uint16_t delta
    Used for delta calculation in CoAP packet.

struct coap_option
    #include <coap.h> Representation of a CoAP option.

    Public Members

    uint16_t delta
        Option delta.

    uint8_t len
        Option length.

    uint8_t value[12]
        Option value.

struct coap_transmission_parameters
    #include <coap.h> CoAP transmission parameters.

    Public Members

    uint32_t ack_timeout
        Initial ACK timeout.
        Value is used as a base value to retry pending CoAP packets.

    uint16_t coap_backoff_percent
        Set CoAP retry backoff factor.
        A value of 200 means a factor of 2.0.

    uint8_t max_retransmission
        Maximum number of retransmissions.

struct coap_pending
    #include <coap.h> Represents a request awaiting for an acknowledgment (ACK).

    Public Members

6.3. Networking
struct sockaddr addr
    Remote address.

int64_t t0
    Time when the request was sent.

uint32_t timeout
    Timeout in ms.

uint16_t id
    Message id.

uint8_t *data
    User allocated buffer.

uint16_t len
    Length of the CoAP packet.

uint8_t retries
    Number of times the request has been sent.

struct coap_transmission_parameters params
    Transmission parameters.

struct coap_reply
    #include <coap.h> Represents the handler for the reply of a request, it is also used when observing resources.

struct coap_block_context
    #include <coap.h> Represents the current state of a block-wise transaction.

struct coap_core_metadata
    #include <coap_link_format.h> In case you want to add attributes to the resources included in the ‘well-known/core’ “virtual” resource, the ‘user_data’ field should point to a valid coap_core_metadata structure.

CoAP client

- Overview
- Sample Usage
- API Reference

Overview  The CoAP client library allows application to send CoAP requests and parse CoAP responses. The library can be enabled with CONFIG_COAP_CLIENT Kconfig option. The application is notified about the response via a callback that is provided to the API in the request. The CoAP client handles the communication over sockets. As the CoAP client doesn’t create socket it is using, the application is responsible for creating the socket. Plain UDP or DTLS sockets are supported.
**Sample Usage** The following is an example of a CoAP client initialization and request sending:

```c
static struct coap_client;
struct coap_client_request req = { 0 };

coap_client_init(&client, NULL);
req.method = COAP_METHOD_GET;
req.confirmable = true;
req.path = "test";
req.fmt = COAP_CONTENT_FORMAT_TEXT_PLAIN;
req.cb = response_cb;
req.payload = NULL;
req.len = 0;
/* Sock is a file descriptor referencing a socket, address is the sockaddr struct for the
destination address of the request or NULL if the socket is already connected. */
ret = coap_client_req(&client, sock, &address, &req, -1);
```

Before any requests can be sent, the CoAP client needs to be initialized. After initialization, the application can send a CoAP request and wait for the response. Currently only one request can be sent for a single CoAP client at a time. There can be multiple CoAP clients.

The callback provided in the callback will be called in following cases:

- There is a response for the request
- The request failed for some reason

The callback contains a flag `last_block`, which indicates if there is more data to come in the response and means that the current response is part of a blockwise transfer. When the `last_block` is set to true, the response is finished and the client is ready for the next request after returning from the callback.

If the server responds to the request, the library provides the response to the application through the response callback registered in the request structure. As the response can be a blockwise transfer and the client calls the callback once per each block, the application should be to process all of the blocks to be able to process the response.

The following is an example of a very simple response handling function:

```c
void response_cb(int16_t code, size_t offset, const uint8_t *payload, size_t len,
                 bool last_block, void *user_data)
{
    if (code >= 0) {
        LOG_INF("CoAP response from server %d", code);
        if (last_block) {
            LOG_INF("Last packet received");
        }
    } else {
        LOG_ERR("Error in sending request %d", code);
    }
}
```

**API Reference**

*group coap_client*

CoAP client API.

**Defines**
typedef void (\*coap_client_response_cb_t\)(int16_t result_code, size_t offset, const uint8_t \*payload, size_t len, bool last_block, void \*user_data)

Callback for CoAP request.

This callback is called for responses to CoAP client requests. It is used to indicate errors, response codes from server or to deliver payload. Blockwise transfers cause this callback to be called sequentially with increasing payload offset and only partial content in buffer pointed by payload parameter.

**Param result_code**
Result code of the response. Negative if there was a failure in send.

**coap_response_code** for positive.

**Param offset**
Payload offset from the beginning of a blockwise transfer.

**Param payload**
Buffer containing the payload from the response. NULL for empty payload.

**Param len**
Size of the payload.

**Param last_block**
Indicates the last block of the response.

**Param user_data**
User provided context.

### Functions

**int coap_client_init(struct coap_client *client, const char *info)**
Initialize the CoAP client.

**Parameters**

- **info** – [in] Name for the receiving thread of the client. Setting this NULL will result as default name of “coap_client”.

**Returns**

int Zero on success, otherwise a negative error code.

**int coap_client_req(struct coap_client *client, int sock, const struct sockaddr *addr,**

**struct coap_client_request *req,**

**struct coap_transmission_parameters *params)**

Send CoAP request.

Operation is handled asynchronously using a background thread. If the socket isn’t connected to a destination address, user must provide a destination address, otherwise the address should be set as NULL. Once the callback is called with last block set as true, socket can be closed or used for another query.

**Parameters**

- **client** – Client instance.
• **sock** – Open socket file descriptor.
• **addr** – the destination address of the request, NULL if socket is already connected.
• **req** – CoAP request structure
• **params** – Pointer to transmission parameters structure or NULL to use default values.

**Returns**
zero when operation started successfully or negative error code otherwise.

```c
struct coap_client_request
#include <coap_client.h> Representation of a CoAP client request.
```

**Public Members**

```c
eenum coap_method method
  Method of the request.

bool confirmable
  CoAP Confirmable/Non-confirmable message.

const char *path
  Path of the requested resource.

eenum coap_content_format fmt
  Content format to be used.

uint8_t *payload
  User allocated buffer for send request.

size_t len
  Length of the payload.

coop_client_response_cb_t cb
  Callback when response received.

struct coap_client_option *options
  Extra options to be added to request.

uint8_t num_options
  Number of extra options.

void *user_data
  User provided context.
```

```c
#include <coap_client.h> Representation of extra options for the CoAP client request.
```
CoAP server

- **Overview**
- **Setup**
- **Sample Usage**
- **Observable resources**
- **CoAP Events**
- **CoRE Link Format**
- **API Reference**

**Overview**  Zephyr comes with a batteries-included CoAP server, which uses services to listen for CoAP requests. The CoAP services handle communication over sockets and pass requests to registered CoAP resources.

**Setup**  Some configuration is required to make sure services can be started using the CoAP server. The `CONFIG_COAP_SERVER` option should be enabled in your project:

```makefile
Listing 1: prj.conf
CONFIG_COAP_SERVER=y
```

All services are added to a predefined linker section and all resources for each service also get their respective linker sections. If you would have a service `my_service` it has to be prefixed with `coap_resource_` and added to a linker file:

```makefile
Listing 2: sections-ram.ld
#include <zephyr/linker/iterable_sections.h>
ITERABLE_SECTION_RAM(coap_resource_my_service, 4)
```

Add this linker file to your application using CMake:

```makefile
Listing 3: CMakeLists.txt
zephyr_linker_sources(DATA_SECTIONS sections-ram.ld)
```

You can now define your service as part of the application:

```c
Listing 4: service.c
#include <zephyr/net/coap_service.h>
static const uint16_t my_service_port = 5683;

COAP_SERVICE_DEFINE(my_service, "0.0.0.0", &my_service_port, COAP_SERVICE_AUTOSTART);
```

**Note:** Services defined with the `COAP_SERVICE_AUTOSTART` flag will be started together with the CoAP server thread. Services can be manually started and stopped with `coap_service_start` and `coap_service_stop` respectively.

**Sample Usage**  The following is an example of a CoAP resource registered with our service:
#include <zephyr/net/coap_service.h>

```c
static int my_get(struct coap_resource *resource, struct coap_packet *request, 
                  struct sockaddr *addr, socklen_t addr_len)
{
    static const char *msg = "Hello, world!";
    uint8_t data[CONFIG_COAP_SERVER_MESSAGE_SIZE];
    struct coap_packet response;
    uint16_t id;
    uint8_t token[COAP_TOKEN_MAX_LEN];
    uint8_t tkl, type;

    type = coap_header_get_type(request);
    id = coap_header_get_id(request);
    tkl = coap_header_get_token(request, token);

    /* Determine response type */
    type = (type == COAP_TYPE_CON) ? COAP_TYPE_ACK : COAP_TYPE_NON_CON;

    coap_packet_init(&response, data, sizeof(data), COAP_VERSION_1, type, tkl, token, 
                     COAP_RESPONSE_CODE_CONTENT, id);

    /* Set content format */
    coap_append_option_int(&response, COAP_OPTION_CONTENT_FORMAT, 
                           COAP_CONTENT_FORMAT_TEXT_PLAIN);

    /* Append payload */
    coap_packet_append_payload_marker(&response);
    coap_packet_append_payload(&response, (uint8_t *)msg, sizeof(msg));

    /* Send to response back to the client */
    return coap_resource_send(resource, &response, addr, addr_len, NULL);
}

static int my_put(struct coap_resource *resource, struct coap_packet *request, 
                   struct sockaddr *addr, socklen_t addr_len)
{
    /* ... Handle the incoming request ... */

    /* Return a CoAP response code as a shortcut for an empty ACK message */
    return COAP_RESPONSE_CODE_CHANGED;
}

static const char * const my_resource_path[] = { "test", NULL };

COAP_RESOURCE_DEFINE(my_resource, my_service, {
    .path = my_resource_path,
    .get = my_get,
    .put = my_put,
});```

**Note:** As demonstrated in the example above, a CoAP resource handler can return response codes to let the server respond with an empty ACK response.

**Observable resources** The CoAP server provides logic for parsing observe requests and stores these using the runtime data of CoAP services. An example using a temperature sensor can look like:
```c
#include <zephyr/kernel.h>
#include <zephyr/drivers/sensor.h>
#include <zephyr/net/coap_service.h>

static void notifyObservers(struct k_work *work);
K_WORK_DELAYABLE_DEFINE(temp_work, notifyObservers);

static int send_temperature(struct coap_resource *resource, const struct sockaddr *addr, socklen_t addr_len, uint16_t age, uint16_t id, const uint8_t *token, uint8_t tkl, bool is_response) {
    const struct device *dev = DEVICE_DT_GET(DT_ALIAS(ambient_temp0));
    uint8_t data[CONFIG_COAP_SERVER_MESSAGE_SIZE];
    struct coap_packet response;
    char payload[14];
    struct sensor_value value;
    double temp;
    uint8_t type;

    /* Determine response type */
    type = is_response ? COAP_TYPE_ACK : COAP_TYPE_CON;

    if (!is_response) {
        id = coap_next_id();
    }

    coap_packet_init(&response, data, sizeof(data), COAP_VERSION_1, type, tkl, token, COAP_RESPONSE_CODE_CONTENT, id);

    if (age >= 2U) {
        coap_append_option_int(&response, COAP_OPTION_OBSERVE, age);
    }

    /* Set content format */
    coap_append_option_int(&response, COAP_OPTION_CONTENT_FORMAT, COAP_CONTENT_FORMAT_TEXT_PLAIN);

    /* Get the sensor data */
    sensor_sample_fetch_chan(dev, SENSOR_CHAN_AMBIENT_TEMP);
    sensor_channel_get(dev, SENSOR_CHAN_AMBIENT_TEMP, &value);
    temp = sensor_value_to_double(&value);

    snprintf(payload, sizeof(payload), "%0.2f°C", temp);

    /* Append payload */
    coap_packet_append_payload_marker(&response);
    coap_packet_append_payload(&response, (uint8_t*)payload, strlen(payload));

    return coap_resource_send(resource, &response, addr, addr_len, NULL);
}

static int temp_get(struct coap_resource *resource, struct coap_packet *request, struct sockaddr *addr, socklen_t addr_len) {
    uint8_t token[COAP_TOKEN_MAX_LEN];
    uint16_t id;
    uint8_t tkl;
    int r;

    /* Let the CoAP server parse the request and add/remove observers if needed */
    r = coap_resource_parse_observe(resource, request, addr);
```
id = coap_header_get_id(request);
tkl = coap_header_get_token(request, token);

return send_temperature(resource, addr, addr_len, r == 0 ? resource->age : 0,
   id, token, tkl, true);
}

static void temp_notify(struct coap_resource *resource, struct coap_observer *observer)
{
  send_temperature(resource, &observer->addr, sizeof(observer->addr), resource->age, 0,
   observer->token, observer->tkl, false);
}

static const char * const temp_resource_path[] = { "sensors", "temp1", NULL };
COAP_RESOURCE_DEFINE(temp_resource, my_service, {
  .path = temp_resource_path,
  .get = temp_get,
  .notify = temp_notify,
});

static void notifyObservers(struct k_work *work)
{
  if (sys_slist_is_empty(&temp_resource.observers)) {
    return;
  }

  coap_resource_notify(&temp_resource);
  k_work_reschedule(&temp_work, K_SECONDS(1));
}

CoAP Events  By enabling CONFIG_NET_MGMT_EVENT the user can register for CoAP events. The
following example simply prints when an event occurs.

#include <zephyr/sys/printk.h>
#include <zephyr/net/coap_mgmt.h>
#include <zephyr/net/coap_service.h>

#define COAP_EVENTS_SET (NET_EVENT_COAP_OBSERVER_ADDED | NET_EVENT_COAP_OBSERVER_REMOVED | 
   NET_EVENT_COAP_SERVICE_STARTED | NET_EVENT_COAP_SERVICE_STOPPED)

void coap_event_handler(uint32_t mgmt_event, struct net_if *iface,
   void *info, size_t info_length, void *user_data)
{
  switch (mgmt_event) {
    case NET_EVENT_COAP_OBSERVER_ADDED:
      printk("CoAP observer added");
      break;
    case NET_EVENT_COAP_OBSERVER_REMOVED:
      printk("CoAP observer removed");
      break;
    case NET_EVENT_COAP_SERVICE_STARTED:
      if (info != NULL && info_length == sizeof(struct net_event_coap_service)) {
        struct net_event_coap_service *net_event = info;

        printk("CoAP service %s started", net_event->service->name);
      } else {
        printk("CoAP service started");
      }
  }
}
break;
case NET_EVENT_COAP_SERVICE_STOPPED:
    if (info != NULL && info_length == sizeof(struct net_event_coap_service)) {
        struct net_event_coap_service *net_event = info;
        printk("CoAP service %s stopped", net_event->service->name);
    } else {
        printk("CoAP service stopped");
    }
break;
}
NET_MGMT_REGISTER_EVENT_HANDLER(coap_events, COAP_EVENTS_SET, coap_event_handler, NULL);

CoRE Link Format  The CONFIG_COAP_SERVER_WELL_KNOWN_CORE option enables handling the well-known/core GET requests by the server. This allows clients to get a list of hypermedia links to other resources hosted in that server.

API Reference  Related code samples

CoAP service
Use the CoAP server subsystem to register CoAP resources.

(group coap_service
    CoAP Service API.
    
    CoAP Service configuration flags
    
    COAP_SERVICE_AUTOSTART
    Start the service on boot.

    Defines
    
    COAP_RESOURCE_DEFINE(_name, _service, ...)
    Define a static CoAP resource owned by the service named _service.

    static const struct gpio_dt_spec led = GPIO_DT_SPEC_GET(DT_ALIAS(led0), gpios);
    static int led_put(struct coap_resource *resource, struct coap_packet *request,
                        struct sockaddr *addr, socklen_t addr_len)
    {
        const uint8_t *payload;
        uint16_t payload_len;

        payload = coap_packet_get_payload(request, &payload_len);
        if (payload_len != 1) {
            (continues on next page)
return COAP_RESPONSE_CODE_BAD_REQUEST;
}
if (gpio_pin_set_dt(&led, payload[0]) < 0) {
    return COAP_RESPONSE_CODE_INTERNAL_ERROR;
}
return COAP_RESPONSE_CODE_CHANGED;
}
COAP_RESOURCE_DEFINE(my_resource, my_service, {
    .put = led_put,
    });

Note: The handlers registered with the resource can return a CoAP response code to reply with an acknowledge without any payload, nothing is sent if the return value is 0 or negative. As seen in the example.

Parameters

- _name – Name of the resource.
- _service – Name of the associated service.

COAP_SERVICE_DEFINE(_name, _host, _port, _flags)
Define a CoAP service with static resources.

See also:

COAP_SERVICE_FLAGS.

Note: The _host parameter can be NULL. If not, it is used to specify an IP address either in IPv4 or IPv6 format a fully-qualified hostname or a virtual host, otherwise the any address is used.

Note: The _port parameter must be non-NULL. It points to a location that specifies the port number to use for the service. If the specified port number is zero, then an ephemeral port number will be used and the actual port number assigned will be written back to memory. For ephemeral port numbers, the memory pointed to by _port must be writeable.

Parameters

- _name – Name of the service.
- _host – IP address or hostname associated with the service.
- _port – [inout] Pointer to port associated with the service.
- _flags – Configuration flags

COAP_SERVICE_COUNT(_dst)
Count the number of CoAP services.

Parameters
• _dst – [out] Pointer to location where result is written.

**COAP_SERVICE_RESOURCE_COUNT(_service)**
Count CoAP service static resources.

**Parameters**
• _service – Pointer to a service.

**COAP_SERVICE_HAS_RESOURCE(_service, _resource)**
Check if service has the specified resource.

**Parameters**
• _service – Pointer to a service.
• _resource – Pointer to a resource.

**COAP_SERVICE_FOREACH(_it)**
Iterate over all CoAP services.

**Parameters**
• _it – Name of iterator (of type CoAP service API)

**COAP_RESOURCE_FOREACH(_service, _it)**
Iterate over static CoAP resources associated with a given _service.

**Note:** This macro requires that _service is defined with **COAP_SERVICE_DEFINE**.

**Parameters**
• _service – Name of CoAP service
• _it – Name of iterator (of type coap_resource)

**COAP_SERVICE_FOREACH_RESOURCE(_service, _it)**
Iterate over all static resources associated with _service.

**Note:** This macro is suitable for a _service defined with **COAP_SERVICE_DEFINE**.

**Parameters**
• _service – Pointer to CoAP service
• _it – Name of iterator (of type coap_resource)

**Functions**

```c
int coap_service_start(const struct coap_service *service)
Start the provided service.
```

**Note:** This function is suitable for a service defined with **COAP_SERVICE_DEFINE**.

**Parameters**
• service – Pointer to CoAP service

**Return values**
int coap_service_stop(const struct coap_service *service)
Stop the provided service.

Note: This function is suitable for a service defined with COAP_SERVICE_DEFINE.

Parameters
• service – Pointer to CoAP service

Return values
• 0 – in case of success.
• -EALREADY – in case the service isn’t running.

int coap_service_is_running(const struct coap_service *service)
Query the provided service running state.

Note: This function is suitable for a service defined with COAP_SERVICE_DEFINE.

Parameters
• service – Pointer to CoAP service

Return values
• 1 – if the service is running
• 0 – if the service is stopped
• negative – in case of an error.

int coap_service_send(const struct coap_service *service, const struct coap_packet *cpkt, const struct sockaddr *addr, socklen_t addr_len, const struct coap_transmission_parameters *params)
Send a CoAP message from the provided service.

Note: This function is suitable for a service defined with COAP_SERVICE_DEFINE.

Parameters
• service – Pointer to CoAP service
• cpkt – CoAP Packet to send
• addr – Peer address
• addr_len – Peer address length
• params – Pointer to transmission parameters structure or NULL to use default values.

Returns
0 in case of success or negative in case of error.
int coap_resource_send(const struct coap_resource *resource, const struct coap_packet *cpkt, const struct sockaddr *addr, socklen_t addr_len, const struct coap_transmission_parameters *params)

Send a CoAP message from the provided resource.

**Note:** This function is suitable for a resource defined with `COAP_RESOURCE_DEFINE`.

**Parameters**

- **resource** – Pointer to CoAP resource
- **cpkt** – CoAP Packet to send
- **addr** – Peer address
- **addr_len** – Peer address length
- **params** – Pointer to transmission parameters structure or NULL to use default values.

**Returns**

0 in case of success or negative in case of error.

int coap_resource_parse_observe(struct coap_resource *resource, const struct coap_packet *request, const struct sockaddr *addr)

Parse a CoAP observe request for the provided resource.

If the observe option value is equal to 0, an observer will be added, if the value is equal to 1, an existing observer will be removed.

**Note:** This function is suitable for a resource defined with `COAP_RESOURCE_DEFINE`.

**Parameters**

- **resource** – Pointer to CoAP resource
- **request** – CoAP request to parse
- **addr** – Peer address

**Returns**

the observe option value in case of success or negative in case of error.

int coap_resource_remove_observer_by_addr(struct coap_resource *resource, const struct sockaddr *addr)

Lookup an observer by address and remove it from the resource.

**Note:** This function is suitable for a resource defined with `COAP_RESOURCE_DEFINE`.

**Parameters**

- **resource** – Pointer to CoAP resource
- **addr** – Peer address

**Returns**

0 in case of success or negative in case of error.
int coap_resource_remove_observer_by_token(struct coap_resource *resource, const uint8_t *token, uint8_t token_len)

Lookup an observer by token and remove it from the resource.

**Note:** This function is suitable for a resource defined with `COAP_RESOURCE_DEFINE`.

**Parameters**
- `resource` – Pointer to CoAP resource
- `token` – Pointer to the token
- `token_len` – Length of valid bytes in the token

**Returns**
0 in case of success or negative in case of error.

**group coap_mgmt**
CoAP Manager Events.

**Defines**

```c
#include <coap_mgmt.h>
```

CoAP Service event structure.

**Enums**

```c
eenum net_event_coap_cmd

*Values:*

enumerator `NET_EVENT_COAP_CMD_SERVICE_STARTED` = 1
enumerator `NET_EVENT_COAP_CMD_SERVICE_STOPPED`
enumerator `NET_EVENT_COAP_CMD_OBSERVER_ADDED`
enumerator `NET_EVENT_COAP_CMD_OBSERVER_REMOVED`
```

`struct net_event_coap_service`

*#include <coap_mgmt.h>* CoAP Service event structure.
HTTP client

Overview The HTTP client library allows you to send HTTP requests and parse HTTP responses. The library communicates over the sockets API but it does not create sockets on its own. It can be enabled with CONFIG_HTTP_CLIENT Kconfig option.

The application must be responsible for creating a socket and passing it to the library. Therefore, depending on the application's needs, the library can communicate over either a plain TCP socket (HTTP) or a TLS socket (HTTPS).

Sample Usage The API of the HTTP client library has a single function.

The following is an example of a request structure created correctly:

```c
struct http_request req = {0};
static uint8_t recv_buf[512];

req.method = HTTP_GET;
req.url = "/";
req.host = "localhost";
req.protocol = "HTTP/1.1";
req.response = response_cb;
req.recv_buf = recv_buf;
req.recv_buf_len = sizeof(recv_buf);

/* sock is a file descriptor referencing a socket that has been connected *
 * to the HTTP server. */
ret = http_client_req(sock, &req, 5000, NULL);
```

If the server responds to the request, the library provides the response to the application through the response callback registered in the request structure. As the library can provide the response in chunks, the application must be able to process these.

Together with the structure containing the response data, the callback function also provides information about whether the library expects to receive more data.

The following is an example of a very simple response handling function:

```c
static void response_cb(struct http_response *rsp,
                        enum http_final_call final_data,
                        void *user_data)
{
    if (final_data == HTTP_DATA_MORE) {
        LOG_INF("Partial data received (%zd bytes)", rsp->data_len);
    } else if (final_data == HTTP_DATA_FINAL) {
        LOG_INF("All the data received (%zd bytes)", rsp->data_len);
    }
}
```

(continues on next page)
See HTTP client sample application for more information about the library usage.

### API Reference

#### Related code samples

**HTTP client**
Implement an HTTP(S) client that issues a variety of HTTP requests.

**TagoIO HTTP Post**
Send random temperature values to TagoIO IoT Cloud Platform using HTTP.

---

**group** http_client
HTTP client API.

#### Defines

**HTTP_CRLF**

**HTTP_STATUS_STR_SIZE**

#### Typedefs

typedef int (*http_payload_cb_t)(int sock, struct http_request *req, void *user_data)
Callback used when data needs to be sent to the server.

- **Param sock**
  Socket id of the connection

- **Param req**
  HTTP request information

- **Param user_data**
  User specified data specified in `http_client_req()`

**Return**

>=0 amount of data sent, in this case `http_client_req()` should continue sending data, <0 if `http_client_req()` should return the error code to the caller.

typedef int (*http_header_cb_t)(int sock, struct http_request *req, void *user_data)
Callback can be used if application wants to construct additional HTTP headers when the HTTP request is sent.

Usage of this is optional.

- **Param sock**
  Socket id of the connection

- **Param req**
  HTTP request information
**Param user_data**  
User specified data specified in `http_client_req()`

**Return**  
>=0 amount of data sent, in this case `http_client_req()` should continue sending data, <0 if `http_client_req()` should return the error code to the caller.

typedef void (*http_response_cb_t)(struct http_response *rsp, enum http_final_call final_data, void *user_data)

Callback used when data is received from the server.

**Param rsp**  
HTTP response information

**Param final_data**  
Does this data buffer contain all the data or is there still more data to come.

**Param user_data**  
User specified data specified in `http_client_req()`

**Enums**

enum http_final_call

*Values:*

enumerator HTTP_DATA_MORE = 0

enumerator HTTP_DATA_FINAL = 1

**Functions**

int http_client_req(int sock, struct http_request *req, int32_t timeout, void *user_data)

Do a HTTP request.

The callback is called when data is received from the HTTP server. The caller must have created a connection to the server before calling this function so `connect()` call must have been done successfully for the socket.

**Parameters**

- `sock` – Socket id of the connection.
- `req` – HTTP request information
- `timeout` – Max timeout to wait for the data. The timeout value cannot be 0 as there would be no time to receive the data. The timeout value is in milliseconds.
- `user_data` – User specified data that is passed to the callback.

**Returns**

<0 if error, >=0 amount of data sent to the server

struct http_response

`#include <client.h>` HTTP response from the server.
Public Members

const struct http_parser_settings *http_cb
HTTP parser settings for the application usage.

http_response_cb_t cb
User provided HTTP response callback which is called when a response is received
to a sent HTTP request.

uint8_t *body_frag_start
Start address of the body fragment contained in the recv_buf.

recv_buffer that contains header + body

|------------------ body_frag_len ------------------|
|--------------------- data len --------------------|
---------------------------------------------------------------
..header | header | body | body..
---------------------------------------------------------------
↑ ↑
recv_buf body_frag_start

recv_buffer that contains body only

|------------------ body_frag_len ------------------|
|--------------------- data len --------------------|
---------------------------------------------------------------

size_t body_frag_len
Length of the body fragment contained in the recv_buf.

uint8_t *recv_buf
Where the response is stored, this is to be provided by the user.

size_t recv_buf_len
Response buffer maximum length.

size_t data_len
Length of the data in the result buf.
If the value is larger than recv_buf_len, then it means that the data is truncated
and could not be fully copied into recv_buf. This can only happen if the user did
not set the response callback. If the callback is set, then the HTTP client API will
call response callback many times so that all the data is delivered to the user. Will
be zero in the event of a null response.

size_t content_length
HTTP Content-Length field value.
Will be set to zero in the event of a null response.
size_t processed
Amount of data given to the response callback so far, including the current data
given to the callback.
This should be equal to the content_length field once the entire body has been
received. Will be zero if a null response is given.

uint16_t http_status_code
Numeric HTTP status code which corresponds to the textual description.
Set to zero if null response is given. Otherwise, will be a 3-digit integer code if valid
HTTP response is given.

struct http_client_internal_data
#include <client.h> HTTP client internal data that the application should not touch.

Public Members

struct http_parser parser
HTTP parser context.

struct http_parser_settings parser_settings
HTTP parser settings.

struct http_response response
HTTP response specific data (filled by http_client_req() when data is received)

void *user_data
User data.

int sock
HTTP socket.

struct http_request
#include <client.h> HTTP client request.
This contains all the data that is needed when doing a HTTP request.

Public Members

struct http_client_internal_data internal
HTTP client request internal data.

enum http_method method
The HTTP method: GET, HEAD, OPTIONS, POST, ...

http_response_cb_t response
User supplied callback function to call when response is received.
const struct http_parser_settings *http_cb
    User supplied list of HTTP callback functions if the calling application wants to know the parsing status or the HTTP fields.
    This is optional and normally not needed.

uint8_t *recv_buf
    User supplied buffer where received data is stored.

size_t recv_buf_len
    Length of the user supplied receive buffer.

const char *url
    The URL for this request, for example: /index.html.

const char *protocol
    The HTTP protocol, for example “HTTP/1.1”.

const char **header_fields
    The HTTP header fields (application specific) The Content-Type may be specified here or in the next field.
    Depending on your application, the Content-Type may vary, however some header fields may remain constant through the application’s life cycle. This is a NULL terminated list of header fields.

const char *content_type_value
    The value of the Content-Type header field, may be NULL.

const char *host
    Hostname to be used in the request.

const char *port
    Port number to be used in the request.

http_payload_cb_t payload_cb
    User supplied callback function to call when payload needs to be sent.
    This can be NULL in which case the payload field in http_request is used. The idea of this payload callback is to allow user to send more data that is practical to store in allocated memory.

const char *payload
    Payload, may be NULL.

size_t payload_len
    Payload length is used to calculate Content-Length.
    Set to 0 for chunked transfers.

http_header_cb_t optional_headers_cb
    User supplied callback function to call when optional headers need to be sent.

6.3. Networking
This can be NULL, in which case the optional_headers field in `http_request` is used. The idea of this optional_headers callback is to allow user to send more HTTP header data that is practical to store in allocated memory.

```c
const char **optional_headers
```

A NULL terminated list of any optional headers that should be added to the HTTP request.

May be NULL. If the optional_headers_cb is specified, then this field is ignored. Note that there are two similar fields that contain headers, the header_fields above and this optional_headers. This is done like this to support Websocket use case where Websocket will use header_fields variable and any optional application specific headers will be placed into this field.

Lightweight M2M (LWM2M)

- **Overview**
- **Example LwM2M object and resources: Device**
- **Sample usage**
- **LwM2M security modes**
- **Multi-thread usage**
- **Support for time series data**
  - **Enabling and configuring**
  - **Read and Write operations**
  - **Limitations**
- **LwM2M engine and application events**
- **Configuring lifetime and activity period**
- **LwM2M shell**
- **API Reference**

**Overview**
Lightweight Machine to Machine (LwM2M) is an application layer protocol designed with device management, data reporting and device actuation in mind. Based on CoAP/UDP, LwM2M is a standard defined by the Open Mobile Alliance and suitable for constrained devices by its use of CoAP packet-size optimization and a simple, stateless flow that supports a REST API.

One of the key differences between LwM2M and CoAP is that an LwM2M client initiates the connection to an LwM2M server. The server can then use the REST API to manage various interfaces with the client.

LwM2M uses a simple resource model with the core set of objects and resources defined in the specification.

The LwM2M library can be enabled with `CONFIG_LWM2M` Kconfig option.

**Example LwM2M object and resources: Device**

<table>
<thead>
<tr>
<th>Object ID</th>
<th>Name</th>
<th>Instance</th>
<th>Mandatory</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>Device</td>
<td>Single</td>
<td>Mandatory</td>
</tr>
</tbody>
</table>
**Resource definitions**

* R=Read, W=Write, E=Execute

<table>
<thead>
<tr>
<th>ID</th>
<th>Name</th>
<th>OP*</th>
<th>Instance</th>
<th>Mandatory</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Manufacturer</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>1</td>
<td>Model</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>2</td>
<td>Serial number</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>3</td>
<td>Firmware version</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>4</td>
<td>Reboot</td>
<td>E</td>
<td>Single</td>
<td>Mandatory</td>
<td></td>
</tr>
<tr>
<td>5</td>
<td>Factory Reset</td>
<td>E</td>
<td>Single</td>
<td>Optional</td>
<td></td>
</tr>
<tr>
<td>6</td>
<td>Available Power Sources</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>Integer 0-7</td>
</tr>
<tr>
<td>7</td>
<td>Power Source Voltage (mV)</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>8</td>
<td>Power Source Current (mA)</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>9</td>
<td>Battery Level %</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>10</td>
<td>Memory Free (Kb)</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>11</td>
<td>Error Code</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>Integer 0-8</td>
</tr>
<tr>
<td>12</td>
<td>Reset Error</td>
<td>E</td>
<td>Single</td>
<td>Optional</td>
<td></td>
</tr>
<tr>
<td>13</td>
<td>Current Time</td>
<td>RW</td>
<td>Single</td>
<td>Optional</td>
<td>Time</td>
</tr>
<tr>
<td>14</td>
<td>UTC Offset</td>
<td>RW</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
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<td>Single</td>
<td>Optional</td>
<td>String</td>
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<tr>
<td>16</td>
<td>Supported Binding</td>
<td>R</td>
<td>Single</td>
<td>Mandatory</td>
<td>String</td>
</tr>
<tr>
<td>17</td>
<td>Device Type</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>18</td>
<td>Hardware Version</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>19</td>
<td>Software Version</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>20</td>
<td>Battery Status</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>Integer 0-6</td>
</tr>
<tr>
<td>21</td>
<td>Memory Total (Kb)</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>22</td>
<td>ExtDevInfo</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>ObjLnk</td>
</tr>
</tbody>
</table>

The server could query the Manufacturer resource for Device object instance 0 (the default and only instance) by sending a READ 3/0/0 operation to the client.

The full list of registered objects and resource IDs can be found in the LwM2M registry.

Zephyr’s LwM2M library lives in the `subsys/net/lib/lwm2m`, with a client sample in `samples/net/lwm2m_client`. For more information about the provided sample see: `lwm2m-client`. The sample can be configured to use normal unsecure network sockets or sockets secured via DTLS.

The Zephyr LwM2M library implements the following items:

- engine to process networking events and core functions
- RD client which performs BOOTSTRAP and REGISTRATION functions
- SenML CBOR, SenML JSON, CBOR, TLV, JSON, and plain text formatting functions
- LwM2M Technical Specification Enabler objects such as Security, Server, Device, Firmware Update, etc.
- Extended IPSO objects such as Light Control, Temperature Sensor, and Timer

By default, the library implements LwM2M specification 1.0.2 and can be set to LwM2M specification 1.1.1 with a Kconfig option.

For more information about LwM2M visit OMA Specworks LwM2M.

**Sample usage**

To use the LwM2M library, start by creating an LwM2M client context `lwm2m_ctx` structure:
Create callback functions for LwM2M resource executions:

```c
static int device_reboot_cb(uint16_t obj_inst_id, uint8_t *args,
                            uint16_t args_len)
{
    LOG_INF("Device rebooting.");
    LOG_PANIC();
    sys_reboot(0);
    return 0; /* won't reach this */
}
```

The LwM2M RD client can send events back to the sample. To receive those events, setup a callback function:

```c
static void rd_client_event(struct lwm2m_ctx *client,
                            enum lwm2m_rd_client_event client_event)
{
    switch (client_event) {
        case LWM2M_RD_CLIENT_EVENT_NONE:
            /* do nothing */
            break;
        case LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_REG_FAILURE:
            LOG_DBG("Bootstrap registration failure!");
            break;
        case LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_REG_COMPLETE:
            LOG_DBG("Bootstrap registration complete");
            break;
        case LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_TRANSFER_COMPLETE:
            LOG_DBG("Bootstrap transfer complete");
            break;
        case LWM2M_RD_CLIENT_EVENT_REGISTRATION_FAILURE:
            LOG_DBG("Registration failure!");
            break;
        case LWM2M_RD_CLIENT_EVENT_REGISTRATION_COMPLETE:
            LOG_DBG("Registration complete");
            break;
        case LWM2M_RD_CLIENT_EVENT_REG_TIMEOUT:
            LOG_DBG("Registration timeout!");
            break;
        case LWM2M_RD_CLIENT_EVENT_REG_UPDATE_COMPLETE:
            LOG_DBG("Registration update complete");
            break;
        case LWM2M_RD_CLIENT_EVENT_DEREGISTER_FAILURE:
            LOG_DBG("Deregister failure!");
            break;
        case LWM2M_RD_CLIENT_EVENT_DISCONNECT:
            LOG_DBG("Disconnected");
            break;
    }
}
```
Next we assign Security resource values to let the client know where and how to connect as well as set the Manufacturer and Reboot resources in the Device object with some data and the callback we defined above:

```c
/*
 * Server URL of default Security object = 0/0/0
 * Use leshan.eclipse.org server IP (5.39.83.206) for connection
 */
lwm2m_set_string(&LWM2M_OBJ(0, 0, 0), "coap://5.39.83.206");

/*
 * Security Mode of default Security object = 0/0/2
 * 3 = NoSec mode (no security beware!)
 */
lwm2m_set_u8(&LWM2M_OBJ(0, 0, 2), 3);

#define CLIENT_MANUFACTURER "Zephyr Manufacturer"

/*
 * Manufacturer resource of Device object = 3/0/0
 * We use lwm2m_set_res_data() function to set a pointer to the
 * CLIENT_MANUFACTURER string.
 * Note the LWM2M_RES_DATA_FLAG_RO flag which stops the engine from
 * trying to assign a new value to the buffer.
 */
lwm2m_set_res_data(&LWM2M_OBJ(3, 0, 0), CLIENT_MANUFACTURER,
                   sizeof(CLIENT_MANUFACTURER),
                   LWM2M_RES_DATA_FLAG_RO);

/* Reboot resource of Device object = 3/0/4 */
lwm2m_register_exec_callback(&LWM2M_OBJ(3, 0, 4), device_reboot_cb);
```

Lastly, we start the LwM2M RD client (which in turn starts the LwM2M engine). The second parameter of `lwm2m_rd_client_start()` is the client endpoint name. This is important as it needs to be unique per LwM2M server:

```c
(void)memset(&client, 0x0, sizeof(client));
lwm2m_rd_client_start(&client, "unique-endpoint-name", 0, rd_client_event);
```

**LwM2M security modes** The Zephyr LwM2M library can be used either without security or use DTLS to secure the communication channel. When using DTLS with the LwM2M engine, PSK (Pre-Shared Key) and X.509 certificates are the security modes that can be used to secure the communication. The engine uses LwM2M Security object (Id 0) to read the stored credentials and feed keys from the security object into the TLS credential subsystem, see secure sockets documentation. Enable the `CONFIG_LWM2M_DTLS_SUPPORT` Kconfig option to use the security.
Depending on the selected mode, the security object must contain following data:

**PSK**

Security Mode (Resource ID 2) set to zero (Pre-Shared Key mode). Identity (Resource ID 3) contains PSK ID in binary form. Secret key (Resource ID 5) contains the PSK key in binary form. If the key or identity is provided as a hex string, it must be converted to binary before storing into the security object.

**X509**

When X509 certificates are used, set Security Mode (ID 2) to 2 (Certificate mode). Identity (ID 3) is used to store the client certificate and Secret key (ID 5) must have a private key associated with the certificate. Server Public Key resource (ID 4) must contain a server certificate or CA certificate used to sign the certificate chain. If the CONFIGMBEDTLS_PEM_CERTIFICATE_FORMAT Kconfig option is enabled, certificates and private key can be entered in PEM format. Otherwise, they must be in binary DER format.

**NoSec**

When no security is used, set Security Mode (Resource ID 2) to 3 (NoSec).

In all modes, Server URI resource (ID 0) must contain the full URI for the target server. When DNS names are used, the DNS resolver must be enabled.

When DTLS is used, following options are recommended to reduce DTLS handshake traffic when connection is re-established:

- CONFIG_LWMS_LWM2MloggedIn enables DTLS Connection Identifier support. When server supports it, this completely removes the handshake when device resumes operation after long idle period. Greatly helps when NAT mappings have timed out.
- CONFIG_LWMS_LWM2M_TLS_SESSION_CACHING uses session cache when before falling back to full DTLS handshake. Reduces few packets from handshake, when session is still cached on server side. Most significant effect is to avoid full registration.

LwM2M stack provides callbacks in the `lwm2m_ctx` structure. They are used to feed keys from the LwM2M security object into the TLS credential subsystem. By default, these callbacks can be left as NULL pointers, in which case default callbacks are used. When an external TLS stack, or non-default socket options are required, you can overwrite the `lwm2m_ctx.load_credentials()` or `lwm2m_ctx.set_socketoptions()` callbacks.

An example of setting up the security object for PSK mode:

```c
/* "00102030405060708090a0b0c0d0e0f" */
static unsigned char client_psk[] = {
    0x00, 0x01, 0x02, 0x03, 0x04, 0x05, 0x06, 0x07,
    0x08, 0x09, 0x0a, 0x0b, 0x0c, 0x0d, 0x0e, 0x0f
};

static const char client_identity[] = "Client_identity";

lwm2m_set_string(&LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 0), "coaps://lwm2m.example.com");
lwm2m_set_u8(&LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 2), LWM2M_SECURITY_PSK);
/* Set the client identity as a string, but this could be binary as well */
lwm2m_set_string(&LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 3), client_identity);
/* Set the client pre-shared key (PSK) */
lwm2m_set_opaque(&LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 5), client_psk, sizeof(client_psk));
```

An example of setting up the security object for X509 certificate mode:

```c
static const char certificate[] = "-----BEGIN CERTIFICATE-----\nMIIB6jCCAY+gAw...
static const char key[] = "-----BEGIN EC PRIVATE KEY-----\nG7hC...
static const char root_ca[] = "-----BEGIN CERTIFICATE-----\nMIIBaz....

lwm2m_set_string(&LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 0), "coaps://lwm2m.example.com");
```

(continues on next page)
lwm2m_set_u8(LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 2), LWM2M_SECURITY_CERT);
lwm2m_set_string(LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 3), certificate);
lwm2m_set_string(LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 5), key);
lwm2m_set_string(LWM2M_OBJ(LWM2M_OBJECT_SECURITY_ID, 0, 4), root_ca);

Before calling lwm2m_rd_client_start() assign the tls_tag # where the LwM2M library should store the DTLS information prior to connection (normally a value of 1 is ok here).

(void)memset(&client, 0x0, sizeof(client));
client.tls_tag = 1; /* <---- */
lwm2m_rd_client_start(&client, "endpoint-name", 0, rd_client_event);

For a more detailed LwM2M client sample see: lwm2m-client.

**Multi-thread usage** Writing a value to a resource can be done using functions like lwm2m_set_u8. When writing to multiple resources, the function lwm2m_registry_lock will ensure that the client halts until all writing operations are finished:

lwm2m_registry_lock();
lwm2m_set_u32(LWM2M_OBJ(1, 0, 1), 60);
lwm2m_set_u8(LWM2M_OBJ(5, 0, 3), 0);
lwm2m_set_f64(LWM2M_OBJ(3303, 0, 5700), value);
lwm2m_registry_unlock();

This is especially useful if the server is composite-observing the resources being written to. Locking will then ensure that the client only updates and sends notifications to the server after all operations are done, resulting in fewer messages in general.

**Support for time series data** LwM2M version 1.1 adds support for SenML CBOR and SenML JSON data formats. These data formats add support for time series data. Time series formats can be used for READ, NOTIFY and SEND operations. When data cache is enabled for a resource, each write will create a timestamped entry in a cache, and its content is then returned as a content in READ, NOTIFY or SEND operation for a given resource.

Data cache is only supported for resources with a fixed data size.

Supported resource types:

- Signed and unsigned 8-64-bit integers
- Float
- Boolean

**Enabling and configuring** Enable data cache by selecting CONFIG_LWM2M_RESOURCE_DATA_CACHE_SUPPORT. Application needs to allocate an array of lwm2m_time_series_elem structures and then enable the cache by calling lwm2m_engine_enable_cache() for a given resource. Each resource must be enabled separately and each resource needs their own storage.

    /* Allocate data cache storage */
    static struct lwm2m_time_series_elem temperature_cache[10];
    /* Enable data cache */
    lwm2m_engine_enable_cache(LWM2M_PATH(IPSO_OBJECT_TEMP_SENSOR_ID, 0, SENSOR_VALUE_RID), temperature_cache, ARRAY_SIZE(temperature_cache));

LwM2M engine have room for four resources that have cache enabled. Limit can be increased by changing CONFIG_LWM2M_MAX_CACHED_RESOURCES. This affects a static memory usage of engine.
Data caches depends on one of the SenML data formats `CONFIG_LWM2M_RW_SENML_CBOR_SUPPORT` or `CONFIG_LWM2M_RW_SENML_JSON_SUPPORT` and needs `CONFIG_POSIX_CLOCK` so it can request a timestamp from the system and `CONFIG_RING_BUFFER` for ring buffer.

**Read and Write operations**  
Full content of data cache is written into a payload when any READ, SEND or NOTIFY operation internally reads the content of a given resource. This has a side effect that any read callbacks registered for a that resource are ignored when cache is enabled. Data is written into a cache when any of the `lwm2m_set_*` functions are called. To filter the data entering the cache, application may register a validation callback using `lwm2m_register_validate_callback()`.

**Limitations**  
Cache size should be manually set so small that the content can fit normal packets sizes. When cache is full, new values are dropped.

**LwM2M engine and application events**  
The Zephyr LwM2M engine defines events that can be sent back to the application through callback functions. The engine state machine shows when the events are spawned. Events depicted in the diagram are listed in the table. The events are prefixed with `LWM2M_RD_CLIENT_EVENT_`.

### Table 21: LwM2M RD Client events

<table>
<thead>
<tr>
<th>Event ID</th>
<th>Event Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>NONE</td>
<td>No event</td>
</tr>
<tr>
<td>1</td>
<td>BOOT-STRAP_REG_FAILURE</td>
<td>Bootstrap registration failed. Occurs if there is a timeout or failure in bootstrap registration.</td>
</tr>
<tr>
<td>2</td>
<td>BOOT-STRAP_REG_COMPLETE</td>
<td>Bootstrap registration complete. Occurs after successful bootstrap registration.</td>
</tr>
<tr>
<td>3</td>
<td>BOOT-STRAP_TRANSPORT</td>
<td>Bootstrap finish command received from the server.</td>
</tr>
<tr>
<td>4</td>
<td>REGISTRATION_FAILURE</td>
<td>Registration to LwM2M server failed. Occurs if there is a failure in the registration.</td>
</tr>
<tr>
<td>5</td>
<td>REGISTRATION_COMPLETE</td>
<td>Registration to LwM2M server successful. Occurs after a successful registration reply from the LwM2M server or when session resumption is used.</td>
</tr>
<tr>
<td>6</td>
<td>REG_TIMEOUT</td>
<td>Registration or registration update timeout. Occurs if there is a timeout during registration. Client have lost connection to the server.</td>
</tr>
<tr>
<td>7</td>
<td>REG_UPDATE_COMPLETE</td>
<td>Registration update completed. Occurs after successful registration update reply from the LwM2M server.</td>
</tr>
<tr>
<td>8</td>
<td>DEREGISTRATION_FAILURE</td>
<td>Deregistration to LwM2M server failed. Occurs if there is a timeout or failure in the deregistration.</td>
</tr>
<tr>
<td>9</td>
<td>DISCONNECT</td>
<td>LwM2M client have de-registered from server and is now stopped. Triggered only if the application have requested the client to stop.</td>
</tr>
<tr>
<td>10</td>
<td>QUEUE_MODE_RX_OFF</td>
<td>Used only in queue mode, not actively listening for incoming packets. In queue mode the client is not required to actively listen for the incoming packets after a configured time period.</td>
</tr>
<tr>
<td>11</td>
<td>ENGINE_SUSPEND</td>
<td>Indicate that client has now paused as a result of calling <code>lwm2m_engine_pause()</code>. State machine is no longer running and the handler thread is suspended. All timers are stopped so notifications are not triggered.</td>
</tr>
<tr>
<td>12</td>
<td>SERVER_DISASSOCIATE</td>
<td>Server have executed the disable command. Client will deregister and stay idle for the disable period.</td>
</tr>
<tr>
<td>13</td>
<td>NETWORK_ERROR</td>
<td>Sending messages to the network failed too many times. Client cannot reach any servers or fallback to bootstrap. LwM2M engine cannot recover and have stopped.</td>
</tr>
</tbody>
</table>
LwM2M engine state machine

Fig. 15: State machine for the LwM2M engine
The LwM2M client engine handles most of the state transitions automatically. The application needs to handle only the events that indicate that the client have stopped or is in a state where it cannot recover.

<table>
<thead>
<tr>
<th>Event Name</th>
<th>How application should react</th>
</tr>
</thead>
<tbody>
<tr>
<td>NONE</td>
<td>Ignore the event.</td>
</tr>
<tr>
<td>BOOT-STRAP_REG_FAIL</td>
<td>Try to recover network connection. Then restart the client by calling <code>lwm2m_rd_client_start()</code>. This might also indicate configuration issue.</td>
</tr>
<tr>
<td>BOOT-STRAP_REG_COMPLETE</td>
<td>No actions needed</td>
</tr>
<tr>
<td>BOOT-STRAP_TRANSFER_COMPLETE</td>
<td>No actions needed</td>
</tr>
<tr>
<td>REGISTRATION_FAILURE</td>
<td>No actions needed</td>
</tr>
<tr>
<td>REGISTRATION_COMPLETE</td>
<td>No actions needed. Application can send or receive data.</td>
</tr>
<tr>
<td>REG_TIMEOUT</td>
<td>No actions needed. Client proceeds to re-registration automatically. Cannot send or receive data.</td>
</tr>
<tr>
<td>REG_UPDATE_COMPLETE</td>
<td>No actions needed. Application can send or receive data.</td>
</tr>
<tr>
<td>DEREGISTRATION_FAILURE</td>
<td>No actions needed. Client proceeds to idle state automatically. Cannot send or receive data.</td>
</tr>
</tbody>
</table>
| DISCONNECT                | Engine have stopped as a result of calling `lwm2m_rd_client_stop()`. If connection is required, the application should restart the client by calling `lwm2m_rd_client_start()`.
| QUEUE_MODE_RX_OFF         | No actions needed. Application can send but cannot receive data. Any data transmission will trigger a registration update. |
| ENGINE_SUSPENDED          | Engine can be resumed by calling `lwm2m_engine_resume()`. Cannot send or receive data.         |
| SERVER_DISABLED           | No actions needed. Client will re-register once the disable period is over. Cannot send or receive data. |
| NETWORK_ERROR             | Try to recover network connection. Then restart the client by calling `lwm2m_rd_client_start()`. This might also indicate configuration issue. |

Sending of data in the table above refers to calling `lwm2m_send_cb()` or by writing into of of the observed resources where observation would trigger a notify message. Receiving of data refers to receiving read, write or execute operations from the server. Application can register callbacks for these operations.

### Configuring lifetime and activity period

In LwM2M engine, there are three Kconfig options and one runtime value that configures how often the client will send LwM2M Update message.

<table>
<thead>
<tr>
<th>Variable</th>
<th>Effect</th>
</tr>
</thead>
<tbody>
<tr>
<td>LwM2M registration lifetime</td>
<td>The lifetime parameter in LwM2M specifies how long a device's registration with an LwM2M server remains valid. Device is expected to send LwM2M Update message before the lifetime expires.</td>
</tr>
<tr>
<td>CONFIG_LWM2M_ENGIN</td>
<td>Default lifetime value, unless set by the bootstrap server. Also defines lower limit that client accepts as a lifetime.</td>
</tr>
<tr>
<td>CONFIG_LWM2M_UPDATE</td>
<td>How long the client can stay idle before sending a next update.</td>
</tr>
<tr>
<td>CONFIG_LWM2M_SECON</td>
<td>Minimum time margin to send the update message before the registration lifetime expires.</td>
</tr>
</tbody>
</table>
By default, the client uses `CONFIG_LWM2M_SECONDS_TO_UPDATE_EARLY` to calculate how many seconds before the expiration of lifetime it is going to send the registration update. The problem with default mode is when the server changes the lifetime of the registration. This is then affecting the period of updates the client is doing. If this is used with the QUEUE mode, which is typical in IPv4 networks, it is also affecting the period of when the device is reachable from the server.

When also the `CONFIG_LWM2M_UPDATE_PERIOD` is set, time to send the update message is the earliest when any of these values expire. This allows setting long lifetime for the registration and configure the period accurately, even if server changes the lifetime parameter.

In runtime, the update frequency is limited to once in 15 seconds to avoid flooding.

**LwM2M shell** For testing the client it is possible to enable Zephyr’s shell and LwM2M specific commands which support changing the state of the client. Operations supported are read, write and execute resources. Client start, stop, pause and resume are also available. The feature is enabled by selecting `CONFIG_LWM2M_SHELL`. The shell is meant for testing so productions systems should not enable it.

One imaginable scenario, where to use the shell, would be executing client side actions over UART when a server side tests would require those. It is assumed that not all tests are able to trigger required actions from the server side.

```bash
uart:~$ lwm2m
lwm2m - LwM2M commands
Subcommands:
    send :send PATHS
        LwM2M SEND operation
    exec :exec PATH [PARAM]
```

(continues on next page)
Execute a resource

**read** :read PATH [OPTIONS]
Read value from LwM2M resource
- `x` Read value as hex stream (default)
- `s` Read value as string
- `b` Read value as bool (1/0)
- `uX` Read value as uintX_t
- `sX` Read value as intX_t
- `f` Read value as float
- `t` Read value as time_t

**write** :write PATH [OPTIONS] VALUE
Write into LwM2M resource
- `s` Write value as string (default)
- `b` Write value as bool
- `uX` Write value as uintX_t
- `sX` Write value as intX_t
- `f` Write value as float
- `t` Write value as time_t

**create** :create PATH
Create object or resource instance

**delete** :delete PATH
Delete object or resource instance

**cache** :cache PATH NUM
Enable data cache for resource
PATH is LwM2M path
NUM how many elements to cache

**start** :start EP_NAME [BOOTSTRAP FLAG]
Start the LwM2M RD (Registration / Discovery) Client
- `b` Set the bootstrap flag (default 0)

**stop** :stop [OPTIONS]
Stop the LwM2M RD (De-register) Client
- `f` Force close the connection

**update** :Trigger Registration Update of the LwM2M RD Client

**pause** :LwM2M engine thread pause
**resume** :LwM2M engine thread resume
**lock** :Lock the LwM2M registry
**unlock** :Unlock the LwM2M registry

**API Reference**

**Related code samples**

**LwM2M client**
Implement a LwM2M client that connects to a LwM2M server.

**group lwm2m_api**
LwM2M high-level API.
LwM2M high-level interface is defined in this header.
Note: The implementation assumes UDP module is enabled.

Note: For more information refer to Technical Specification OMA-TS-LightweightM2M_Core-V1_1-1-20190617-A

LwM2M Objects managed by OMA for LwM2M tech specification.

Objects in this range have IDs from 0 to 1023.

**LWM2M_OBJECT_SECURITY_ID**
Security object.

**LWM2M_OBJECT_SERVER_ID**
Server object.

**LWM2M_OBJECT_ACCESS_CONTROL_ID**
Access Control object.

**LWM2M_OBJECT_DEVICE_ID**
Device object.

**LWM2M_OBJECT_CONNECTIVITY_MONITORING_ID**
Connectivity Monitoring object.

**LWM2M_OBJECT_FIRMWARE_ID**
Firmware object.

**LWM2M_OBJECT_LOCATION_ID**
Location object.

**LWM2M_OBJECT_CONNECTIVITY_STATISTICS_ID**
Connectivity Statistics object.

**LWM2M_OBJECT_SOFTWARE_MANAGEMENT_ID**
Software Management object.

**LWM2M_OBJECT_PORTFOLIO_ID**
Portfolio object.

**LWM2M_OBJECT_BINARYAPPDATACONTAINER_ID**
Binary App Data Container object.

**LWM2M_OBJECT_EVENT_LOG_ID**
Event Log object.

**LWM2M_OBJECT_OSCORE_ID**
OSCORE object.
LWM2M_OBJECT_GATEWAY_ID
Gateway object.

**LwM2M Objects produced by 3rd party Standards Development Organizations.**

Refer to the OMA LightweightM2M (LwM2M) Object and Resource Registry: [http://www.openmobilealliance.org/wp/OMNA/LwM2M/LwM2MRegistry.html](http://www.openmobilealliance.org/wp/OMNA/LwM2M/LwM2MRegistry.html)

IPSO_OBJECT_GENERIC_SENSOR_ID
IPSO Generic Sensor object.

IPSO_OBJECT_TEMP_SENSOR_ID
IPSO Temperature Sensor object.

IPSO_OBJECT_HUMIDITY_SENSOR_ID
IPSO Humidity Sensor object.

IPSO_OBJECT_LIGHT_CONTROL_ID
IPSO Light Control object.

IPSO_OBJECT_ACCELEROMETER_ID
IPSO Accelerometer object.

IPSO_OBJECT_VOLTAGE_SENSOR_ID
IPSO Voltage Sensor object.

IPSO_OBJECT_CURRENT_SENSOR_ID
IPSO Current Sensor object.

IPSO_OBJECT_PRESSURE_ID
IPSO Pressure Sensor object.

IPSO_OBJECT_BUZZER_ID
IPSO Buzzer object.

IPSO_OBJECT_TIMER_ID
IPSO Timer object.

IPSO_OBJECT_ONOFF_SWITCH_ID
IPSO On/Off Switch object.

IPSO_OBJECT_PUSH_BUTTON_ID
IPSO Push Button object.

UCIFI_OBJECT_BATTERY_ID
uCIFI Battery object
IPSO_OBJECT_FILLING_LEVEL_SENSOR_ID
IPSO Filling Level Sensor object.

**Power source types used for the “Available Power Sources” resource of**
the LwM2M Device object (3/0/6).

- **LWM2M_DEVICE_PWR_SRC_TYPE_DC_POWER**
  DC power.
- **LWM2M_DEVICE_PWR_SRC_TYPE_BAT_INT**
  Internal battery.
- **LWM2M_DEVICE_PWR_SRC_TYPE_BAT_EXT**
  External battery.
- **LWM2MDEVICE_PWR_SRC_TYPE_FUEL_CELL**
  Fuel cell.
- **LWM2M_DEVICE_PWR_SRC_TYPE_PWR_OVER_ETH**
  Power over Ethernet.
- **LWM2MDEVICE_PWR_SRC_TYPE_USB**
  USB.
- **LWM2MDEVICE_PWR_SRC_TYPE_AC_POWER**
  AC (mains) power.
- **LWM2MDEVICE_PWR_SRC_TYPE_SOLAR**
  Solar.
- **LWM2MDEVICE_PWR_SRC_TYPE_MAX**
  Max value for Available Power Source type.

**Error codes used for the “Error Code” resource of the LwM2M Device**
object.
An LwM2M client can register one of the following error codes via the
`lwm2m_device_add_err()` function.

- **LWM2M_DEVICE_ERROR_NONE**
  No error.
- **LWM2M_DEVICE_ERROR_LOW_POWER**
  Low battery power.
- **LWM2M_DEVICE_ERROR_EXT_POWER_SUPPLY_OFF**
  External power supply off.
LWM2M_DEVICE_ERROR_GPS_FAILURE  
GPS module failure.

LWM2M_DEVICE_ERROR_LOW_SIGNAL_STRENGTH  
Low received signal strength.

LWM2MDEVICE_ERROR_OUT_OF_MEMORY  
Out of memory.

LWM2M DEVICE_ERROR_SMS_FAILURE  
SMS failure.

LWM2M_DEVICE_ERROR_NETWORK_FAILURE  
IP Connectivity failure.

LWM2MDEVICE_ERROR_PERIPHERAL_FAILURE  
Peripheral malfunction.

Battery status codes used for the “Battery Status” resource (3/0/20)
of the LwM2M Device object.
As the battery status changes, an LwM2M client can set one of the following codes via:
lwm2m_engine_set_u8(“3/0/20”, [battery status])

LWM2M_DEVICE_BATTERY_STATUS_NORMAL  
The battery is operating normally and not on power.

LWM2M_DEVICE_BATTERY_STATUS_CHARGING  
The battery is currently charging.

LWM2M_DEVICE_BATTERY_STATUS_CHARGE_COMP  
The battery is fully charged and the charger is still connected.

LWM2M_DEVICE_BATTERY_STATUS_DAMAGED  
The battery has some problem.

LWM2M_DEVICE_BATTERY_STATUS_LOW  
The battery is low on charge.

LWM2M_DEVICE_BATTERY_STATUS_NOT_INST  
The battery is not installed.

LWM2M_DEVICE_BATTERY_STATUS_UNKNOWN  
The battery information is not available.
LWM2M Firmware Update object states

An LwM2M client or the LwM2M Firmware Update object use the following codes to represent the LwM2M Firmware Update state (5/0/3).

STATE_IDLE
   Idle.
   Before downloading or after successful updating.

STATE_DOWNLOADING
   Downloading.
   The data sequence is being downloaded.

STATE_DOWNLOADED
   Downloaded.
   The whole data sequence has been downloaded.

STATE_UPDATING
   Updating.
   The device is being updated.

LWM2M Firmware Update object result codes

After processing a firmware update, the client sets the result via one of the following codes via lwm2m_engine_set_u8("5/0/5", [result code])

RESULT_DEFAULT
   Initial value.

RESULT_SUCCESS
   Firmware updated successfully.

RESULT_NO_STORAGE
   Not enough flash memory for the new firmware package.

RESULT_OUT_OF_MEM
   Out of RAM during downloading process.

RESULT_CONNECTION_LOST
   Connection lost during downloading process.

RESULT_INTEGRITY_FAILED
   Integrity check failure for new downloaded package.

RESULT_UNSUP_FW
   Unsupported package type.
RESULT_INVALID_URI
Invalid URI.

RESULT_UPDATE_FAILED
Firmware update failed.

RESULT_UNSUP_PROTO
Unsupported protocol.

Defines

LWM2M_OBJLNK_MAX_ID
Maximum value for Objlnk resource fields.

LWM2M_RES_DATA_READ_ONLY
Resource read-only value bit.

LWM2M_RES_DATA_FLAG_RO
Resource read-only flag.

LWM2M_HAS_RES_FLAG(res, f)
Read resource flags helper macro.

LWM2M_RD_CLIENT_EVENT_REG_UPDATE_FAILURE
Define for old event name keeping backward compatibility.

LWM2M_RD_CLIENT_FLAG_BOOTSTRAP
Run bootstrap procedure in current session.

LWM2M_MAX_PATH_STR_SIZE
LwM2M path maximum length.

Typedefs

typedef void (*lwm2m_socket_fault_cb_t)(int error)
Callback function called when a socket error is encountered.

Param error
Error code

typedef void (*lwm2m_observe_cb_t)(enum lwm2m_observe_event event, struct lwm2m_obj_path *path, void *user_data)
Observe callback indicating observer adds and deletes, and notification ACKs and time-outs.

Param event
[in] Observer add/delete or notification ack/timeout

Param path
[in] LwM2M path
**Param user_data**

[in] Pointer to user_data buffer, as provided in `send_traceable_notification()`. Used to determine for which data the ACKed/timed out notification was.

```c
typedef void (*lwm2m_ctx_event_cb_t)(struct lwm2m_ctx *ctx, enum lwm2m_rd_client_event event)
```

Asynchronous RD client event callback.

- **Param ctx**
  - [in] LwM2M context generating the event

- **Param event**
  - [in] LwM2M RD client event code

```c
typedef void *(*lwm2m_engine_get_data_cb_t)(uint16_t obj_inst_id, uint16_t res_id, uint16_t res_inst_id, size_t *data_len)
```

Asynchronous callback to get a resource buffer and length.

Prior to accessing the data buffer of a resource, the engine can use this callback to get the buffer pointer and length instead of using the resource's data buffer.

The client or LwM2M objects can register a function of this type via:

- `lwm2m_engine_register_read_callback()`
- `lwm2m_engine_register_pre_write_callback()`

- **Param obj_inst_id**
  - [in] Object instance ID generating the callback.

- **Param res_id**
  - [in] Resource ID generating the callback.

- **Param res_inst_id**
  - [in] Resource instance ID generating the callback (typically 0 for non-multi instance resources).

- **Param data_len**
  - [out] Length of the data buffer.

- **Return**
  - Callback returns a pointer to the data buffer or NULL for failure.

```c
typedef int (*lwm2m_engine_set_data_cb_t)(uint16_t obj_inst_id, uint16_t res_id, uint16_t res_inst_id, uint8_t *data, uint16_t data_len, bool last_block, size_t total_size)
```

Asynchronous callback when data has been set to a resource buffer.

After changing the data of a resource buffer, the LwM2M engine can make use of this callback to pass the data back to the client or LwM2M objects.

A function of this type can be registered via:

- `lwm2m_engine_register_validate_callback()`
- `lwm2m_engine_register_post_write_callback()`

- **Param obj_inst_id**
  - [in] Object instance ID generating the callback.

- **Param res_id**
  - [in] Resource ID generating the callback.

- **Param res_inst_id**
  - [in] Resource instance ID generating the callback (typically 0 for non-multi instance resources).

- **Param data**
  - [in] Pointer to data.
Param data_len
   [in] Length of the data.

Param last_block
   [in] Flag used during block transfer to indicate the last block of data. For non-block transfers this is always false.

Param total_size
   [in] Expected total size of data for a block transfer. For non-block transfers this is 0.

Return
   Callback returns a negative error code (errno.h) indicating reason of failure or 0 for success.

typedef int (*lwm2m_engine_user_cb_t)(uint16_t obj_inst_id)
   Asynchronous event notification callback.
   Various object instance and resource-based events in the LwM2M engine can trigger a callback of this function type: object instance create, and object instance delete.
   Register a function of this type via: lwm2m_engine_register_create_callback()
     lwm2m_engine_register_delete_callback()

   Param obj_inst_id
      [in] Object instance ID generating the callback.

   Return
      Callback returns a negative error code (errno.h) indicating reason of failure or 0 for success.

typedef int (*lwm2m_engine_execute_cb_t)(uint16_t obj_inst_id, uint8_t *args, uint16_t args_len)
   Asynchronous execute notification callback.
   Resource executes trigger a callback of this type.
   Register a function of this type via: lwm2m_engine_register_exec_callback()

   Param obj_inst_id
      [in] Object instance ID generating the callback.

   Param args
      [in] Pointer to execute arguments payload. (This can be NULL if no arguments are provided)

   Param args_len
      [in] Length of argument payload in bytes.

   Return
      Callback returns a negative error code (errno.h) indicating reason of failure or 0 for success.

typedef void (*lwm2m_send_cb_t)(enum lwm2m_send_status status)
   Callback returning send status.

Enums

enum lwm2m_observe_event
   Observe callback events.

Values:
enumerator LWM2M_OBSERVE_EVENT_OBSERVER_ADDED
   Observer added.

enumerator LWM2M_OBSERVE_EVENT_OBSERVER_REMOVED
   Observer removed.

enumerator LWM2M_OBSERVE_EVENT_NOTIFY_ACK
   Notification ACKed.

enumerator LWM2M_OBSERVE_EVENT_NOTIFY_TIMEOUT
   Notification timed out.

enum lwm2m_socket_states
   Different traffic states of the LwM2M socket.
   This information can be used to give hints for the network interface that can decide
   what kind of power management should be used.
   These hints are given from CoAP layer messages, so usage of DTLS might affect the
   actual number of expected datagrams.
   Values:

   enumerator LWM2M_SOCKET_STATE_ONGOING
      Ongoing traffic is expected.

   enumerator LWM2M_SOCKET_STATE_ONE_RESPONSE
      One response is expected for the next message.

   enumerator LWM2M_SOCKET_STATE_LAST
      Next message is the last one.

   enumerator LWM2M_SOCKET_STATE_NO_DATA
      No more data is expected.

enum lwm2m_rd_client_event
   LwM2M RD client events.
   LwM2M client events are passed back to the event_cb function in
   lwm2m_rd_client_start()
   Values:

   enumerator LWM2M_RD_CLIENT_EVENT_NONE

   enumerator LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_REG_FAILURE

   enumerator LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_REG_COMPLETE

   enumerator LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_TRANSFER_COMPLETE

   enumerator LWM2M_RD_CLIENT_EVENT_REGISTRATION_FAILURE

6.3. Networking
enumerator LWM2M_RD_CLIENT_EVENT_REGISTRATION_COMPLETE
enumerator LWM2M_RD_CLIENT_EVENT_REG_TIMEOUT
enumerator LWM2M_RD_CLIENT_EVENT_REG_UPDATE_COMPLETE
enumerator LWM2M_RD_CLIENT_EVENT_DEREGISTER_FAILURE
enumerator LWM2M_RD_CLIENT_EVENT_DISCONNECT
enumerator LWM2M_RD_CLIENT_EVENT_QUEUE_MODE_RX_OFF
enumerator LWM2M_RD_CLIENT_EVENT_ENGINE_SUSPENDED
enumerator LWM2M_RD_CLIENT_EVENT_NETWORK_ERROR
enumerator LWM2M_RD_CLIENT_EVENT_REG_UPDATE
enumerator LWM2M_RD_CLIENT_EVENT_DEREGISTER
enumerator LWM2M_RD_CLIENT_EVENT_SERVER.Disabled

enum lwm2m_send_status
LwM2M send status.
LwM2M send status are generated back to the lwm2m_send_cb_t function in lwm2m_send_cb()

Values:

enumerator LWM2M_SEND_STATUS_SUCCESS
enumerator LWM2M_SEND_STATUS_FAILURE
enumerator LWM2M_SEND_STATUS_TIMEOUT

enum lwm2m_security_mode_e
Security modes as defined in LwM2M Security object.

Values:

enumerator LWM2M_SECURITY_PSK = 0
Pre-Shared Key mode.
enumerator LWM2M_SECURITY_RAW_PK = 1
Raw Public Key mode.
enumerator LWM2M_SECURITY_CERT = 2
Certificate mode.
enumerator LWM2M_SECURITY_NOSEC = 3
  NoSec mode.

enumerator LWM2M_SECURITY_CERT_EST = 4
  Certificate mode with EST.

Functions

int lwm2m_device_add_err(uint8_t error_code)
  Register a new error code with LwM2M Device object.

  Parameters

  Returns
  0 for success or negative in case of error.

void lwm2m_firmware_set_write_cb(lwm2m_engine_set_data_cb_t cb)
  Set data callback for firmware block transfer.

  Parameters
  • cb – [in] A callback function to receive the block transfer data

lwm2m_engine_set_data_cb_t lwm2m_firmware_get_write_cb(void)
  Get the data callback for firmware block transfer writes.

  Returns
  A registered callback function to receive the block transfer data

void lwm2m_firmware_set_write_cb_inst(uint16_t obj_inst_id, lwm2m_engine_set_data_cb_t cb)
  Set data callback for firmware block transfer.

  Parameters
  • obj_inst_id – [in] Object instance ID
  • cb – [in] A callback function to receive the block transfer data

lwm2m_engine_set_data_cb_t lwm2m_firmware_get_write_cb_inst(uint16_t obj_inst_id)
  Get the data callback for firmware block transfer writes.

  Parameters
  • obj_inst_id – [in] Object instance ID

  Returns
  A registered callback function to receive the block transfer data

void lwm2m_firmware_set_cancel_cb(lwm2m_engine_user_cb_t cb)
  Set callback for firmware update cancel.

  Parameters
  • cb – [in] A callback function to perform actions on firmware update cancel.

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```c
lwm2m_engine_user_cb_t lwm2m_firmware_get_cancel_cb(void)
Get a callback for firmware update cancel.
```

**Returns**
A registered callback function perform actions on firmware update cancel.

```c
void lwm2m_firmware_set_cancel_cb_inst(uint16_t obj_inst_id, lwm2m_engine_user_cb_t cb)
Set data callback for firmware update cancel.
LwM2M clients use this function to register a callback to perform actions on firmware update cancel.
```

**Parameters**

- obj_inst_id – [in] Object instance ID

```c
lwm2m_engine_user_cb_t lwm2m_firmware_get_cancel_cb_inst(uint16_t obj_inst_id)
Get the callback for firmware update cancel.
```

**Parameters**

- obj_inst_id – [in] Object instance ID

**Returns**
A registered callback function perform actions on firmware update cancel.

```c
void lwm2m_firmware_set_update_cb(lwm2m_engine_execute_cb_t cb)
Set data callback to handle firmware update execute events.
LwM2M clients use this function to register a callback for receiving the update resource “execute” operation on the LwM2M Firmware Update object.
```

**Parameters**

- cb – [in] A callback function to receive the execute event.

```c
lwm2m_engine_execute_cb_t lwm2m_firmware_get_update_cb(void)
Get the event callback for firmware update execute events.
```

**Returns**
A registered callback function to receive the execute event.

```c
void lwm2m_firmware_set_update_cb_inst(uint16_t obj_inst_id, lwm2m_engine_execute_cb_t cb)
Set data callback to handle firmware update execute events.
LwM2M clients use this function to register a callback for receiving the update resource “execute” operation on the LwM2M Firmware Update object.
```

**Parameters**

- obj_inst_id – [in] Object instance ID
- cb – [in] A callback function to receive the execute event.

```c
lwm2m_engine_execute_cb_t lwm2m_firmware_get_update_cb_inst(uint16_t obj_inst_id)
Get the event callback for firmware update execute events.
```

**Parameters**

- obj_inst_id – [in] Object instance ID

**Returns**
A registered callback function to receive the execute event.
int lwm2m_swmgmt_set_activate_cb(uint16_t obj_inst_id, lwm2m_engine_execute_cb_t cb)
Set callback to handle software activation requests.
The callback will be executed when the LWM2M execute operation gets called on the corresponding object's Activate resource instance.

Parameters
• obj_inst_id – [in] The instance number to set the callback for.
• cb – [in] A callback function to receive the execute event.

Returns
0 on success, otherwise a negative integer.

int lwm2m_swmgmt_set_deactivate_cb(uint16_t obj_inst_id, lwm2m_engine_execute_cb_t cb)
Set callback to handle software deactivation requests.
The callback will be executed when the LWM2M execute operation gets called on the corresponding object's Deactivate resource instance.

Parameters
• obj_inst_id – [in] The instance number to set the callback for.
• cb – [in] A callback function to receive the execute event.

Returns
0 on success, otherwise a negative integer.

int lwm2m_swmgmt_set_install_package_cb(uint16_t obj_inst_id, lwm2m_engine_execute_cb_t cb)
Set callback to handle software install requests.
The callback will be executed when the LWM2M execute operation gets called on the corresponding object's Install resource instance.

Parameters
• obj_inst_id – [in] The instance number to set the callback for.
• cb – [in] A callback function to receive the execute event.

Returns
0 on success, otherwise a negative integer.

int lwm2m_swmgmt_set_delete_package_cb(uint16_t obj_inst_id, lwm2m_engine_execute_cb_t cb)
Set callback to handle software uninstall requests.
The callback will be executed when the LWM2M execute operation gets called on the corresponding object's Uninstall resource instance.

Parameters
• obj_inst_id – [in] The instance number to set the callback for.
• cb – [in] A callback function for handling the execute event.

Returns
0 on success, otherwise a negative integer.

int lwm2m_swmgmt_set_read_package_version_cb(uint16_t obj_inst_id, lwm2m_engine_get_data_cb_t cb)
Set callback to read software package.
The callback will be executed when the LWM2M read operation gets called on the corresponding object.
Parameters

- obj_inst_id – [in] The instance number to set the callback for.
- cb – [in] A callback function for handling the read event.

Returns

0 on success, otherwise a negative integer.

```c
int lwm2m_swmgmt_set_write_package_cb(uint16_t obj_inst_id, lwm2m_engine_set_data_cb_t cb)
```

Set data callback for software management block transfer.

The callback will be executed when the LWM2M block write operation gets called on the corresponding object’s resource instance.

Parameters

- obj_inst_id – [in] The instance number to set the callback for.
- cb – [in] A callback function for handling the block write event.

Returns

0 on success, otherwise a negative integer.

```c
int lwm2m_swmgmt_install_completed(uint16_t obj_inst_id, int error_code)
```

Function to be called when a Software Management object instance completed the Install operation.

return 0 on success, otherwise a negative integer.

Parameters

- error_code – [in] The result code of the operation. Zero on success otherwise it should be a negative integer.

```c
void lwm2m_event_log_set_read_log_data_cb(lwm2m_engine_get_data_cb_t cb)
```

Set callback to read log data.

The callback will be executed when the LWM2M read operation gets called on the corresponding object.

Parameters

- cb – [in] A callback function for handling the read event.

```c
int lwm2m_engine_update_observer_min_period(struct lwm2m_ctx *client_ctx, const char *pathstr, uint32_t period_s)
```

Change an observer's pmin value.

*Deprecated:*

Use `lwm2m_update_observer_min_period()` instead.

LwM2M clients use this function to modify the pmin attribute for an observation being made. Example to update the pmin of a temperature sensor value being observed:

```c
lwm2m_engine_update_observer_min_period("client_ctx, 3303/0/5700", 5);
```

Parameters

- client_ctx – [in] LwM2M context
- pathstr – [in] LwM2M path string “obj/obj-inst/res”
- period_s – [in] Value of pmin to be given (in seconds).
### Returns

0 for success or negative in case of error.

```c
int lwm2m_update_observer_min_period(struct lwm2m_ctx *client_ctx, const struct lwm2m_obj_path *path, uint32_t period_s)
```

Change an observer's pmin value.

LwM2M clients use this function to modify the pmin attribute for an observation being made. Example to update the pmin of a temperature sensor value being observed:

```c
lwm2m_update_observer_min_period(client_ctx, &LWM2M_OBJ(3303, 0, 5700), 5);
```

**Parameters**

- `client_ctx` – [in] LwM2M context
- `path` – [in] LwM2M path as a struct
- `period_s` – [in] Value of pmin to be given (in seconds).

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_engine_update_observer_max_period(struct lwm2m_ctx *client_ctx, const char *pathstr, uint32_t period_s)
```

Change an observer's pmax value.

**Deprecated:**

Use `lwm2m_update_observer_max_period()` instead.

LwM2M clients use this function to modify the pmax attribute for an observation being made. Example to update the pmax of a temperature sensor value being observed:

```c
lwm2m_engine_update_observer_max_period("client_ctx, 3303/0/5700", 5);
```

**Parameters**

- `client_ctx` – [in] LwM2M context
- `pathstr` – [in] LwM2M path string “obj/obj-inst/res”
- `period_s` – [in] Value of pmax to be given (in seconds).

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_update_observer_max_period(struct lwm2m_ctx *client_ctx, const struct lwm2m_obj_path *path, uint32_t period_s)
```

Change an observer's pmax value.

LwM2M clients use this function to modify the pmax attribute for an observation being made. Example to update the pmax of a temperature sensor value being observed:

```c
lwm2m_update_observer_max_period(client_ctx, &LWM2M_OBJ(3303, 0, 5700), 5);
```

**Parameters**

- `client_ctx` – [in] LwM2M context
- `path` – [in] LwM2M path as a struct
- `period_s` – [in] Value of pmax to be given (in seconds).

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_engine_create_obj_inst(const char *pathstr)
```

Create an LwM2M object instance.
LwM2M clients use this function to create non-default LwM2M objects: Example to create first temperature sensor object: `lwm2m_engine_create_obj_inst("3303/0")`;

**Parameters**
- `pathstr` – [in] LwM2M path string “obj/obj-inst”

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_create_object_inst(const struct lwm2m_obj_path *path)
```
Create an LwM2M object instance.

LwM2M clients use this function to create non-default LwM2M objects: Example to create first temperature sensor object: `lwm2m_create_obj_inst(&LWM2M_OBJ(3303, 0));`

**Parameters**
- `path` – [in] LwM2M path as a struct

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_delete_obj_inst(const char *pathstr)
```
Delete an LwM2M object instance.

**Deprecated:**
Use `lwm2m_delete_obj_inst()` instead.

LwM2M clients use this function to delete LwM2M objects.

**Parameters**
- `pathstr` – [in] LwM2M path string “obj/obj-inst”

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_delete_object_inst(const struct lwm2m_obj_path *path)
```
Delete an LwM2M object instance.

LwM2M clients use this function to delete LwM2M objects.

**Parameters**
- `path` – [in] LwM2M path as a struct

**Returns**
0 for success or negative in case of error.

```c
void lwm2m_registry_lock(void)
```
Locks the registry for this thread.

Use this function before writing to multiple resources. This halts the lwm2m main thread until all the write-operations are finished.

```c
void lwm2m_registry_unlock(void)
```
Unlocks the registry previously locked by `lwm2m_registry_lock()`.

```c
int lwm2m_engine_set_opaque(const char *pathstr, const char *data_ptr, uint16_t data_len)
```
Set resource (instance) value (opaque buffer)
Zephyr Project Documentation, Release 3.6.0-rc3

Deprecated:
Use `lwm2m_set_opaque()` instead.

Parameters
- `data_ptr` – [in] Data buffer
- `data_len` – [in] Length of buffer

Returns
0 for success or negative in case of error.

```c
int lwm2m_set_opaque(const struct lwm2m_obj_path *path, const char *data_ptr, uint16_t data_len)
```

Set resource (instance) value (opaque buffer)

Parameters
- `path` – [in] LwM2M path as a struct
- `data_ptr` – [in] Data buffer
- `data_len` – [in] Length of buffer

Returns
0 for success or negative in case of error.

```c
int lwm2m_engine_set_string(const char *pathstr, const char *data_ptr)
```

Set resource (instance) value (string)

Deprecated:
Use `lwm2m_set_string()` instead.

Parameters
- `data_ptr` – [in] NULL terminated char buffer

Returns
0 for success or negative in case of error.

```c
int lwm2m_set_string(const struct lwm2m_obj_path *path, const char *data_ptr)
```

Set resource (instance) value (string)

Parameters
- `path` – [in] LwM2M path as a struct
- `data_ptr` – [in] NULL terminated char buffer

Returns
0 for success or negative in case of error.

```c
int lwm2m_engine_set_u8(const char *pathstr, uint8_t value)
```

Set resource (instance) value (u8)

Deprecated:
Use `lwm2m_set_u8()` instead.

Parameters
• **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
  • **value** – [in] u8 value

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_set_u8(const struct lwm2m_obj_path *path, uint8_t value)
```
Set resource (instance) value (u8)

**Parameters**
• **path** – [in] LwM2M path as a struct
  • **value** – [in] u8 value

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_set_u16(const char *pathstr, uint16_t value)
```
Set resource (instance) value (u16)

*Deprecated:*
Use `lwm2m_set_u16()` instead.

**Parameters**
• **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
  • **value** – [in] u16 value

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_set_u16(const struct lwm2m_obj_path *path, uint16_t value)
```
Set resource (instance) value (u16)

**Parameters**
• **path** – [in] LwM2M path as a struct
  • **value** – [in] u16 value

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_set_u32(const char *pathstr, uint32_t value)
```
Set resource (instance) value (u32)

*Deprecated:*
Use `lwm2m_set_u32()` instead.

**Parameters**
• **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
  • **value** – [in] u32 value

**Returns**
0 for success or negative in case of error.
int lwm2m_set_u32(const struct lwm2m_obj_path *path, uint32_t value)
Set resource (instance) value (u32)

Parameters
• path – [in] LwM2M path as a struct
• value – [in] u32 value

Returns
0 for success or negative in case of error.

int lwm2m_engine_set_u64(const char *pathstr, uint64_t value)
Set resource (instance) value (u64)

Deprecated:
Use lwm2m_set_u64() instead.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [in] u64 value

Returns
0 for success or negative in case of error.

int lwm2m_set_u64(const struct lwm2m_obj_path *path, uint64_t value)
Set resource (instance) value (u64)

Deprecated:
Unsigned 64bit value type does not exits. This is internally handled as a int64_t.
Use lwm2m_set_s64() instead.

Parameters
• path – [in] LwM2M path as a struct
• value – [in] u64 value

Returns
0 for success or negative in case of error.

int lwm2m_engine_set_s8(const char *pathstr, int8_t value)
Set resource (instance) value (s8)

Deprecated:
Use lwm2m_set_s8() instead.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [in] s8 value

Returns
0 for success or negative in case of error.
int lwm2m_set_s8(const struct lwm2m_obj_path *path, int8_t value)
Set resource (instance) value (s8)

**Parameters**
- *path* – [in] LwM2M path as a struct
- *value* – [in] s8 value

**Returns**
0 for success or negative in case of error.

int lwm2m_engine_set_s16(const char *pathstr, int16_t value)
Set resource (instance) value (s16)

*Deprecated:*
Use `lwm2m_set_s16()` instead.

**Parameters**
- *value* – [in] s16 value

**Returns**
0 for success or negative in case of error.

int lwm2m_set_s16(const struct lwm2m_obj_path *path, int16_t value)
Set resource (instance) value (s16)

**Parameters**
- *path* – [in] LwM2M path as a struct
- *value* – [in] s16 value

**Returns**
0 for success or negative in case of error.

int lwm2m_engine_set_s32(const char *pathstr, int32_t value)
Set resource (instance) value (s32)

*Deprecated:*
Use `lwm2m_set_s32()` instead.

**Parameters**
- *value* – [in] s32 value

**Returns**
0 for success or negative in case of error.

int lwm2m_set_s32(const struct lwm2m_obj_path *path, int32_t value)
Set resource (instance) value (s32)

**Parameters**
- *path* – [in] LwM2M path as a struct
- *value* – [in] s32 value

**Returns**
0 for success or negative in case of error.
int lwm2m_engine_set_s64(const char *pathstr, int64_t value)
Set resource (instance) value (s64)

 Deprecated:
Use lwm2m_set_s64() instead.

 Parameters
 • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
 • value – [in] s64 value

 Returns
0 for success or negative in case of error.

int lwm2m_set_s64(const struct lwm2m_obj_path *path, int64_t value)
Set resource (instance) value (s64)

 Parameters
 • path – [in] LwM2M path as a struct
 • value – [in] s64 value

 Returns
0 for success or negative in case of error.

int lwm2m_engine_set_bool(const char *pathstr, bool value)
Set resource (instance) value (bool)

 Deprecated:
Use lwm2m_set_bool() instead.

 Parameters
 • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
 • value – [in] bool value

 Returns
0 for success or negative in case of error.

int lwm2m_set_bool(const struct lwm2m_obj_path *path, bool value)
Set resource (instance) value (bool)

 Parameters
 • path – [in] LwM2M path as a struct
 • value – [in] bool value

 Returns
0 for success or negative in case of error.

int lwm2m_engine_set_float(const char *pathstr, const double *value)
Set resource (instance) value (double)

 Deprecated:
Use lwm2m_set_f64() instead.

 Parameters
• **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”  
• **value** – [in] double value

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_set_f64(const struct lwm2m_obj_path *path, const double value);
```
Set resource (instance) value (double)

**Parameters**
• **path** – [in] LwM2M path as a struct  
• **value** – [in] double value

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_set_objlnk(const char *pathstr, const struct lwm2m_objlnk *value);
```
Set resource (instance) value (Objlnk)

*Deprecated:*
Use `lwm2m_set_objlnk()` instead.

**Parameters**
• **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”  
• **value** – [in] pointer to the `lwm2m_objlnk` structure

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_set_objlnk(const struct lwm2m_obj_path *path, const struct lwm2m_objlnk *value);
```
Set resource (instance) value (Objlnk)

**Parameters**
• **path** – [in] LwM2M path as a struct  
• **value** – [in] pointer to the `lwm2m_objlnk` structure

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_set_time(const char *pathstr, time_t value);
```
Set resource (instance) value (Time)

*Deprecated:*
Use `lwm2m_set_time()` instead.

**Parameters**
• **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”  
• **value** – [in] Epoch timestamp

**Returns**
0 for success or negative in case of error.
int lwm2m_set_time(const struct lwm2m_obj_path *path, time_t value)
Set resource (instance) value (Time)

Parameters
- path – [in] LwM2M path as a struct
- value – [in] Epoch timestamp

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_opaque(const char *pathstr, void *buf, uint16_t buflen)
Get resource (instance) value (opaque buffer)

Deprecated:
Use lwm2m_get_opaque() instead.

Parameters
- buf – [out] Data buffer to copy data into
- buflen – [in] Length of buffer

Returns
0 for success or negative in case of error.

int lwm2m_get_opaque(const struct lwm2m_obj_path *path, void *buf, uint16_t buflen)
Get resource (instance) value (opaque buffer)

Parameters
- path – [in] LwM2M path as a struct
- buf – [out] Data buffer to copy data into
- buflen – [in] Length of buffer

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_string(const char *pathstr, void *str, uint16_t buflen)
Get resource (instance) value (string)

Deprecated:
Use lwm2m_get_string() instead.

Parameters
- str – [out] String buffer to copy data into
- buflen – [in] Length of buffer

Returns
0 for success or negative in case of error.
int lwm2m_get_string(const struct lwm2m_obj_path *path, void *str, uint16_t buflen)
Get resource (instance) value (string)

Parameters
• path – [in] LwM2M path as a struct
• str – [out] String buffer to copy data into
• buflen – [in] Length of buffer

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_u8(const char *pathstr, uint8_t *value)
Get resource (instance) value (u8)

Deprecated:
Use lwm2m_get_u8() instead.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res/(res-inst)”
• value – [out] u8 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_get_u8(const struct lwm2m_obj_path *path, uint8_t *value)
Get resource (instance) value (u8)

Parameters
• path – [in] LwM2M path as a struct
• value – [out] u8 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_u16(const char *pathstr, uint16_t *value)
Get resource (instance) value (u16)

Deprecated:
Use lwm2m_get_u16() instead.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res/(res-inst)”
• value – [out] u16 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_get_u16(const struct lwm2m_obj_path *path, uint16_t *value)
Get resource (instance) value (u16)

Parameters
• path – [in] LwM2M path as a struct
• value – [out] u16 buffer to copy data into
Returns
0 for success or negative in case of error.

int lwm2m_engine_get_u32(const char *pathstr, uint32_t *value)
Get resource (instance) value (u32)

Deprecated:
Use lwm2m_get_u32() instead.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] u32 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_get_u32(const struct lwm2m_obj_path *path, uint32_t *value)
Get resource (instance) value (u32)

Parameters
• path – [in] LwM2M path as a struct
• value – [out] u32 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_u64(const char *pathstr, uint64_t *value)
Get resource (instance) value (u64)

Deprecated:
Use lwm2m_get_u64() instead.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] u64 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_get_u64(const struct lwm2m_obj_path *path, uint64_t *value)
Get resource (instance) value (u64)

Deprecated:
Unsigned 64bit value type does not exits. This is internally handled as a int64_t.
Use lwm2m_get_s64() instead.

Parameters
• path – [in] LwM2M path as a struct
• value – [out] u64 buffer to copy data into

Returns
0 for success or negative in case of error.
int lwm2m_engine_get_s8(const char *pathstr, int8_t *value)
Get resource (instance) value (s8)

*Deprecated*: Use `lwm2m_get_s8()` instead.

**Parameters**
- `value` – [out] s8 buffer to copy data into

**Returns**
0 for success or negative in case of error.

int lwm2m_get_s8(const struct lwm2m_obj_path *path, int8_t *value)
Get resource (instance) value (s8)

**Parameters**
- `path` – [in] LwM2M path as a struct
- `value` – [out] s8 buffer to copy data into

**Returns**
0 for success or negative in case of error.

int lwm2m_engine_get_s16(const char *pathstr, int16_t *value)
Get resource (instance) value (s16)

*Deprecated*: Use `lwm2m_get_s16()` instead.

**Parameters**
- `value` – [out] s16 buffer to copy data into

**Returns**
0 for success or negative in case of error.

int lwm2m_get_s16(const struct lwm2m_obj_path *path, int16_t *value)
Get resource (instance) value (s16)

**Parameters**
- `path` – [in] LwM2M path as a struct
- `value` – [out] s16 buffer to copy data into

**Returns**
0 for success or negative in case of error.

int lwm2m_engine_get_s32(const char *pathstr, int32_t *value)
Get resource (instance) value (s32)

*Deprecated*: Use `lwm2m_get_s32()` instead.

**Parameters**
• **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• **value** – [out] s32 buffer to copy data into

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_get_s32(const struct lwm2m_obj_path *path, int32_t *value)
```
Get resource (instance) value (s32)

**Parameters**
- **path** – [in] LwM2M path as a struct
- **value** – [out] s32 buffer to copy data into

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_get_s64(const char *pathstr, int64_t *value)
```
Get resource (instance) value (s64)

**Deprecated:**
Use `lwm2m_get_s64()` instead.

**Parameters**
- **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- **value** – [out] s64 buffer to copy data into

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_get_s64(const char *pathstr, int64_t *value)
```
Get resource (instance) value (s64)

**Parameters**
- **path** – [in] LwM2M path as a struct
- **value** – [out] s64 buffer to copy data into

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_get_bool(const char *pathstr, bool *value)
```
Get resource (instance) value (bool)

**Deprecated:**
Use `lwm2m_get_bool()` instead.

**Parameters**
- **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- **value** – [out] bool buffer to copy data into

**Returns**
0 for success or negative in case of error.
int lwm2m_get_bool(const struct lwm2m_obj_path *path, bool *value)
Get resource (instance) value (bool)

Parameters
• path – [in] LwM2M path as a struct
• value – [out] bool buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_float(const char *pathstr, double *buf)
Get resource (instance) value (double)

Deprecated:
Use lwm2m_get_f64() instead.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res/(res-inst)”
• buf – [out] double buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_get_f64(const struct lwm2m_obj_path *path, double *value)
Get resource (instance) value (double)

Parameters
• path – [in] LwM2M path as a struct
• value – [out] double buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_objlnk(const char *pathstr, struct lwm2m_objlnk *buf)
Get resource (instance) value (Objlnk)

Deprecated:
Use lwm2m_get_objlnk() instead.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res/(res-inst)”
• buf – [out] lwm2m_objlnk buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_get_objlnk(const struct lwm2m_obj_path *path, struct lwm2m_objlnk *buf)
Get resource (instance) value (Objlnk)

Parameters
• path – [in] LwM2M path as a struct
• buf – [out] lwm2m_objlnk buffer to copy data into

Returns
0 for success or negative in case of error.
int lwm2m_engine_get_time(const char *pathstr, time_t *buf)
Get resource (instance) value (Time)

*Deprecated:*
Use *lwm2m_get_time()* instead.

**Parameters**
- **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- **buf** – [out] time_t pointer to copy data

**Returns**
0 for success or negative in case of error.

int lwm2m_get_time(const struct lwm2m_obj_path *path, time_t *buf)
Get resource (instance) value (Time)

**Parameters**
- **path** – [in] LwM2M path as a struct
- **buf** – [out] time_t pointer to copy data

**Returns**
0 for success or negative in case of error.

int lwm2m_engine_register_read_callback(const char *pathstr, lwm2m_engine_get_data_cb_t cb)
Set resource (instance) read callback.

*Deprecated:*
Use *lwm2m_register_read_callback()* instead.

LwM2M clients can use this to set the callback function for resource reads when data handling in the LwM2M engine needs to be bypassed. For example reading back opaque binary data from external storage.

This callback should not generally be used for any data that might be observed as engine does not have any knowledge of data changes.

When separate buffer for data should be used, use *lwm2m_engine_set_res_buf()* instead to set the storage.

**Parameters**
- **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- **cb** – [in] Read resource callback

**Returns**
0 for success or negative in case of error.

int lwm2m_register_read_callback(const struct lwm2m_obj_path *path, lwm2m_engine_get_data_cb_t cb)
Set resource (instance) read callback.

LwM2M clients can use this to set the callback function for resource reads when data handling in the LwM2M engine needs to be bypassed. For example reading back opaque binary data from external storage.

This callback should not generally be used for any data that might be observed as engine does not have any knowledge of data changes.
When separate buffer for data should be used, use `lwm2m_engine_set_res_buf()` instead to set the storage.

**Parameters**
- `path` – [in] LwM2M path as a struct
- `cb` – [in] Read resource callback

**Returns**
- 0 for success or negative in case of error.

```c
int lwm2m_engine_register_pre_write_callback(const char *pathstr, lwm2m_engine_get_data_cb_t cb)
```

Set resource (instance) pre-write callback.

**Deprecated:**
Use `lwm2m_register_pre_write_callback()` instead.

This callback is triggered before setting the value of a resource. It can pass a special data buffer to the engine so that the actual resource value can be calculated later, etc.

**Parameters**
- `cb` – [in] Pre-write resource callback

**Returns**
- 0 for success or negative in case of error.

```c
int lwm2m_register_pre_write_callback(const struct lwm2m_obj_path *path, lwm2m_engine_get_data_cb_t cb)
```

Set resource (instance) pre-write callback.

This callback is triggered before setting the value of a resource. It can pass a special data buffer to the engine so that the actual resource value can be calculated later, etc.

**Parameters**
- `path` – [in] LwM2M path as a struct
- `cb` – [in] Pre-write resource callback

**Returns**
- 0 for success or negative in case of error.

```c
int lwm2m_engine_register_validate_callback(const char *pathstr, lwm2m_engine_set_data_cb_t cb)
```

Set resource (instance) validation callback.

**Deprecated:**
Use `lwm2m_register_validate_callback()` instead.

This callback is triggered before setting the value of a resource to the resource data buffer. The callback allows an LwM2M client or object to validate the data before writing and notify an error if the data should be discarded for any reason (by returning a negative error code).

**Note:** All resources that have a validation callback registered are initially decoded into a temporary validation buffer. Make sure that CON-
FIG_LWM2M_ENGINE_VALIDATION_BUFFER_SIZE is large enough to store each of the validated resources (individually).

### Parameters

- **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- **cb** – [in] Validate resource data callback

### Returns

0 for success or negative in case of error.

```c
int lwm2m_register_validate_callback(const struct lwm2m_obj_path *path,
                                      lwm2m_engine_set_data_cb_t cb)
```

Set resource (instance) validation callback.

This callback is triggered before setting the value of a resource to the resource data buffer.

The callback allows an LwM2M client or object to validate the data before writing and notify an error if the data should be discarded for any reason (by returning a negative error code).

**Note:** All resources that have a validation callback registered are initially decoded into a temporary validation buffer. Make sure that CONFIG_LWM2M_ENGINE_VALIDATION_BUFFER_SIZE is large enough to store each of the validated resources (individually).

### Parameters

- **path** – [in] LwM2M path as a struct
- **cb** – [in] Validate resource data callback

### Returns

0 for success or negative in case of error.

```c
int lwm2m_engine_register_post_write_callback(const char *pathstr,
                                               lwm2m_engine_set_data_cb_t cb)
```

Set resource (instance) post-write callback.

**Deprecated:**

Use `lwm2m_register_post_write_callback()` instead.

This callback is triggered after setting the value of a resource to the resource data buffer.

It allows an LwM2M client or object to post-process the value of a resource or trigger other related resource calculations.

### Parameters

- **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- **cb** – [in] Post-write resource callback

### Returns

0 for success or negative in case of error.
int lwm2m_register_post_write_callback(const struct lwm2m_obj_path *path, lwm2m_engine_set_data_cb_t cb)

Set resource (instance) post-write callback.
This callback is triggered after setting the value of a resource to the resource data buffer.
It allows an LwM2M client or object to post-process the value of a resource or trigger other related resource calculations.

Parameters
• path – [in] LwM2M path as a struct
• cb – [in] Post-write resource callback

Returns
0 for success or negative in case of error.

int lwm2m_engine_register_exec_callback(const char *pathstr, lwm2m_engine_execute_cb_t cb)

Set resource execute event callback.

Deprecated:
Use lwm2m_register_exec_callback() instead.
This event is triggered when the execute method of a resource is enabled.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res”
• cb – [in] Execute resource callback

Returns
0 for success or negative in case of error.

int lwm2m_register_exec_callback(const struct lwm2m_obj_path *path, lwm2m_engine_execute_cb_t cb)

Set resource execute event callback.
This event is triggered when the execute method of a resource is enabled.

Parameters
• path – [in] LwM2M path as a struct
• cb – [in] Execute resource callback

Returns
0 for success or negative in case of error.

int lwm2m_engine_register_create_callback(uint16_t obj_id, lwm2m_engine_user_cb_t cb)

Set object instance create event callback.

Deprecated:
Use lwm2m_register_create_callback instead.
This event is triggered when an object instance is created.

Parameters
• obj_id – [in] LwM2M object id
• cb – [in] Create object instance callback
Returns
0 for success or negative in case of error.

```c
int lwm2m_register_create_callback(uint16_t obj_id, lwm2m_engine_user_cb_t cb)
```

Set object instance create event callback.
This event is triggered when an object instance is created.

**Parameters**
- `obj_id` – [in] LwM2M object id
- `cb` – [in] Create object instance callback

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_register_delete_callback(uint16_t obj_id, lwm2m_engine_user_cb_t cb)
```

Set object instance delete event callback.

*Deprecated:*
Use `lwm2m_register_delete_callback` instead
This event is triggered when an object instance is deleted.

**Parameters**
- `obj_id` – [in] LwM2M object id
- `cb` – [in] Delete object instance callback

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_register_delete_callback(uint16_t obj_id, lwm2m_engine_user_cb_t cb)
```

Set object instance delete event callback.
This event is triggered when an object instance is deleted.

**Parameters**
- `obj_id` – [in] LwM2M object id
- `cb` – [in] Delete object instance callback

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_set_res_buf(const char *pathstr, void *buffer_ptr, uint16_t buffer_len, uint16_t data_len, uint8_t data_flags)
```

Set data buffer for a resource.

*Deprecated:*
Use `lwm2m_set_res_buf()` instead.
Use this function to set the data buffer and flags for the specified LwM2M resource.

**Parameters**
- `buffer_ptr` – [in] Data buffer pointer
- `buffer_len` – [in] Length of buffer
- `data_len` – [in] Length of existing data in the buffer
• **data_flags** – [in] Data buffer flags (such as read-only, etc)

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_set_res_buf(const struct lwm2m_obj_path *path, void *buffer_ptr, uint16_t buffer_len, uint16_t data_len, uint8_t data_flags)
```

Set data buffer for a resource.

Use this function to set the data buffer and flags for the specified LwM2M resource.

**Parameters**

- `path` – [in] LwM2M path as a struct
- `buffer_ptr` – [in] Data buffer pointer
- `buffer_len` – [in] Length of buffer
- `data_len` – [in] Length of existing data in the buffer
- `data_flags` – [in] Data buffer flags (such as read-only, etc)

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_engine_set_res_data(const char *pathstr, void *data_ptr, uint16_t data_len, uint8_t data_flags)
```

Set data buffer for a resource.

Use this function to set the data buffer and flags for the specified LwM2M resource.

**Deprecated:**

Use `lwm2m_set_res_buf()` instead, so you can define buffer size and data size separately.

**Parameters**

- `data_ptr` – [in] Data buffer pointer
- `data_len` – [in] Length of buffer
- `data_flags` – [in] Data buffer flags (such as read-only, etc)

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_engine_set_res_data_len(const char *pathstr, uint16_t data_len)
```

Update data size for a resource.

**Deprecated:**

Use `lwm2m_set_res_data_len()` instead.

Use this function to set the new size of data in the buffer if you write to a buffer received by `lwm2m_engine_get_res_buf()`.

**Parameters**

- `data_len` – [in] Length of data

**Returns**

0 for success or negative in case of error.
int lwm2m_set_res_data_len(const struct lwm2m_obj_path *path, uint16_t data_len)
Update data size for a resource.

Use this function to set the new size of data in the buffer if you write to a buffer received by `lwm2m_engine_get_res_buf()`.

Parameters
- `path` – [in] LwM2M path as a struct
- `data_len` – [in] Length of data

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_res_buf(const char *pathstr, void **buffer_ptr, uint16_t *buffer_len, uint16_t *data_len, uint8_t *data_flags)
Get data buffer for a resource.

Deprecated:
Use `lwm2m_get_res_buf()` instead.

Use this function to get the data buffer information for the specified LwM2M resource.
If you directly write into the buffer, you must use `lwm2m_engine_set_res_data_len()` function to update the new size of the written data.
All parameters except `pathstr` can NULL if you don’t want to read those values.

Parameters
- `buffer_ptr` – [out] Data buffer pointer
- `buffer_len` – [out] Length of buffer
- `data_len` – [out] Length of existing data in the buffer
- `data_flags` – [out] Data buffer flags (such as read-only, etc)

Returns
0 for success or negative in case of error.

int lwm2m_get_res_buf(const struct lwm2m_obj_path *path, void **buffer_ptr, uint16_t *buffer_len, uint16_t *data_len, uint8_t *data_flags)
Get data buffer for a resource.

Use this function to get the data buffer information for the specified LwM2M resource.
If you directly write into the buffer, you must use `lwm2m_set_res_data_len()` function to update the new size of the written data.
All parameters, except for the `pathstr`, can be NULL if you don’t want to read those values.

Parameters
- `path` – [in] LwM2M path as a struct
- `buffer_ptr` – [out] Data buffer pointer
- `buffer_len` – [out] Length of buffer
- `data_len` – [out] Length of existing data in the buffer
- `data_flags` – [out] Data buffer flags (such as read-only, etc)

Returns
0 for success or negative in case of error.
int lwm2m_engine_get_res_data(const char *pathstr, void **data_ptr, uint16_t *data_len, uint8_t *data_flags)
Get data buffer for a resource.
Use this function to get the data buffer information for the specified LwM2M resource.

 Deprecated:
Use lwm2m_get_res_buf() as it can tell you the size of the buffer as well.

 Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(res-inst)”
• data_ptr – [out] Data buffer pointer
• data_len – [out] Length of existing data in the buffer
• data_flags – [out] Data buffer flags (such as read-only, etc)

 Returns
0 for success or negative in case of error.

int lwm2m_engine_create_res_inst(const char *pathstr)
Create a resource instance.

 Deprecated:
Use lwm2m_create_res_inst() instead.

LwM2M clients use this function to create multi-resource instances:
Example to create 0 instance of device available power sources:
lwm2m_engine_create_res_inst("3/0/6/0");

 Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res/res-inst”

 Returns
0 for success or negative in case of error.

int lwm2m_create_res_inst(const struct lwm2m_obj_path *path)
Create a resource instance.

LwM2M clients use this function to create multi-resource instances:
Example to create 0 instance of device available power sources:
lwm2m_create_res_inst(&LWM2M_OBJ(3, 0, 6, 0));

 Parameters
• path – [in] LwM2M path as a struct

 Returns
0 for success or negative in case of error.

int lwm2m_engine_delete_res_inst(const char *pathstr)
Delete a resource instance.

 Deprecated:
Use lwm2m_delete_res_inst() instead.

Use this function to remove an existing resource instance

 Parameters
• \texttt{pathstr} – [in] LwM2M path string “obj/obj-inst/res/res-inst”

**Returns**
0 for success or negative in case of error.

\texttt{int lwm2m_delete_res_inst(const struct lwm2m_obj_path *}\
\texttt{path)}

Delete a resource instance.

Use this function to remove an existing resource instance

**Parameters**
• \texttt{path} – [in] LwM2M path as a struct

**Returns**
0 for success or negative in case of error.

\texttt{int lwm2m_update_device_service_period(uint32_t period_ms)}

Update the period of the device service.

Change the duration of the periodic device service that notifies the current time.

**Parameters**
• \texttt{period_ms} – [in] New period for the device service (in milliseconds)

**Returns**
0 for success or negative in case of error.

\texttt{bool lwm2m_engine_path_is_observed(const char *}\
\texttt{pathstr)}

Check whether a path is observed.

*Deprecated:*
Use \texttt{lwm2m_path_is_observed()} instead.

**Parameters**
• \texttt{pathstr} – [in] LwM2M path string to check, e.g. “3/0/1”

**Returns**
true when there exists an observation of the same level or lower as the given path, false if it doesn’t or path is not a valid LwM2M-path. E.g. true if path refers to a resource and the parent object has an observation, false for the inverse.

\texttt{bool lwm2m_path_is_observed(const struct lwm2m_obj_path *}\
\texttt{path)}

Check whether a path is observed.

**Parameters**
• \texttt{path} – [in] LwM2M path as a struct to check

**Returns**
true when there exists an observation of the same level or lower as the given path, false if it doesn’t or path is not a valid LwM2M-path. E.g. true if path refers to a resource and the parent object has an observation, false for the inverse.

\texttt{int lwm2m_engine_stop(struct lwm2m_ctx *}\
\texttt{client_ctx)}

Stop the LwM2M engine.

LwM2M clients normally do not need to call this function as it is called within lwm2m_rd_client. However, if the client does not use the RD client implementation, it will need to be called manually.

**Parameters**
int lwm2m_engine_start(struct lwm2m_ctx *client_ctx)

Start the LwM2M engine.

LwM2M clients normally do not need to call this function as it is called by lwm2m_rd_client_start(). However, if the client does not use the RD client implementation, it will need to be called manually.

Parameters

- **client_ctx** – [in] LwM2M context

Returns

- 0 for success or negative in case of error.

void lwm2m_acknowledge(struct lwm2m_ctx *client_ctx)

Acknowledge the currently processed request with an empty ACK.

LwM2M engine by default sends piggybacked responses for requests. This function allows to send an empty ACK for a request earlier (from the application callback). The LwM2M engine will then send the actual response as a separate CON message after all callbacks are executed.

Parameters

- **client_ctx** – [in] LwM2M context

int lwm2m_rd_client_start(struct lwm2m_ctx *client_ctx, const char *ep_name, uint32_t flags, lwm2m_ctx_event_cb_t event_cb, lwm2m_observe_cb_t observe_cb)

Start the LwM2M RD (Registration / Discovery) Client.

The RD client sits just above the LwM2M engine and performs the necessary actions to implement the “Registration interface”. For more information see Section “Client Registration Interface” of LwM2M Technical Specification.

NOTE: lwm2m_engine_start() is called automatically by this function.

Parameters

- **client_ctx** – [in] LwM2M context
- **ep_name** – [in] Registered endpoint name
- **flags** – [in] Flags used to configure current LwM2M session.
- **event_cb** – [in] Client event callback function
- **observe_cb** – [in] Observe callback function called when an observer was added or deleted, and when a notification was acked or has timed out

Returns

- 0 for success, -EINPROGRESS when client is already running or negative error codes in case of failure.

int lwm2m_rd_client_stop(struct lwm2m_ctx *client_ctx, lwm2m_ctx_event_cb_t event_cb, bool deregister)

Stop the LwM2M RD (De-register) Client.

The RD client sits just above the LwM2M engine and performs the necessary actions to implement the “Registration interface”. For more information see Section “Client Registration Interface” of the LwM2M Technical Specification.
Parameters

- **client_ctx** – [in] LwM2M context
- **event_cb** – [in] Client event callback function
- **deregister** – [in] True to deregister the client if registered. False to force close the connection.

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_engine_pause(void)
```

Suspend the LwM2M engine Thread.

Suspend LwM2M engine. Use case could be when network connection is down. LwM2M Engine indicate before it suspend by LWM2M_RD_CLIENT_EVENT_ENGINE_SUSPENDED event.

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_engine_resume(void)
```

Resume the LwM2M engine thread.

Resume suspended LwM2M engine. After successful resume call engine will do full registration or registration update based on suspended time. Event's LWM2M_RD_CLIENT_EVENT_REGISTRATION_COMPLETE or LWM2M_RD_CLIENT_EVENT_REG_UPDATE_COMPLETE indicate that client is connected to server.

**Returns**

0 for success or negative in case of error.

```c
void lwm2m_rd_client_update(void)
```

Trigger a Registration Update of the LwM2M RD Client.

```c
char *lwm2m_path_log_buf(char *buf, struct lwm2m_obj_path *path)
```

Helper function to print path objects' contents to log.

**Parameters**

- **buf** – [in] The buffer to use for formatting the string
- **path** – [in] The path to stringify

**Returns**

Resulting formatted path string

```c
int lwm2m_engine_send(struct lwm2m_ctx *ctx, char const *path_list[], uint8_t path_list_size, bool confirmation_request)
```

LwM2M SEND operation to given path list

**Deprecated:**

Use `lwm2m_send_cb()` instead.

**Parameters**

- **ctx** – LwM2M context
- **path_list** – LwM2M Path string list
- **path_list_size** – Length of path list. Max size is CONFIG_LWM2M_COMPOSITE_PATH_LIST_SIZE
- **confirmation_request** – True request confirmation for operation.
Returns
0 for success or negative in case of error.

```c
int lwm2m_send(struct lwm2m_ctx *ctx, const struct lwm2m_obj_path path_list[], uint8_t path_list_size, bool confirmation_request)
```

LwM2M SEND operation to given path list

 Deprecated:
Use `lwm2m_send_cb()` instead.

**Parameters**
- `ctx` – LwM2M context
- `path_list` – LwM2M path struct list
- `path_list_size` – Length of path list. Max size is `CONFIG_LWM2M_COMPOSITE_PATH_LIST_SIZE`
- `confirmation_request` – True request confirmation for operation.

Returns
0 for success or negative in case of error.

```c
int lwm2m_send_cb(struct lwm2m_ctx *ctx, const struct lwm2m_obj_path path_list[], uint8_t path_list_size, lwm2m_send_cb_t reply_cb)
```

LwM2M SEND operation to given path list asynchronously with confirmation callback

**Parameters**
- `ctx` – LwM2M context
- `path_list` – LwM2M path struct list
- `path_list_size` – Length of path list. Max size is `CONFIG_LWM2M_COMPOSITE_PATH_LIST_SIZE`
- `reply_cb` – Callback triggered with confirmation state or NULL if not used

Returns
0 for success or negative in case of error.

```c
struct lwm2m_ctx *lwm2m_rd_client_ctx(void)
```

Returns LwM2M client context

```c
int lwm2m_engine_enable_cache(char const *resource_path, struct lwm2m_time_series_elem *data_cache, size_t cache_len)
```

Enable data cache for a resource.

 Deprecated:
Use `lwm2m_enable_cache` instead

Application may enable caching of resource data by allocating buffer for LwM2M engine to use. Buffer must be size of struct `lwm2m_time_series_elem` times `cache_len`

**Parameters**
- `resource_path` – LwM2M resourcepath string “obj/obj-inst/res(/res-inst)”
• data_cache – Pointer to Data cache array
• cache_len – number of cached entries

Returns
0 for success or negative in case of error.

int lwm2m_enable_cache(const struct lwm2m_obj_path *path, struct lwm2m_time_series_elem *data_cache, size_t cache_len)

Enable data cache for a resource.
Application may enable caching of resource data by allocating buffer for LwM2M engine to use. Buffer must be size of struct lwm2m_time_series_elem times cache_len

Parameters
• path – LwM2M path to resource as a struct
• data_cache – Pointer to Data cache array
• cache_len – number of cached entries

Returns
0 for success or negative in case of error.

int lwm2m_security_mode(struct lwm2m_ctx *ctx)

Read security mode from selected security object instance.
This data is valid only if RD client is running.

Parameters
• ctx – Pointer to client context.

Returns
int Positive values are lwm2m_security_mode_e, negative error codes otherwise.

int lwm2m_set_default_sockopt(struct lwm2m_ctx *ctx)

Set default socket options for DTLS connections.
The engine calls this when lwm2m_ctx::set_socketoptions is not overwritten. You can call this from the overwritten callback to set extra options after or before defaults.

Parameters
• ctx – Client context

Returns
0 for success or negative in case of error.

struct lwm2m_obj_path

#include <lwm2m.h> LwM2M object path structure.

Public Members

uint16_t obj_id
Object ID.

uint16_t obj_inst_id
Object instance ID.
Zephyr Project Documentation, Release 3.6.0-rc3

- **uint16_t res_id**
  Resource ID.

- **uint16_t res_inst_id**
  Resource instance ID.

- **uint8_t level**
  Path level (0-4).
  Ex. 4 = resource instance.

```
struct lwm2m_ctx
#include <lwm2m.h>
LwM2M context structure to maintain information for a single LwM2M connection.
```

**DTLS related information**

Available only when `CONFIG_LWM2M_DTLS_SUPPORT` is enabled and `lwm2m_ctx::use_dtls` is set to true.

- **int tls_tag**
  TLS tag is set by client as a reference used when the LwM2M engine calls `tls_credential_(add|delete)`

- **char *desthostname**
  Destination hostname.
  When MBEDTLS SNI is enabled socket must be set with destination server hostname.

- **uint16_t desthostnamelen**
  Destination hostname length.

- **bool hostname_verify**
  Flag to indicate if hostname verification is enabled.

- **int (*load_credentials)(struct lwm2m_ctx *client_ctx)**
  Custom load_credentials function.
  Client can set load_credentials function as a way of overriding the default behavior of `load_tls_credential()` in `lwm2m_engine.c`

**Public Members**

- **struct sockaddr remote_addr**
  Destination address storage.

- **void *processed_req**
  A pointer to currently processed request, for internal LwM2M engine use.
  The underlying type is `struct lwm2m_message`, but since it's declared in a private header and not exposed to the application, it's stored as a void pointer.
int (*set_socketoptions)(struct lwm2m_ctx *client_ctx)

Custom socket options.
Client can override default socket options by providing a callback that is called after a socket is created and before connect.

bool use_dtls
Flag to indicate if context should use DTLS.
Enabled via the use of coaps:// protocol prefix in connection information. NOTE: requires CONFIG_LWM2M_DTLS_SUPPORT

bool connection_suspended
Flag to indicate that the socket connection is suspended.
With queue mode, this will tell if there is a need to reconnect.

bool buffer_client_messages
Flag to indicate that the client is buffering Notifications and Send messages.
True value buffer Notifications and Send messages.

int sec_obj_inst
Current index of Security Object used for server credentials.

int srv_obj_inst
Current index of Server Object used in this context.

bool bootstrap_mode
Flag to enable BOOTSTRAP interface.
See Section “Bootstrap Interface” of LwM2M Technical Specification for more information.

int sock_fd
Socket File Descriptor.

lwm2m_socket_fault_cb_t fault_cb
Socket fault callback.
LwM2M processing thread will call this callback in case of socket errors on receive.

lwm2m_observe_cb_t observe_cb
Callback for new or cancelled observations, and acknowledged or timed out notifications.

lwm2m_ctx_event_cb_t event_cb
Callback for client events.

uint8_t validate_buf[CONFIG_LWM2M_ENGINE_VALIDATION_BUFFER_SIZE]
Validation buffer.
Used as a temporary buffer to decode the resource value before validation. On successful validation, its content is copied into the actual resource buffer.
void (*set_socket_state)(int fd, enum lwm2m_socket_states state)

Callback to indicate transmission states.

Client application may request LwM2M engine to indicate hints about transmission states and use that information to control various power saving modes.

struct lwm2m_time_series_elem
    #include <lwm2m.h> LwM2M Time series data structure.

Public Members

time_t t
    Cached data Unix timestamp.

struct lwm2m_objlnk
    #include <lwm2m.h> LWM2M Objlnk resource type structure.

Public Members

uint16_t obj_id
    Object ID.

uint16_t obj_inst
    Object instance ID.

MQTT

Overview  MQTT (Message Queuing Telemetry Transport) is an application layer protocol which works on top of the TCP/IP stack. It is a lightweight publish/subscribe messaging transport for machine-to-machine communication. For more information about the protocol itself, see http://mqtt.org/.

Zephyr provides an MQTT client library built on top of BSD sockets API. The library can be enabled with CONFIG_MQTT_LIB Kconfig option and is configurable at a per-client basis, with support for MQTT versions 3.1.0 and 3.1.1. The Zephyr MQTT implementation can be used with either plain sockets communicating over TCP, or with secure sockets communicating over TLS. See BSD Sockets for more information about Zephyr sockets.

MQTT clients require an MQTT server to connect to. Such a server, called an MQTT Broker, is responsible for managing client subscriptions and distributing messages published by clients. There are many implementations of MQTT brokers, one of them being Eclipse Mosquitto. See https://mosquitto.org/ for more information about the Eclipse Mosquitto project.
Sample usage

To create an MQTT client, a client context structure and buffers need to be defined:

```c
/* Buffers for MQTT client. */
static uint8_t rx_buffer[256];
static uint8_t tx_buffer[256];

/* MQTT client context */
static struct mqtt_client client_ctx;
```

Multiple MQTT client instances can be created in the application and managed independently. Additionally, a structure for MQTT Broker address information is needed. This structure must be accessible throughout the lifespan of the MQTT client and can be shared among MQTT clients:

```c
/* MQTT Broker address information. */
static struct sockaddr_storage broker;
```

An MQTT client library will notify MQTT events to the application through a callback function created to handle respective events:

```c
void mqtt_evt_handler(struct mqtt_client *client,
                      const struct mqtt_evt *evt)
{
    switch (evt->type) {
        /* Handle events here. */
    }
}
```

For a list of possible events, see API Reference.

The client context structure needs to be initialized and set up before it can be used. An example configuration for TCP transport is shown below:

```c
mqtt_client_init(&client_ctx);

/* MQTT client configuration */
client_ctx.broker = &broker;
client_ctx.evt_cb = mqtt_evt_handler;
client_ctx.client_id.utf8 = (uint8_t *)"zephyr_mqtt_client";
client_ctx.client_id.size = sizeof("zephyr_mqtt_client") - 1;
client_ctx.password = NULL;
client_ctx.user_name = NULL;
client_ctx.protocol_version = MQTT_VERSION_3_1_1;
client_ctx.transport.type = MQTT_TRANSPORT_NON_SECURE;

/* MQTT buffers configuration */
client_ctx.rx_buf = rx_buffer;
client_ctx.rx_buf_size = sizeof(rx_buffer);
client_ctx.tx_buf = tx_buffer;
client_ctx.tx_buf_size = sizeof(tx_buffer);
```

After the configuration is set up, the MQTT client can connect to the MQTT broker. Call the mqtt_connect function, which will create the appropriate socket, establish a TCP/TLS connection, and send an MQTT CONNECT message. When notified, the application should call the mqtt_input function to process the response received. Note, that mqtt_input is a non-blocking function, therefore the application should use socket poll to wait for the response. If the connection was successful, MQTT_EVT_CONNACK will be notified to the application through the callback function.

```c
rc = mqtt_connect(&client_ctx);
if (rc != 0) {
    return rc;
}
```

(continues on next page)
In the above code snippet, the MQTT callback function should set the connected flag upon a successful connection. If the connection fails at the MQTT level or a timeout occurs, the connection will be aborted, and the underlying socket closed.

After the connection is established, an application needs to call `mqtt_input` and `mqtt_live` functions periodically to process incoming data and upkeep the connection. If an MQTT message is received, an MQTT callback function will be called and an appropriate event notified.

The connection can be closed by calling the `mqtt_disconnect` function.

Zephyr provides sample code utilizing the MQTT client API. See `mqtt-publisher` for more information.

**Using MQTT with TLS** The Zephyr MQTT library can be used with TLS transport for secure communication by selecting a secure transport type (`MQTT_TRANSPORT_SECURE`) and some additional configuration information:

```c
client_ctx.transport.type = MQTT_TRANSPORT_SECURE;
struct mqtt_sec_config *tls_config = &client_ctx.transport.tls.config;

tls_config->peer_verify = TLS_PEER_VERIFY_REQUIRED;
tls_config->cipher_list = NULL;
tls_config->sec_tag_list = m_sec_tags;
tls_config->sec_tag_count = ARRAY_SIZE(m_sec_tags);
tls_config->hostname = MQTT_BROKER_HOSTNAME;
```

In this sample code, the `m_sec_tags` array holds a list of tags, referencing TLS credentials that the MQTT library should use for authentication. We do not specify `cipher_list`, to allow the use of all cipher suites available in the system. We set `hostname` field to broker hostname, which is required for server authentication. Finally, we enforce peer certificate verification by setting the `peer_verify` field.

Note, that TLS credentials referenced by the `m_sec_tags` array must be registered in the system first. For more information on how to do that, refer to secure sockets documentation.

An example of how to use TLS with MQTT is also present in `mqtt-publisher` sample application.

**API Reference**

**Related code samples**

**AWS IoT Core MQTT**
Connect to AWS IoT Core and publish messages using MQTT.

**MQTT publisher**
Send MQTT PUBLISH messages to an MQTT server.

**Microsoft Azure IoT Hub MQTT**
Connect to Azure IoT Hub and publish messages using MQTT.
**group mqtt_socket**

MQTT Client Implementation.

**Note:** The implementation assumes TCP module is enabled.

**Note:** By default the implementation uses MQTT version 3.1.1.

**Defines**

**MQTT_UTF8_LITERAL** (literal)

Initialize UTF-8 encoded string from C literal string.

Use it as follows:

```c
struct mqtt_utf8 password = MQTT_UTF8_LITERAL("my_pass");
```

**Parameters**

- **literal** – **[in]** Literal string from which to generate `mqtt_utf8` object.

**Typedefs**

typedef void (*`mqtt_evt_cb_t`)(struct `mqtt_client` *client, const struct `mqtt_evt` *evt)

Asynchronous event notification callback registered by the application.

**Param client**

**[in]** Identifies the client for which the event is notified.

**Param evt**

**[in]** Event description along with result and associated parameters (if any).

** Enums**

define `mqtt_evt_type`

MQTT Asynchronous Events notified to the application from the module through the callback registered by the application.

**Values**:

- **enumerator MQTT_EVT_CONNACK**

  Acknowledgment of connection request.

  Event result accompanying the event indicates whether the connection failed or succeeded.

- **enumerator MQTT_EVT_DISCONNECT**

  Disconnection Event.

  MQTT Client Reference is no longer valid once this event is received for the client.
enumerator MQTT_EVT_PUBLISH
Publish event received when message is published on a topic client is subscribed to.

**Note:** PUBLISH event structure only contains payload size, the payload data parameter should be ignored. Payload content has to be read manually with `mqtt_read_publish_payload` function.

enumerator MQTT_EVT_PUBACK
Acknowledgment for published message with QoS 1.

enumerator MQTT_EVT_PUBREC
Reception confirmation for published message with QoS 2.

enumerator MQTT_EVT_PUBREL
Release of published message with QoS 2.

enumerator MQTT_EVT_PUBCOMP
Confirmation to a publish release message with QoS 2.

enumerator MQTT_EVT_SUBACK
Acknowledgment to a subscribe request.

enumerator MQTT_EVT_UNSUBACK
Acknowledgment to a unsubscribe request.

enumerator MQTT_EVT_PINGRESP
Ping Response from server.

defines mqtt_version
MQTT version protocol level.

*Values:*

enumerator MQTT_VERSION_3_1_0 = 3
Protocol level for 3.1.0.

enumerator MQTT_VERSION_3_1_1 = 4
Protocol level for 3.1.1.

defines mqtt_qos
MQTT Quality of Service types.

*Values:*

enumerator MQTT_QOS_0_AT_MOST_ONCE = 0x00
Lowest Quality of Service, no acknowledgment needed for published message.
enumerator \texttt{MQTT\_QOS\_1\_AT\_LEAST\_ONCE} = 0x01
Medium Quality of Service, if acknowledgment expected for published message, duplicate messages permitted.

enumerator \texttt{MQTT\_QOS\_2\_EXACTLY\_ONCE} = 0x02
Highest Quality of Service, acknowledgment expected and message shall be published only once.
Message not published to interested parties unless client issues a PUBREL.

enum \texttt{mqtt\_conn\_return\_code}
MQTT CONNACK return codes.
\textit{Values:}

enumerator \texttt{MQTT\_CONNECTION\_ACCEPTED} = 0x00
Connection accepted.

enumerator \texttt{MQTT\_UNACCEPTABLE\_PROTOCOL\_VERSION} = 0x01
The Server does not support the level of the MQTT protocol requested by the Client.

enumerator \texttt{MQTT\_IDENTIFIER\_REJECTED} = 0x02
The Client identifier is correct UTF-8 but not allowed by the Server.

enumerator \texttt{MQTT\_SERVER\_UNAVAILABLE} = 0x03
The Network Connection has been made but the MQTT service is unavailable.

enumerator \texttt{MQTT\_BAD\_USER\_NAME\_OR\_PASSWORD} = 0x04
The data in the user name or password is malformed.

enumerator \texttt{MQTT\_NOT\_AUTHORIZED} = 0x05
The Client is not authorized to connect.

enum \texttt{mqtt\_suback\_return\_code}
MQTT SUBACK return codes.
\textit{Values:}

enumerator \texttt{MQTT\_SUBACK\_SUCCESS\_QoS\_0} = 0x00
Subscription with QoS 0 succeeded.

enumerator \texttt{MQTT\_SUBACK\_SUCCESS\_QoS\_1} = 0x01
Subscription with QoS 1 succeeded.

enumerator \texttt{MQTT\_SUBACK\_SUCCESS\_QoS\_2} = 0x02
Subscription with QoS 2 succeeded.

enumerator \texttt{MQTT\_SUBACK\_FAILURE} = 0x80
Subscription for a topic failed.
enum mqtt_transport_type
MQTT transport type.

Values:

enumerator MQTT_TRANSPORT_NON_SECURE
Use non secure TCP transport for MQTT connection.

enumerator MQTT_TRANSPORT_NUM
Shall not be used as a transport type.
Indicator of maximum transport types possible.

Functions

void mqtt_client_init(struct mqtt_client *client)
Initializes the client instance.

Note: Shall be called to initialize client structure, before setting any client parameters and before connecting to broker.

Parameters

• client – [in] Client instance for which the procedure is requested. Shall not be NULL.

int mqtt_connect(struct mqtt_client *client)
API to request new MQTT client connection.

Note: This memory is assumed to be resident until mqtt_disconnect is called.

Note: Any subsequent changes to parameters like broker address, user name, device id, etc. have no effect once MQTT connection is established.

Note: Default protocol revision used for connection request is 3.1.1. Please set client.protocol_version = MQTT_VERSION_3_1_0 to use protocol 3.1.0.

Note: Please modify CONFIG_MQTT_KEEPALIVE time to override default of 1 minute.

Parameters

• client – [in] Client instance for which the procedure is requested. Shall not be NULL.

Returns
0 or a negative error code (errno.h) indicating reason of failure.
int mqtt_publish(struct mqtt_client *client, const struct mqtt_publish_param *param)
API to publish messages on topics.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.
• param – [in] Parameters to be used for the publish message. Shall not be NULL.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_publish_qos1_ack(struct mqtt_client *client, const struct mqtt_puback_param *param)
API used by client to send acknowledgment on receiving QoS1 publish message.
Should be called on reception of MQTT_EVT_PUBLISH with QoS level MQTT_QOS_1_AT_LEAST_ONCE.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.
• param – [in] Identifies message being acknowledged.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_publish_qos2_receive(struct mqtt_client *client, const struct mqtt_pubrec_param *param)
API used by client to send acknowledgment on receiving QoS2 publish message.
Should be called on reception of MQTT_EVT_PUBLISH with QoS level MQTT_QOS_2_EXACTLY_ONCE.

Parameters
• client – [in] Identifies client instance for which the procedure is requested. Shall not be NULL.
• param – [in] Identifies message being acknowledged.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_publish_qos2_release(struct mqtt_client *client, const struct mqtt_pubrel_param *param)
API used by client to request release of QoS2 publish message.
Should be called on reception of MQTT_EVT_PUBREC.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.
• param – [in] Identifies message being released.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_publish_qos2_complete(struct mqtt_client *client, const struct mqtt_pubcomp_param *param)
API used by client to send acknowledgment on receiving QoS2 publish release message.
Should be called on reception of MQTT_EVT_PUBREL.

6.3. Networking
Parameters

- **client** – [in] Identifies client instance for which the procedure is requested. Shall not be NULL.
- **param** – [in] Identifies message being completed.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

```c
int mqtt_subscribe(struct mqtt_client *client, const struct mqtt_subscription_list *param)
```

API to request subscription of one or more topics on the connection.

Parameters

- **client** – [in] Identifies client instance for which the procedure is requested. Shall not be NULL.
- **param** – [in] Subscription parameters. Shall not be NULL.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

```c
int mqtt_unsubscribe(struct mqtt_client *client, const struct mqtt_subscription_list *param)
```

API to request unsubscription of one or more topics on the connection.

**Note:** QoS included in topic description is unused in this API.

Parameters

- **client** – [in] Identifies client instance for which procedure is requested.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

```c
int mqtt_ping(struct mqtt_client *client)
```

API to send MQTT ping.

The use of this API is optional, as the library handles the connection keep-alive on its own, see `mqtt_live`.

Parameters

- **client** – [in] Identifies client instance for which procedure is requested.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

```c
int mqtt_disconnect(struct mqtt_client *client)
```

API to disconnect MQTT connection.

Parameters

- **client** – [in] Identifies client instance for which procedure is requested.

Returns

0 or a negative error code (errno.h) indicating reason of failure.
int mqtt_abort(struct mqtt_client *client)
  API to abort MQTT connection.
  This will close the corresponding transport without closing the connection gracefully
  at the MQTT level (with disconnect message).

  **Parameters**
  - client – [in] Identifies client instance for which procedure is requested.

  **Returns**
  0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_live(struct mqtt_client *client)
  This API should be called periodically for the client to be able to keep the connection
  alive by sending Ping Requests if need be.

  **Note:** Application shall ensure that the periodicity of calling this function makes
  it possible to respect the Keep Alive time agreed with the broker on connection.
  mqtt_connect for details on Keep Alive time.

  **Parameters**
  - client – [in] Client instance for which the procedure is requested. Shall
    not be NULL.

  **Returns**
  0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_keepalive_time_left(const struct mqtt_client *client)
  Helper function to determine when next keep alive message should be sent.
  Can be used for instance as a source for poll timeout.

  **Parameters**
  - client – [in] Client instance for which the procedure is requested.

  **Returns**
  Time in milliseconds until next keep alive message is expected to be sent.
  Function will return -1 if keep alive messages are not enabled.

int mqtt_input(struct mqtt_client *client)
  Receive an incoming MQTT packet.
  The registered callback will be called with the packet content.

  **Note:** In case of PUBLISH message, the payload has to be read separately with
  mqtt_read_publish_payload function. The size of the payload to read is provided in
  the publish event structure.

  **Note:** This is a non-blocking call.

  **Parameters**
  - client – [in] Client instance for which the procedure is requested. Shall
    not be NULL.

  **Returns**
  0 or a negative error code (errno.h) indicating reason of failure.
int mqtt_read_publish_payload(struct mqtt_client *client, void *buffer, size_t length)
Read the payload of the received PUBLISH message.
This function should be called within the MQTT event handler, when MQTT PUBLISH message is notified.

Note: This is a non-blocking call.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.
• buffer – [out] Buffer where payload should be stored.
• length – [in] Length of the buffer, in bytes.

Returns
Number of bytes read or a negative error code (errno.h) indicating reason of failure.

int mqtt_read_publish_payload_blocking(struct mqtt_client *client, void *buffer, size_t length)
Blocking version of mqtt_read_publish_payload function.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.
• buffer – [out] Buffer where payload should be stored.
• length – [in] Length of the buffer, in bytes.

Returns
Number of bytes read or a negative error code (errno.h) indicating reason of failure.

int mqtt_readall_publish_payload(struct mqtt_client *client, uint8_t *buffer, size_t length)
Blocking version of mqtt_read_publish_payload function which runs until the required number of bytes are read.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.
• buffer – [out] Buffer where payload should be stored.
• length – [in] Number of bytes to read.

Returns
0 if success, otherwise a negative error code (errno.h) indicating reason of failure.

struct mqtt_utf8
#include <mqtt.h> Abstracts UTF-8 encoded strings.

Public Members
const uint8_t *utf8
  Pointer to UTF-8 string.

uint32_t size
  Size of UTF string, in bytes.

struct mqtt_binstr
  #include <mqtt.h> Abstracts binary strings.

Public Members

uint8_t *data
  Pointer to binary stream.

uint32_t len
  Length of binary stream.

struct mqtt_topic
  #include <mqtt.h> Abstracts MQTT UTF-8 encoded topic that can be subscribed to or published.

Public Members

struct mqtt_utf8 topic
  Topic on to be published or subscribed to.

uint8_t qos
  Quality of service requested for the subscription. 
  mqtt_qos for details.

struct mqtt_publish_message
  #include <mqtt.h> Parameters for a publish message.

Public Members

struct mqtt_topic topic
  Topic on which data was published.

struct mqtt_binstr payload
  Payload on the topic published.

struct mqtt_connack_param
  #include <mqtt.h> Parameters for a connection acknowledgment (CONNACK).
Public Members

uint8_t session_present_flag
The Session Present flag enables a Client to establish whether the Client and Server have a consistent view about whether there is already stored Session state.

enum mqtt_conn_return_code return_code
The appropriate non-zero Connect return code indicates if the Server is unable to process a connection request for some reason.

struct mqtt_puback_param
#include <mqtt.h> Parameters for MQTT publish acknowledgment (PUBACK).

Public Members

uint16_t message_id
Message id of the PUBLISH message being acknowledged.

struct mqtt_pubrec_param
#include <mqtt.h> Parameters for MQTT publish receive (PUBREC).

Public Members

uint16_t message_id
Message id of the PUBLISH message being acknowledged.

struct mqtt_pubrel_param
#include <mqtt.h> Parameters for MQTT publish release (PUBREL).

Public Members

uint16_t message_id
Message id of the PUBREC message being acknowledged.

struct mqtt_pubcomp_param
#include <mqtt.h> Parameters for MQTT publish complete (PUBCOMP).

Public Members

uint16_t message_id
Message id of the PUBREL message being acknowledged.

struct mqtt_suback_param
#include <mqtt.h> Parameters for MQTT subscription acknowledgment (SUBACK).
**Public Members**

`uint16_t message_id`

Message id of the SUBSCRIBE message being acknowledged.

**struct mqtt_binstr return_codes**

Return codes indicating maximum QoS level granted for each topic in the subscription list.

**struct mqtt_unsuback_param**

#include `<mqtt.h>` Parameters for MQTT unsubscribe acknowledgment (UNSUBACK).

**Public Members**

`uint16_t message_id`

Message id of the UNSUBSCRIBE message being acknowledged.

**struct mqtt_publish_param**

#include `<mqtt.h>` Parameters for a publish message (PUBLISH).

**Public Members**

**struct mqtt_publish_message message**

Messages including topic, QoS and its payload (if any) to be published.

`uint16_t message_id`

Message id used for the publish message.

Redundant for QoS 0.

`uint8_t dup_flag`

Duplicate flag.

If 1, it indicates the message is being retransmitted. Has no meaning with QoS 0.

`uint8_t retain_flag`

Retain flag.

If 1, the message shall be stored persistently by the broker.

**struct mqtt_subscription_list**

#include `<mqtt.h>` List of topics in a subscription request.

**Public Members**

**struct mqtt_topic *list**

Array containing topics along with QoS for each.
### Public Members

```c
union mqtt_evt_param

#include <mqtt.h> Defines event parameters notified along with asynchronous events to the application.
```

### Public Members

```c
struct mqtt_connack_param connack

Parameters accompanying MQTT_EVT_CONNACK event.
```

```c
struct mqtt_publish_param publish

Parameters accompanying MQTT_EVT_PUBLISH event.
```

**Note:** PUBLISH event structure only contains payload size, the payload data parameter should be ignored. Payload content has to be read manually with `mqtt_read_publish_payload` function.

```c
struct mqtt_puback_param puback

Parameters accompanying MQTT_EVT_PUBACK event.
```

```c
struct mqtt_pubrec_param pubrec

Parameters accompanying MQTT_EVT_PUBREC event.
```

```c
struct mqtt_pubrel_param pubrel

Parameters accompanying MQTT_EVT_PUBREL event.
```

```c
struct mqtt_pubcomp_param pubcomp

Parameters accompanying MQTT_EVT_PUBCOMP event.
```

```c
struct mqtt_suback_param suback

Parameters accompanying MQTT_EVT_SUBACK event.
```

```c
struct mqtt_unsuback_param unsuback

Parameters accompanying MQTT_EVT_UNSUBACK event.
```

```c
struct mqtt_evt

#include <mqtt.h> Defines MQTT asynchronous event notified to the application.
```

### Public Members
enum mqtt_evt_type type
    Identifies the event.

union mqtt_evt_param param
    Contains parameters (if any) accompanying the event.

int result
    Event result.
    0 or a negative error code (errno.h) indicating reason of failure.

struct mqtt_sec_config
    #include <mqtt.h> TLS configuration for secure MQTT transports.

Public Members

int peer_verify
    Indicates the preference for peer verification.

uint32_t cipher_count
    Indicates the number of entries in the cipher list.

const int *cipher_list
    Indicates the list of ciphers to be used for the session.
    May be NULL to use the default ciphers.

uint32_t sec_tag_count
    Indicates the number of entries in the sec tag list.

const sec_tag_t *sec_tag_list
    Indicates the list of security tags to be used for the session.

const char *hostname
    Peer hostname for ceritificate verification.
    May be NULL to skip hostname verification.

int cert_nocopy
    Indicates the preference for copying certificates to the heap.

struct mqtt_transport
    #include <mqtt.h> MQTT transport specific data.

Public Members

6.3. Networking
enum mqtt_transport_type type
    Transport type selection for client instance.

    mqtt_transport_type for possible values. MQTT_TRANSPORT_MAX is not a valid type.

int sock
    Socket descriptor.

struct mqtt_internal
    #include <mqtt.h> MQTT internal state.

Public Members

struct sys_mutex mutex
    Internal.
    Mutex to protect access to the client instance.

uint32_t last_activity
    Internal.
    Wall clock value (in milliseconds) of the last activity that occurred. Needed for periodic PING.

uint32_t state
    Internal.
    Client's state in the connection.

uint32_t rx_buf_datalen
    Internal.
    Packet length read so far.

uint32_t remaining_payload
    Internal.
    Remaining payload length to read.

struct mqtt_client
    #include <mqtt.h> MQTT Client definition to maintain information relevant to the client.

Public Members

struct mqtt_internal internal
    MQTT client internal state.

struct mqtt_transport transport
    MQTT transport configuration and data.
struct `mqtt_utf8` client_id
  Unique client identification to be used for the connection.

const void *`broker`
  Broker details, for example, address, port.
  Address type should be compatible with transport used.

struct `mqtt_utf8` *`user_name`
  User name (if any) to be used for the connection.
  NULL indicates no user name.

struct `mqtt_utf8` *`password`
  Password (if any) to be used for the connection.
  Note that if password is provided, user name shall also be provided. NULL indicates no password.

struct `mqtt_topic` *`will_topic`
  Will topic and QoS.
  Can be NULL.

struct `mqtt_utf8` *`will_message`
  Will message.
  Can be NULL. Non NULL value valid only if will topic is not NULL.

`mqtt_evt_cb_t` `evt_cb`
  Application callback registered with the module to get MQTT events.

uint8_t *`rx_buf`
  Receive buffer used for MQTT packet reception in RX path.

uint32_t `rx_buf_size`
  Size of receive buffer.

uint8_t *`tx_buf`
  Transmit buffer used for creating MQTT packet in TX path.

uint32_t `tx_buf_size`
  Size of transmit buffer.

uint16_t `keepalive`
  Keepalive interval for this client in seconds.
  Default is CONFIG_MQTT_KEEPALIVE.

uint8_t `protocol_version`
  MQTT protocol version.
int8_t unacked_ping
Unanswered PINGREQ count on this connection.

uint8_t will_retain
Will retain flag, 1 if will message shall be retained persistently.

uint8_t clean_session
Clean session flag indicating a fresh (1) or a retained session (0).
Default is CONFIG_MQTT_CLEAN_SESSION.

MQTT-SN

- Overview
- Sample usage
- Deviations from the standard
- API Reference

Overview  MQTT-SN is a variant of the well-known MQTT protocol - see MQTT.
In contrast to MQTT, MQTT-SN does not require a TCP transport, but is designed to be used over any message-based transport. Originally, it was mainly created with ZigBee in mind, but others like Bluetooth, UDP or even a UART can be used just as well.

Zephyr provides an MQTT-SN client library built on top of BSD sockets API. The library can be enabled with CONFIG_MQTT_SN_LIB Kconfig option and is configurable at a per-client basis, with support for MQTT-SN version 1.2. The Zephyr MQTT-SN implementation can be used with any message-based transport, but support for UDP is already built-in.


The MQTT-SN spec v1.2 can be found here: [https://www.oasis-open.org/committees/download.php/66091/MQTT-SN_spec_v1.2.pdf](https://www.oasis-open.org/committees/download.php/66091/MQTT-SN_spec_v1.2.pdf)

Sample usage  To create an MQTT-SN client, a client context structure and buffers need to be defined:

```c
/* Buffers for MQTT client. */
static uint8_t rx_buffer[256];
static uint8_t tx_buffer[256];

/* MQTT-SN client context */
static struct mqtt_sn_client client;
```

Multiple MQTT-SN client instances can be created in the application and managed independently. Additionally, a structure for the transport is needed as well. The library already comes with an example implementation for UDP.

```c
/* MQTT Broker address information. */
static struct mqtt_sn_transport tp;
```
The MQTT-SN library will inform clients about certain events using a callback.

```c
static void evt_cb(struct mqtt_sn_client *client, const struct mqtt_sn_evt *evt)
{
    switch(evt->type) {
    /* Handle events here. */
    }
}
```

For a list of possible events, see *API Reference*.

The client context structure needs to be initialized and set up before it can be used. An example configuration for UDP transport is shown below:

```c
struct mqtt_sn_data client_id = MQTT_SN_DATA_STRING_LITERAL("ZEPHYR");
struct sockaddr_in gateway = {0};

uint8_t tx_buf[256];
uint8_t rx_buf[256];

mqtt_sn_transport_udp_init(&tp, (struct sockaddr*)&gateway, sizeof((gateway)));
mqtt_sn_client_init(&client, &client_id, &tp.tp, evt_cb, tx_buf, sizeof(tx_buf), rx_buf,
                    sizeof(rx_buf));
```

After the configuration is set up, the MQTT-SN client can connect to the gateway. While the MQTT-SN protocol offers functionality to discover gateways through an advertisement mechanism, this is not implemented yet in the library.

Call the `mqtt_sn_connect` function, which will send a CONNECT message. The application should periodically call the `mqtt_sn_input` function to process the response received. The application does not have to call `mqtt_sn_input` if it knows that no data has been received (e.g. when using Bluetooth). Note that `mqtt_sn_input` is a non-blocking function, if the transport struct contains a poll compatible function pointer. If the connection was successful, `MQTT_SN_EVT_CONNECTED` will be notified to the application through the callback function.

```c
err = mqtt_sn_connect(client, false, true);
__ASSERT(err == 0, "mqtt_sn_connect() failed %d", err);

while (!) {
    mqtt_sn_input(&client);
    if (connected) {
        mqtt_sn_publish(&client, MQTT_SN_QOS_0, &topic_p, false, &pubdata);
    }
    k_sleep(K_MSEC(500));
}
```

In the above code snippet, the event handler function should set the connected flag upon a successful connection. If the connection fails at the MQTT level or a timeout occurs, the connection will be aborted.

After the connection is established, an application needs to call `mqtt_input` function periodically to process incoming data. Connection upkeep, on the other hand, is done automatically using a `k_work` item. If a MQTT message is received, an MQTT callback function will be called and an appropriate event notified.

The connection can be closed by calling the `mqtt_sn_disconnect` function. This has no effect on the transport, however. If you want to close the transport (e.g. the socket), call `mqtt_sn_client_deinit`, which will deinit the transport as well.

Zephyr provides sample code utilizing the MQTT-SN client API. See mqtt-sn-publisher for more information.
Deviations from the standard  Certain parts of the protocol are not yet supported in the library. * Pre-defined topic IDs * QoS -1 - it's most useful with predefined topics * Gateway discovery using ADVERTISE, SEARCHGW and GWINFO messages. * Setting the will topic and message after the initial connect * Forwarder Encapsulation

API Reference

Related code samples

MQTT-SN publisher
Send MQTT-SN PUBLISH messages to an MQTT-SN gateway.

group mqtt_sn_socket
MQTT-SN Client Implementation.
MQTT-SN Client's Application interface is defined in this header. Targets protocol version 1.2.

Defines

MQTT_SN_DATA_STRING_LITERAL(literal)
Initialize memory buffer from C literal string.
Use it as follows:
struct mqtt_sn_data topic = MQTT_SN_DATA_STRING_LITERAL("/zephyr");

Parameters

• literal – [in] Literal string from which to generate mqtt_sn_data object.

MQTT_SN_DATA_BYTES(...)Initialize memory buffer from single bytes.
Use it as follows:
struct mqtt_sn_data data = MQTT_SN_DATA_BYTES(0x13, 0x37);

Typedefs
typedef void (*mqtt_sn_evt_cb_t)(struct mqtt_sn_client *client, const struct mqtt_sn_evt *evt)
Asynchronous event notification callback registered by the application.

Param client
[in] Identifies the client for which the event is notified.

Param evt
[in] Event description along with result and associated parameters (if any).

Enums
enum mqtt_sn_qos
Quality of Service.
QoS 0-2 work the same as basic MQTT, QoS -1 is an MQTT-SN addition. QOS -1 is not supported yet.
Values:

enumerator MQTT_SN_QOS_0
  QOS 0.

enumerator MQTT_SN_QOS_1
  QOS 1.

enumerator MQTT_SN_QOS_2
  QOS 2.

enumerator MQTT_SN_QOS_M1
  QOS -1.

enum mqtt_sn_topic_type
  MQTT-SN topic types.
  Values:

enumerator MQTT_SN_TOPIC_TYPE_NORMAL
  Normal topic.
  It allows usage of any valid UTF-8 string as a topic name.

enumerator MQTT_SN_TOPIC_TYPE_PREDEF
  Pre-defined topic.
  It allows usage of a two-byte identifier representing a topic name for which the
  corresponding topic name is known in advance by both the client and the gate-
  way/server.

enumerator MQTT_SN_TOPIC_TYPE_SHORT
  Short topic.
  It allows usage of a two-byte string as a topic name.

enum mqtt_sn_return_code
  MQTT-SN return codes.
  Values:

enumerator MQTT_SN_CODE_ACCEPTED = 0x00
  Accepted.

enumerator MQTT_SN_CODE_REJECTED_CONGESTION = 0x01
  Rejected: congestion.

enumerator MQTT_SN_CODE_REJECTED_TOPIC_ID = 0x02
  Rejected: Invalid Topic ID.

enumerator MQTT_SN_CODE_REJECTED_NOTSUP = 0x03
  Rejected: Not Supported.
enum mqtt_sn_evt_type
   Event types that can be emitted by the library.
   Values:

   enumerator MQTT_SN_EVT_CONNECTED
      Connected to a gateway.

   enumerator MQTT_SN_EVT_DISCONNECTED
      Disconnected.

   enumerator MQTT_SN_EVT_ASLEEP
      Entered ASLEEP state.

   enumerator MQTT_SN_EVT_AWAKE
      Entered AWAKE state.

   enumerator MQTT_SN_EVT_PUBLISH
      Received a PUBLISH message.

   enumerator MQTT_SN_EVT_PINGRESP
      Received a PINGRESP.

Functions

int mqtt_sn_client_init(struct mqtt_sn_client *client, const struct mqtt_sn_data
                        *client_id, struct mqtt_sn_transport *transport, mqtt_sn_evt_cb_t
                        evt_cb, void *tx, size_t txsz, void *rx, size_t rxsz)

Initialize a client.

Parameters

- client – The MQTT-SN client to initialize.
- client_id – The ID to be used by the client.
- transport – The transport to be used by the client.
- evt_cb – The event callback function for the client.
- tx – Pointer to the transmit buffer.
- txsz – Size of the transmit buffer.
- rx – Pointer to the receive buffer.
- rxsz – Size of the receive buffer.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

void mqtt_sn_client_deinit(struct mqtt_sn_client *client)

Deinitialize the client.

This removes all topics and publishes, and also de-inits the transport.

Parameters

- client – The MQTT-SN client to deinitialize.
int mqtt_sn_connect(struct mqtt_sn_client *client, bool will, bool clean_session)
    Connect the client.

Parameters
    • client – The MQTT-SN client to connect.
    • will – Flag indicating if a Will message should be sent.
    • clean_session – Flag indicating if a clean session should be started.

Returns
    0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_sn_disconnect(struct mqtt_sn_client *client)
    Disconnect the client.

Parameters
    • client – The MQTT-SN client to disconnect.

Returns
    0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_sn_sleep(struct mqtt_sn_client *client, uint16_t duration)
    Set the client into sleep state.

Parameters
    • client – The MQTT-SN client to be put to sleep.
    • duration – Sleep duration (in seconds).

Returns
    0 on success, negative errno code on failure.

int mqtt_sn_subscribe(struct mqtt_sn_client *client, enum mqtt_sn_qos qos, struct mqtt_sn_data *topic_name)
    Subscribe to a given topic.

Parameters
    • client – The MQTT-SN client that should subscribe.
    • qos – The desired quality of service for the subscription.
    • topic_name – The name of the topic to subscribe to.

Returns
    0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_sn_unsubscribe(struct mqtt_sn_client *client, enum mqtt_sn_qos qos, struct mqtt_sn_data *topic_name)
    Unsubscribe from a topic.

Parameters
    • client – The MQTT-SN client that should unsubscribe.
    • qos – The quality of service used when subscribing.
    • topic_name – The name of the topic to unsubscribe from.

Returns
    0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_sn_publish(struct mqtt_sn_client *client, enum mqtt_sn_qos qos, struct mqtt_sn_data *topic_name, bool retain, struct mqtt_sn_data *data)
    Publish a value.

If the topic is not yet registered with the gateway, the library takes care of it.
Parameters

- client – The MQTT-SN client that should publish.
- qos – The desired quality of service for the publish.
- topic_name – The name of the topic to publish to.
- retain – Flag indicating if the message should be retained by the broker.
- data – The data to be published.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

```c
int mqtt_sn_input(struct mqtt_sn_client *client)
```

Check the transport for new incoming data.

Call this function periodically, or if you have good reason to believe there is any data. If the client's transport struct contains a poll-function, this function is non-blocking.

Parameters

- client – The MQTT-SN client to check for incoming data.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

```c
int mqtt_sn_get_topic_name(struct mqtt_sn_client *client, uint16_t id, struct mqtt_sn_data *topic_name)
```

Get topic name by topic ID.

Parameters

- topic_name – [out] Will be assigned to topic name.

Returns

0 on success, -ENOENT if topic ID doesn’t exist, or -EINVAL on invalid arguments.

```c
struct mqtt_sn_data
#include <mqtt_sn.h> Abstracts memory buffers.
```

Public Members

```c
const uint8_t *data
```

Pointer to data.

```c
uint16_t size
```

Size of data, in bytes.

```c
union mqtt_sn_evt_param
#include <mqtt_sn.h> Event metadata.
```
Public Members

struct mqtt_sn_data data
   The payload data associated with the event.

enum mqtt_sn_topic_type topic_type
   The type of topic for the event.

uint16_t topic_id
   The identifier for the topic of the event.

struct mqtt_sn_evt_param publish
   Structure holding publish event details.

struct mqtt_sn_evt
   #include <mqtt_sn.h> MQTT-SN event structure to be handled by the event callback.

Public Members

enum mqtt_sn_evt_type type
   Event type.

union mqtt_sn_evt_param param
   Event parameters.

struct mqtt_sn_transport
   #include <mqtt_sn.h> Structure to describe an MQTT-SN transport.
   MQTT-SN does not require transports to be reliable or to hold a connection. Transports just need to be frame-based, so you can use UDP, ZigBee, or even a simple UART, given some kind of framing protocol is used.

Public Members

int (*init)(struct mqtt_sn_transport *transport)
   Will be called once on client init to initialize the transport.
   Use this to open sockets or similar. May be NULL.

void (*deinit)(struct mqtt_sn_transport *transport)
   Will be called on client deinit.
   Use this to close sockets or similar. May be NULL.

int (*msg_send)(struct mqtt_sn_client *client, void *buf, size_t sz)
   Will be called by the library when it wants to send a message.
ssize_t (*recv)(struct mqtt_sn_client *client, void *buffer, size_t length)
   Will be called by the library when it wants to receive a message.
   Implementations should follow recv conventions.

int (*poll)(struct mqtt_sn_client *client)
   Check if incoming data is available.
   If poll() returns a positive number, recv must not block.
   May be NULL, but recv should not block then either.
   Return
       Positive number if data is available, or zero if there is none. Negative
       values signal errors.

struct mqtt_sn_client
   #include <mqtt_sn.h> Structure describing an MQTT-SN client.

Public Members

struct mqtt_sn_data client_id
   1-23 character unique client ID

struct mqtt_sn_data will_topic
   Topic for Will message.
   Must be initialized before connecting with will=true

struct mqtt_sn_data will_msg
   Will message.
   Must be initialized before connecting with will=true

enum mqtt_sn_qos will_qos
   Quality of Service for the Will message.

bool will_retain
   Flag indicating if the will message should be retained by the broker.

struct mqtt_sn_transport *transport
   Underlying transport to be used by the client.

struct net_buf_simple tx
   Buffer for outgoing data.

struct net_buf_simple rx
   Buffer for incoming data.

mqtt_sn_evt_cb_t evt_cb
   Event callback.
uint16_t next_msg_id
Message ID for the next message to be sent.

sys_slist_t publish
List of pending publish messages.

sys_slist_t topic
List of registered topics.

int state
Current state of the MQTT-SN client.

int64_t last_ping
Timestamp of the last ping request.

uint8_t ping_retries
Number of retries for failed ping attempts.

struct k_work_delayable process_work
Delayable work structure for processing MQTT-SN events.

TFTP Zephyr provides a simple TFTP client library that can enabled with CONFIG_MQTT_SN_LIB Kconfig option.
See TFTP client sample application for more information about the library usage.

API Reference Related code samples
TFTP client
Use the TFTP client library to get/put files from/to a TFTP server.

group tftp_client
TFTP Client Implementation.

TFTP client error codes.

TFTPC_SUCCESS
Success.

TFTPC_DUPLICATE_DATA
Duplicate data received.

TFTPC_BUFFER_OVERFLOW
User buffer is too small.

TFTPC_UNKNOWN_FAILURE
Unknown failure.
TFTPC_REMOTE_ERROR
Remote server error.

TFTPC_RETRIES_EXHAUSTED
Retries exhausted.

Defines

TFTP_BLOCK_SIZE
RFC1350: the file is sent in fixed length blocks of 512 bytes.
Each data packet contains one block of data, and must be acknowledged by an ac-
knowledged packet before the next packet can be sent. A data packet of less than
512 bytes signals termination of a transfer.

TFTP_HEADER_SIZE
RFC1350: For non-request TFTP message, the header contains 2-byte operation code
plus 2-byte block number or error code.

TFTPC_MAX_BUF_SIZE
Maximum amount of data that can be sent or received.

Typedefs

typedef void (*tftp_callback_t)(const struct tftp_evt *evt)
TFTP event notification callback registered by the application.

Param evt
[in] Event description along with result and associated parameters (if any).

Enums

enum tftp_evt_type
TFTP Asynchronous Events notified to the application from the module through the
callback registered by the application.

Values:

enumerator TFTP_EVT_DATA
DATA event when data is received from remote server.

Note: DATA event structure contains payload data and size.

enumerator TFTP_EVT_ERROR
ERROR event when error is received from remote server.

Note: ERROR event structure contains error code and message.
Functions

```c
int tftp_get(struct tftpc *client, const char *remote_file, const char *mode)
This function gets data from a “file” on the remote server.
```

**Note:** This function blocks until the transfer is completed or network error happens. The integrity of the client structure must be ensured until the function returns.

**Parameters**
- `client` – Client information of type `tftpc`.
- `remote_file` – Name of the remote file to get.
- `mode` – TFTP Client “mode” setting.

**Return values**
- `size` – size of data being received if the operation completed successfully.
- `TFTPC_BUFFER_OVERFLOW` – if the file is larger than the user buffer.
- `TFTPC_REMOTE_ERROR` – if the server failed to process our request.
- `TFTPC_RETRIES_EXHAUSTED` – if the client timed out waiting for server.
- `-EINVAL` – if `client` is NULL.

```c
int tftp_put(struct tftpc *client, const char *remote_file, const char *mode, const uint8_t *user_buf, uint32_t user_buf_size)
This function puts data to a “file” on the remote server.
```

**Note:** This function blocks until the transfer is completed or network error happens. The integrity of the client structure must be ensured until the function returns.

**Parameters**
- `client` – Client information of type `tftpc`.
- `remote_file` – Name of the remote file to put.
- `mode` – TFTP Client “mode” setting.
- `user_buf` – Data buffer containing the data to put.
- `user_buf_size` – Length of the data to put.

**Return values**
- `size` – size of data being sent if the operation completed successfully.
- `TFTPC_REMOTE_ERROR` – if the server failed to process our request.
- `TFTPC_RETRIES_EXHAUSTED` – if the client timed out waiting for server.
- `-EINVAL` – if `client` or `user_buf` is NULL or if `user_buf_size` is zero.

```c
struct tftp_data_param
#include <tftp.h> Parameters for data event.
```

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Public Members

uint8_t *data_ptr
   Pointer to binary data.

uint32_t len
   Length of binary data.

struct tftp_error_param
   #include <tftp.h> Parameters for error event.

Public Members

char *msg
   Error message.

int code
   Error code.

union tftp_evt_param
   #include <tftp.h> Defines event parameters notified along with asynchronous events to
   the application.

Public Members

struct tftp_data_param data
   Parameters accompanying TFTP_EVT_DATA event.

struct tftp_error_param error
   Parameters accompanying TFTP_EVT_ERROR event.

struct tftp_evt
   #include <tftp.h> Defines TFTP asynchronous event notified to the application.

Public Members

enum tftp_evt_type type
   Identifies the event.

union tftp_evt_param param
   Contains parameters (if any) accompanying the event.

struct tftpc
   #include <tftp.h> TFTP client definition to maintain information relevant to the client.
Note: Application must initialize server and callback before calling GET or PUT API with the tftpc structure.

Public Members

struct sockaddr server
    Socket address pointing to the remote TFTP server.

tftp_callback_t callback
    Event notification callback.
    No notification if NULL

uint8_t tftp_buf[(512 + 4)]
    Buffer for internal usage.

Network System Management

Network Configuration Library

- Overview
- Sample usage
- API Reference

Overview  The network configuration library sets up networking devices in a semi-automatic way during the system boot, based on user-supplied Kconfig options.
The following Kconfig options affect how configuration library will setup the system:
Table 24: Kconfig options for network configuration library

<table>
<thead>
<tr>
<th>Option name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>CONFIG_NET_CONFIG_SETTINGS</td>
<td>This option controls whether the network system is configured or initialized at all. If not set, then the config library is not used for initialization and the application needs to do all the network related configuration itself. If this option is set, then the user can optionally configure static IP addresses to be set to the first network interface in the system. Typically setting static IP addresses is only usable in testing and should not be used in production code. See the config library Kconfig file sub-sys/net/lib/config/Kconfig for specific options to set the static IP addresses.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_AUTO_INIT</td>
<td>The networking system is automatically configured when the device is started.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_INIT_TIMEOUT</td>
<td>This tells how long to wait for the networking to be ready and available. If for example IPv4 address from DHCPv4 is not received within this limit, then a call to net_config_init() will return error during the device startup.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_NEED_IPV4</td>
<td>The network application needs IPv4 support to function properly. This option makes sure the network application is initialized properly in order to use IPv4. If CONFIG_NET_IPV4 is not enabled, then setting this option will automatically enable IPv4.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_NEED_IPV6</td>
<td>The network application needs IPv6 support to function properly. This option makes sure the network application is initialized properly in order to use IPv6. If CONFIG_NET_IPV6 is not enabled, then setting this option will automatically enable IPv6.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_NEED_IPV6_ROUTER</td>
<td>If IPv6 is enabled, then this option tells that the network application needs IPv6 router to exists before continuing. This means in practice that the application wants to wait until it receives IPv6 router advertisement message before continuing.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_BT_NODE</td>
<td>Enables application to operate in Bluetooth node mode which requires GATT service to be registered and start advertising as peripheral.</td>
</tr>
</tbody>
</table>
group net_config
Network configuration library.

Defines

NET_CONFIG_NEED_ROUTER
Application needs routers to be set so that connectivity to remote network is possible.
For IPv6 networks, this means that the device should receive IPv6 router advertisement message before continuing.

NET_CONFIG_NEED_IPV6
Application needs IPv6 subsystem configured and initialized.
Typically this means that the device has IPv6 address set.

NET_CONFIG_NEED_IPV4
Application needs IPv4 subsystem configured and initialized.
Typically this means that the device has IPv4 address set.

Functions

int net_config_init(const char *app_info, uint32_t flags, int32_t timeout)
Initialize this network application.
This will call net_config_init_by_iface() with NULL network interface.

Parameters
• app_info – String describing this application.
• flags – Flags related to services needed by the client.
• timeout – How long to wait the network setup before continuing the startup.

Returns
0 if ok, <0 if error.

int net_config_init_by_iface(struct net_if *iface, const char *app_info, uint32_t flags, int32_t timeout)
Initialize this network application using a specific network interface.
If network interface is set to NULL, then the default one is used in the configuration.

Parameters
• iface – Initialize networking using this network interface.
• app_info – String describing this application.
• flags – Flags related to services needed by the client.
• timeout – How long to wait the network setup before continuing the startup.

Returns
0 if ok, <0 if error.
int net_config_init_app(const struct device *dev, const char *app_info)
Initialize this network application.

If CONFIG_NET_CONFIG_AUTO_INIT is set, then this function is called automatically when the device boots. If that is not desired, unset the config option and call the function manually when the application starts.

Parameters
- dev – Network device to use. The function will figure out what network interface to use based on the device. If the device is NULL, then default network interface is used by the function.
- app_info – String describing this application.

Returns
0 if ok, <0 if error.

DHCPv4

Overview
The Dynamic Host Configuration Protocol (DHCP) is a network management protocol used on IPv4 networks. A DHCPv4 server dynamically assigns an IPv4 address and other network configuration parameters to each device on a network so they can communicate with other IP networks. See this DHCP Wikipedia article for a detailed overview of how DHCP works.

Note that Zephyr only supports DHCP client functionality.

Sample usage
See dhcpv4-client sample application for details.

API Reference
Related code samples

DHCPv4 client
Start a DHCPv4 client to obtain an IPv4 address from a DHCPv4 server.

group dhcpv4
DHCPv4.

 Enums

enum net_dhcpv4_msg_type
DHCPv4 message types.
These enumerations represent RFC2131 defined msg type codes, hence they should not be renumbered.
Additions, removal and reorders in this definition must be reflected within corresponding changes to net_dhcpv4_msg_type_name.
Values:

enumerator NET_DHCPV4_MSG_TYPE_DISCOVER = 1
enumerator NET_DHCPV4_MSG_TYPE_OFFER = 2
enumerator NET_DHCPV4_MSG_TYPE_REQUEST = 3
enumerator NET_DHCPV4_MSG_TYPE_decline = 4
enumerator NET_DHCPV4_MSG_TYPE_ACK = 5
enumerator NET_DHCPV4_MSG_TYPE_NAK = 6
enumerator NET_DHCPV4_MSG_TYPE_RELEASE = 7
enumerator NET_DHCPV4_MSG_TYPE_INFORM = 8

Functions

void net_dhcpv4_start(struct net_if *iface)
Start DHCPv4 client on an iface.
Start DHCPv4 client on a given interface. DHCPv4 client will start negotiation for IPv4 address. Once the negotiation is success IPv4 address details will be added to interface.

Parameters
  • iface – A valid pointer on an interface

void net_dhcpv4_stop(struct net_if *iface)
Stop DHCPv4 client on an iface.
Stop DHCPv4 client on a given interface. DHCPv4 client will remove all configuration obtained from a DHCP server from the interface and stop any further negotiation with the server.

Parameters
  • iface – A valid pointer on an interface

void net_dhcpv4_restart(struct net_if *iface)
Restart DHCPv4 client on an iface.
Restart DHCPv4 client on a given interface. DHCPv4 client will restart the state machine without any of the initial delays used in start.

Parameters
  • iface – A valid pointer on an interface

const char *net_dhcpv4_msg_type_name(enum net_dhcpv4_msg_type msg_type)
Return a text representation of the msg_type.

Parameters
  • msg_type – The msg_type to be converted to text

Returns
  A text representation of msg_type
Hostname Configuration

Overview

A networked device might need a hostname, for example, if the device is configured to be a mDNS responder (see DNS Resolve for details) and needs to respond to `<hostname>.local` DNS queries.

The CONFIG_NET_HOSTNAME_ENABLE must be set in order to store the hostname and enable the relevant APIs. If the option is enabled, then the default hostname is set to be `zephyr` by CONFIG_NET_HOSTNAME option.

If the same firmware image is used to flash multiple boards, then it is not practical to use the same hostname in all of the boards. In that case, one can enable CONFIG_NET_HOSTNAME_UNIQUE which will add a unique postfix to the hostname. By default the link local address of the first network interface is used as a postfix. In Ethernet networks, the link local address refers to MAC address. For example, if the link local address is `01:02:03:04:05:06`, then the unique hostname could be `zephyr010203040506`. If you want to set the prefix yourself, then call net_hostname_set_postfix() before the network interfaces are created. For example for the Ethernet networks, the initialization priority is set by CONFIG_ETH_INIT_PRIORITY so you would need to set the postfix before that. The postfix can be set only once.

API Reference

**group net_hostname**

Network hostname configuration library.

**Defines**

NET_HOSTNAME_MAX_LEN

NET_HOSTNAME_SIZE

**Functions**

**static inline const char *net_hostname_get(void)**

  Get the device hostname.
  
  Return pointer to device hostname.

  **Returns**
  
  Pointer to hostname or NULL if not set.

**static inline int net_hostname_set(char *host, size_t len)**

  Set the device hostname.

  **Parameters**
  
  - **host** – new hostname as char array.
  - **len** – Length of the hostname array.

  **Returns**
  
  0 if ok, <0 on error
static inline void net_hostname_init(void)
    Initialize and set the device hostname.

static inline int net_hostname_set_postfix(const uint8_t *hostname_postfix, int
    postfix_len)
    Set the device hostname postfix.
    Set the device hostname to some value. This is only used if CONFIG_NET_HOSTNAME_UNIQUE is set.

Parameters
    • hostname_postfix – Usually link address. The function will convert this to a string.
    • postfix_len – Length of the hostname_postfix array.

Returns
    0 if ok, <0 if error

Network Core Helpers

Overview
    The network subsystem contains two functions for sending and receiving data from the network. The net_recv_data() is typically used by network device driver when the received network data needs to be pushed up in the network stack for further processing. All the data is received via a network interface which is typically created by the device driver.

    For sending, the net_send_data() can be used. Typically applications do not call this function directly as there is the BSD Sockets API for sending and receiving network data.

API Reference

Related code samples

Telnet console
    Access Zephyr shell over telnet.

mDNS responder
    Listen and respond to mDNS queries.


group net_core
    Network core library.

Enums

enum net_verdict
    Net Verdict.
    Values:
enumerator NET_OK
Packet has been taken care of.

enumerator NET_CONTINUE
Packet has not been touched, other part should decide about its fate.

enumerator NET_DROP
Packet must be dropped.

Functions

int net_recv_data(struct net_if *iface, struct net_pkt *pkt)
Called by lower network stack or network device driver when a network packet has been received.

The function will push the packet up in the network stack for further processing.

Parameters
• iface – Network interface where the packet was received.
• pkt – Network packet data.

Returns
0 if ok, <0 if error.

int net_send_data(struct net_pkt *pkt)
Send data to network.

Send data to network. This should not be used normally by applications as it requires that the network packet is properly constructed.

Parameters
• pkt – Network packet.

Returns
0 if ok, <0 if error. If <0 is returned, then the caller needs to unref the pkt in order to avoid memory leak.

Network Interface

• Overview
• Network interface state management
• API Reference

Overview  The network interface is a nexus that ties the network device drivers and the upper part of the network stack together. All the sent and received data is transferred via a network interface. The network interfaces cannot be created at runtime. A special linker section will contain information about them and that section is populated at linking time.

Network interfaces are created by NET_DEVICE_INIT() macro. For Ethernet network, a macro called ETH_NET_DEVICE_INIT() should be used instead as it will create VLAN interfaces automatically if CONFIG_NET_VLAN is enabled. These macros are typically used in network device driver source code.
The network interface can be turned ON by calling `net_if_up()` and OFF by calling `net_if_down()`. When the device is powered ON, the network interface is also turned ON by default.

The network interfaces can be referenced either by a `struct net_if *` pointer or by a network interface index. The network interface can be resolved from its index by calling `net_if_get_by_index()` and from interface pointer by calling `net_if_get_by_iface()`.

The IP address for network devices must be set for them to be connectable. In a typical dynamic network environment, IP addresses are set automatically by DHCPv4, for example. If needed though, the application can set a device's IP address manually. See the API documentation below for functions such as `net_if_ipv4_addr_add()` that do that.

The default interface is returned by `net_if_get_default()`. What this default interface means can be configured via options like `CONFIG_NET_DEFAULT_IF_FIRST` and `CONFIG_NET_DEFAULT_IF_ETHERNET`. See Kconfig file `subsys/net/ip/Kconfig` for what options are available for selecting the default network interface.

The transmitted and received network packets can be classified via a network packet priority. This is typically done in Ethernet networks when virtual LANs (VLANs) are used. Higher priority packets can be sent or received earlier than lower priority packets. The traffic class setup can be configured by `CONFIG_NET_TC_TX_COUNT` and `CONFIG_NET_TC_RX_COUNT` options.

If the `CONFIG_NET_PROMISCUOUS_MODE` is enabled and if the underlying network technology supports promiscuous mode, then it is possible to receive all the network packets that the network device driver is able to receive. See Promiscuous Mode API for more details.

**Network interface state management**  Zephyr distinguishes between two interface states: administrative state and operational state, as described in RFC 2863. The administrative state indicates whether an interface is turned ON or OFF. This state is represented by `NET_IF_UP` flag and is controlled by the application. It can be changed by calling `net_if_up()` or `net_if_down()` functions. Network drivers or L2 implementations should not change administrative state on their own.

Bringing an interface up however not always means that the interface is ready to transmit packets. Because of that, operational state, which represents the internal interface status, was implemented. The operational state is updated whenever one of the following conditions take place:

- The interface is brought up/down by the application (administrative state changes).
- The interface is notified by the driver/L2 that PHY status has changed.
- The interface is notified by the driver/L2 that it joined/left a network.

The PHY status is represented with `NET_IF_LOWER_UP` flag and can be changed with `net_if_carrier_on()` and `net_if_carrier_off()`. By default, the flag is set on a newly initialized interface. An example of an event that changes the carrier state is Ethernet cable being plugged in or out.

The network association status is represented with `NET_IF_DORMANT` flag and can be changed with `net_if_dormant_on()` and `net_if_dormant_off()`. By default, the flag is cleared on a newly initialized interface. An example of an event that changes the dormant state is a Wi-Fi driver successfully connecting to an access point. In this scenario, driver should set the dormant state to ON during initialization, and once it detects that it connected to a Wi-Fi network, the dormant state should be set to OFF.

The operational state of an interface is updated as follows:

- `!net_if_is_admin_up()`  Interface is in `NET_IF_OPER_DOWN`.
- `net_if_is_admin_up() && !net_if_is_carrier_ok()`
Interface is in `NET_IF_OPER_DOWN` or `NET_IF_OPER_LOWERLAYERDOWN` if the interface is stacked (virtual).

- `net_if_is_admin_up() && net_if_is_carrier_ok() && net_if_is_dormant()`
  
  Interface is in `NET_IF_OPER_DORMANT`.

- `net_if_is_admin_up() && net_if_is_carrier_ok() && !net_if_is_dormant()`
  
  Interface is in `NET_IF_OPER_UP`.

Only after an interface enters `NET_IF_OPER_UP` state the `NET_IF_RUNNING` flag is set on the interface indicating that the interface is ready to be used by the application.

### API Reference

#### Related code samples

**IPv4 autoconf client**

Perform IPv4 autoconfiguration and self-assign a random IPv4 address.

**Network management socket**

Listen to network management events using a network management socket.

**Telnet console**

Access Zephyr shell over telnet.

**Virtual LAN**

Setup two virtual LAN networks and use net-shell to view the networks' settings.

---

*group net_if*

Network Interface abstraction layer.

**Defines**

`NET_DEVICE_INIT(dev_id, name, init_fn, pm, data, config, prio, api, l2, l2_ctx_type, mtu)`

Create a network interface and bind it to network device.

**Parameters**

- `dev_id` – Network device id.
- `name` – The name this instance of the driver exposes to the system.
- `init_fn` – Address to the init function of the driver.
- `pm` – Reference to struct `pm_device` associated with the device. (optional).
- `data` – Pointer to the device's private data.
- `config` – The address to the structure containing the configuration information for this instance of the driver.
- `prio` – The initialization level at which configuration occurs.
- `api` – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
- `l2` – Network L2 layer for this network interface.
- `l2_ctx_type` – Type of L2 context data.
- `mtu` – Maximum transfer unit in bytes for this network interface.
NET_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, prio, api, l2, l2_ctx_type, mtu)

Like NET_DEVICE_INIT but taking metadata from a devicetree node.

Create a network interface and bind it to network device.

Parameters

- `node_id` – The devicetree node identifier.
- `init_fn` – Address to the init function of the driver.
- `pm` – Reference to struct `pm_device` associated with the device. (optional).
- `data` – Pointer to the device's private data.
- `config` – The address to the structure containing the configuration information for this instance of the driver.
- `prio` – The initialization level at which configuration occurs.
- `api` – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
- `l2` – Network L2 layer for this network interface.
- `l2_ctx_type` – Type of L2 context data.
- `mtu` – Maximum transfer unit in bytes for this network interface.

NET_DEVICE_DT_INST_DEFINE(inst, ...)

Like NET_DEVICE_DT_DEFINE for an instance of a DT_DRV_COMPAT compatible.

Parameters

- `inst` – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to NET_DEVICE_DT_DEFINE.
- `...` – other parameters as expected by NET_DEVICE_DT_DEFINE.

NET_DEVICE_INIT_INSTANCE(dev_id, name, instance, init_fn, pm, data, config, prio, api, l2, l2_ctx_type, mtu)

Create multiple network interfaces and bind them to network device.

If your network device needs more than one instance of a network interface, use this macro below and provide a different instance suffix each time (0, 1, 2, ... or a, b, c ... whatever works for you)

Parameters

- `dev_id` – Network device id.
- `name` – The name this instance of the driver exposes to the system.
- `instance` – Instance identifier.
- `init_fn` – Address to the init function of the driver.
- `pm` – Reference to struct `pm_device` associated with the device. (optional).
- `data` – Pointer to the device's private data.
- `config` – The address to the structure containing the configuration information for this instance of the driver.
- `prio` – The initialization level at which configuration occurs.
- `api` – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
- `l2` – Network L2 layer for this network interface.
- `l2_ctx_type` – Type of L2 context data.
• **mtu** – Maximum transfer unit in bytes for this network interface.

```c
NET_DEVICE_DT_DEFINE_INSTANCE(node_id, instance, init_fn, pm, data, config, prio, api, l2, l2_ctx_type, mtu)
```

Like `NET_DEVICE_OFFLOAD_INIT` but taking metadata from a devicetree.

Create multiple network interfaces and bind them to network device. If your network device needs more than one instance of a network interface, use this macro below and provide a different instance suffix each time (0, 1, 2, ... or a, b, c ... whatever works for you)

**Parameters**
- **node_id** – The devicetree node identifier.
- **instance** – Instance identifier.
- **init_fn** – Address to the init function of the driver.
- **pm** – Reference to struct `pm_device` associated with the device. (optional).
- **data** – Pointer to the device's private data.
- **config** – The address to the structure containing the configuration information for this instance of the driver.
- **prio** – The initialization level at which configuration occurs.
- **api** – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
- **l2** – Network L2 layer for this network interface.
- **l2_ctx_type** – Type of L2 context data.
- **mtu** – Maximum transfer unit in bytes for this network interface.

```c
NET_DEVICE_DT_INST_DEFINE_INSTANCE(inst, ...)
```

Like `NET_DEVICE_DT_DEFINE_INSTANCE` for an instance of a DT_DRV_COMPAT compatible.

**Parameters**
- **inst** – Instance number. This is replaced by `DT_DRV_COMPAT(inst)` in the call to `NET_DEVICE_DT_DEFINE_INSTANCE`.
- **...** – other parameters as expected by `NET_DEVICE_DT_DEFINE_INSTANCE`.

```c
NET_DEVICE_OFFLOAD_INIT(dev_id, name, init_fn, pm, data, config, prio, api, mtu)
```

Create a offloaded network interface and bind it to network device.

The offloaded network interface is implemented by a device vendor HAL or similar.

**Parameters**
- **dev_id** – Network device id.
- **name** – The name this instance of the driver exposes to the system.
- **init_fn** – Address to the init function of the driver.
- **pm** – Reference to struct `pm_device` associated with the device. (optional).
- **data** – Pointer to the device's private data.
- **config** – The address to the structure containing the configuration information for this instance of the driver.
- **prio** – The initialization level at which configuration occurs.
• **api** – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
• **mtu** – Maximum transfer unit in bytes for this network interface.

**NET_DEVICE_DT_OFFLOAD_DEFINE**(node_id, init_fn, pm, data, config, prio, api, mtu)
Like **NET_DEVICE_OFFLOAD_INIT** but taking metadata from a devicetree node.
Create a offloaded network interface and bind it to network device. The offloaded network interface is implemented by a device vendor HAL or similar.

**Parameters**
- **node_id** – The devicetree node identifier.
- **init_fn** – Address to the init function of the driver.
- **pm** – Reference to struct **pm_device** associated with the device. (optional).
- **data** – Pointer to the device's private data.
- **config** – The address to the structure containing the configuration information for this instance of the driver.
- **prio** – The initialization level at which configuration occurs.
- **api** – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
- **mtu** – Maximum transfer unit in bytes for this network interface.

**NET_DEVICE_DT_INST_OFFLOAD_DEFINE**(inst, ...)
Like **NET_DEVICE_DT_OFFLOAD_DEFINE** for an instance of a DT_DRV_COMPAT compatible.

**Parameters**
- **inst** – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to **NET_DEVICE_DT_OFFLOAD_DEFINE**.
- **...** – other parameters as expected by **NET_DEVICE_DT_OFFLOAD_DEFINE**.

**NET_IFACE_COUNT**(_dst)
Count the number of network interfaces.

**Parameters**
- **_dst** – [out] Pointer to location where result is written.

**Typedefs**

typedef int (*net_socket_create_t)(int, int, int)
A function prototype to create an offloaded socket.
The prototype is compatible with **socket()** function.

typedef void (*net_if_ip_addr_cb_t)(struct net_if *iface, struct net_if_addr *addr, void *user_data)
Callback used while iterating over network interface IP addresses.

**Param iface**
Pointer to the network interface the address belongs to

**Param addr**
Pointer to current IP address

6.3. Networking
**Param user_data**
A valid pointer to user data or NULL

typedef void (*net_if_mcast_callback_t)(struct net_if *iface, const struct net_addr *addr, bool is_joined)
Defining a callback that is called whenever an IPv6 or IPv4 multicast address group is joined or left.

**Param iface**
A pointer to a struct net_if to which the multicast address is attached.

**Param addr**
IP multicast address.

**Param is_joined**
True if the multicast group is joined, false if group is left.

typedef void (*net_if_link_callback_t)(struct net_if *iface, struct net_linkaddr *dst, int status)
Define callback that is called after a network packet has been sent.

**Param iface**
A pointer to a struct net_if to which the net_pkt was sent to.

**Param dst**
Link layer address of the destination where the network packet was sent.

**Param status**
Send status, 0 is ok, < 0 error.

typedef void (*net_if_cb_t)(struct net_if *iface, void *user_data)
Callback used while iterating over network interfaces.

**Param iface**
Pointer to current network interface

**Param user_data**
A valid pointer to user data or NULL

**Enums**

enum net_if_flag
Network interface flags.

*Values:*

enumeration NET_IF_UP
Interface is admin up.

enumeration NET_IF_POINTOPOINT
Interface is pointto point.

enumeration NET_IF_PROMISC
Interface is in promiscuous mode.
enumerator **NET_IF_NO_AUTO_START**
Do not start the interface immediately after initialization.
This requires that either the device driver or some other entity will need to manually take the interface up when needed. For example for Ethernet this will happen when the driver calls the *net_eth_carrier_on()* function.

enumerator **NET_IF_SUSPENDED**
Power management specific: interface is being suspended.

enumerator **NET_IF_FORWARD_MULTICASTS**
Flag defines if received multicasts of other interface are forwarded on this interface.
This activates multicast routing / forwarding for this interface.

enumerator **NET_IF_IPV4**
Interface supports IPv4.

denumerator **NET_IF_IPV6**
Interface supports IPv6.

denumerator **NET_IF_RUNNING**
Interface up and running (ready to receive and transmit).

denumerator **NET_IF_LOWER_UP**
Driver signals L1 is up.

denumerator **NET_IF_DORMANT**
Driver signals dormant.

denumerator **NET_IF_IPV6_NO_ND**
IPv6 Neighbor Discovery disabled.

denumerator **NET_IF_IPV6_NO_MLD**
IPv6 Multicast Listener Discovery disabled.

denumerator **NET_IF_NO_TX_LOCK**
Mutex locking on TX data path disabled on the interface.

enum **net_if_oper_state**
Network interface operational status (RFC 2863).
*Values:*

enumerator **NET_IF_OPER_UNKNOWN**

enumerator **NET_IF_OPER_NOTPRESENT**

enumerator **NET_IF_OPER_DOWN**
enumerator NET_IF_OPER_LOWERLAYERDOWN
enumerator NET_IF_OPER_TESTING
enumerator NET_IF_OPER_DORMANT
enumerator NET_IF_OPER_UP

Functions

static inline void net_if_lock(struct net_if *iface)
static inline void net_if_unlock(struct net_if *iface)
static inline bool net_if_flag_is_set(struct net_if *iface, enum net_if_flag value)
  Check if a value in network interface flags is set.
  Parameters
  • iface – Pointer to network interface
  • value – Flag value
  Returns
  True if the value is set, false otherwise
static inline void net_if_tx_lock(struct net_if *iface)
static inline void net_if_tx_unlock(struct net_if *iface)
static inline void net_if_flag_set(struct net_if *iface, enum net_if_flag value)
  Set a value in network interface flags.
  Parameters
  • iface – Pointer to network interface
  • value – Flag value
static inline bool net_if_flag_test_and_set(struct net_if *iface, enum net_if_flag value)
  Test and set a value in network interface flags.
  Parameters
  • iface – Pointer to network interface
  • value – Flag value
  Returns
  true if the bit was set, false if it wasn't.
static inline void net_if_flag_clear(struct net_if *iface, enum net_if_flag value)
  Clear a value in network interface flags.
  Parameters
  • iface – Pointer to network interface
  • value – Flag value
static inline bool net_if_flag_test_and_clear(struct net_if *iface, enum net_if_flag value)

Test and clear a value in network interface flags.

Parameters
• iface – Pointer to network interface
• value – Flag value

Returns
true if the bit was set, false if it wasn’t.

static inline enum net_if_oper_state net_if_oper_state_set(struct net_if *iface, enum net_if_oper_state oper_state)

Set an operational state on an interface.

Parameters
• iface – Pointer to network interface
• oper_state – Operational state to set

Returns
The new operational state of an interface

static inline enum net_if_oper_state net_if_oper_state(struct net_if *iface)

Get an operational state of an interface.

Parameters
• iface – Pointer to network interface

Returns
Operational state of an interface

enum net_verdict net_if_send_data(struct net_if *iface, struct net_pkt *pkt)

Send a packet through a net iface.

return verdict about the packet

Parameters
• iface – Pointer to a network interface structure
• pkt – Pointer to a net packet to send

static inline const struct net_l2 *net_if_l2(struct net_if *iface)

Get a pointer to the interface L2.

Parameters
• iface – a valid pointer to a network interface structure

Returns
a pointer to the iface L2

enum net_verdict net_if_recv_data(struct net_if *iface, struct net_pkt *pkt)

Input a packet through a net iface.

Parameters
• iface – Pointer to a network interface structure
• pkt – Pointer to a net packet to input

Returns
verdict about the packet
static inline void *net_if_l2_data(struct net_if *iface)

Get a pointer to the interface L2 private data.

Parameters

• iface – a valid pointer to a network interface structure

Returns

a pointer to the iface L2 data

static inline const struct device *net_if_get_device(struct net_if *iface)

Get an network interface's device.

Parameters

• iface – Pointer to a network interface structure

Returns

a pointer to the device driver instance

void net_if_queue_tx(struct net_if *iface, struct net_pkt *pkt)

Queue a packet to the net interface TX queue.

Parameters

• iface – Pointer to a network interface structure

• pkt – Pointer to a net packet to queue

static inline bool net_if_is_ip_offloaded(struct net_if *iface)

Return the IP offload status.

Parameters

• iface – Network interface

Returns

True if IP offloading is active, false otherwise.

bool net_if_is_offloaded(struct net_if *iface)

Return offload status of a given network interface.

Parameters

• iface – Network interface

Returns

True if IP or socket offloading is active, false otherwise.

static inline struct net_offload *net_if_offload(struct net_if *iface)

Return the IP offload plugin.

Parameters

• iface – Network interface

Returns

NULL if there is no offload plugin defined, valid pointer otherwise

static inline bool net_if_is_socket_offloaded(struct net_if *iface)

Return the socket offload status.

Parameters

• iface – Network interface

Returns

True if socket offloading is active, false otherwise.
static inline void net_if_socket_offload_set(struct net_if *iface, net_socket_create_t socket_offload)

Set the function to create an offloaded socket.

Parameters
- iface – Network interface
- socket_offload – A function to create an offloaded socket

static inline net_socket_create_t net_if_socket_offload(struct net_if *iface)

Return the function to create an offloaded socket.

Parameters
- iface – Network interface

Returns
- NULL if the interface is not socket offloaded, valid pointer otherwise

static inline struct net_linkaddr *net_if_get_link_addr(struct net_if *iface)

Get an network interface's link address.

Parameters
- iface – Pointer to a network interface structure

Returns
- a pointer to the network link address

static inline struct net_if_config *net_if_get_config(struct net_if *iface)

Return network configuration for this network interface.

Parameters
- iface – Pointer to a network interface structure

Returns
- Pointer to configuration

static inline void net_if_start_dad(struct net_if *iface)

Start duplicate address detection procedure.

Parameters
- iface – Pointer to a network interface structure

void net_if_start_rs(struct net_if *iface)

Start neighbor discovery and send router solicitation message.

Parameters
- iface – Pointer to a network interface structure

static inline void net_if_stop_rs(struct net_if *iface)

Stop neighbor discovery.

Parameters
- iface – Pointer to a network interface structure

static inline int net_if_set_link_addr(struct net_if *iface, uint8_t *addr, uint8_t len, enum net_link_type type)

Set a network interface's link address.

Parameters
- iface – Pointer to a network interface structure
• `addr` – A pointer to a uint8_t buffer representing the address. The buffer
  must remain valid throughout interface lifetime.
• `len` – length of the address buffer
• `type` – network bearer type of this link address

**Returns**
0 on success

```c
static inline uint16_t net_if_get_mtu(struct net_if *iface)
```
Get an network interface’s MTU.

**Parameters**
• `iface` – Pointer to a network interface structure

**Returns**
the MTU

```c
static inline void net_if_set_mtu(struct net_if *iface, uint16_t mtu)
```
Set an network interface’s MTU.

**Parameters**
• `iface` – Pointer to a network interface structure
• `mtu` – New MTU, note that we store only 16 bit mtu value.

```c
static inline void net_if_addr_set_lf(struct net_if_addr *ifaddr, bool is_infinite)
```
Set the infinite status of the network interface address.

**Parameters**
• `ifaddr` – IP address for network interface
• `is_infinite` – Infinite status

```c
struct net_if *net_if_get_by_link_addr(struct net_linkaddr *ll_addr)
```
Get an interface according to link layer address.

**Parameters**
• `ll_addr` – Link layer address.

**Returns**
Network interface or NULL if not found.

```c
struct net_if *net_if_lookup_by_dev(const struct device *dev)
```
Find an interface from it’s related device.

**Parameters**
• `dev` – A valid struct device pointer to relate with an interface

**Returns**
a valid struct `net_if` pointer on success, NULL otherwise

```c
static inline struct net_if_config *net_if_config_get(struct net_if *iface)
```
Get network interface IP config.

**Parameters**
• `iface` – Interface to use.

**Returns**
NULL if not found or pointer to correct config settings.
void net_if_router_rm(struct net_if_router *router)
    Remove a router from the system.

Parameters
    • router – Pointer to existing router

void net_if_set_default(struct net_if *iface)
    Set the default network interface.

Parameters
    • iface – New default interface, or NULL to revert to the one set by Kconfig.

struct net_if *net_if_get_default(void)
    Get the default network interface.

Returns
    Default interface or NULL if no interfaces are configured.

struct net_if *net_if_get_first_by_type(const struct net_l2 *l2)
    Get the first network interface according to its type.

Parameters
    • l2 – Layer 2 type of the network interface.

Returns
    First network interface of a given type or NULL if no such interfaces was found.

struct net_if *net_if_get_first_up(void)
    Get the first network interface which is up.

Returns
    First network interface which is up or NULL if all interfaces are down.

int net_if_config_ipv6_get(struct net_if *iface, struct net_if_ipv6 **ipv6)
    Allocate network interface IPv6 config.
    This function will allocate new IPv6 config.

Parameters
    • iface – Interface to use.
    • ipv6 – Pointer to allocated IPv6 struct is returned to caller.

Returns
    0 if ok, <0 if error

int net_if_config_ipv6_put(struct net_if *iface)
    Release network interface IPv6 config.

Parameters
    • iface – Interface to use.

Returns
    0 if ok, <0 if error

struct net_if_addr *net_if_ipv6_addr_lookup(const struct in6_addr *addr, struct net_if **iface)
    Check if this IPv6 address belongs to one of the interfaces.

Parameters
    • addr – IPv6 address
    • iface – Pointer to interface is returned
Returns
Pointer to interface address, NULL if not found.

struct net_if_addr *net_if_ipv6_addr_lookup_by_iface(struct net_if *iface, struct in6_addr *addr)

Check if this IPv6 address belongs to this specific interfaces.

Parameters
• iface – Network interface
• addr – IPv6 address

Returns
Pointer to interface address, NULL if not found.

int net_if_ipv6_addr_lookup_by_index(const struct in6_addr *addr)

Check if this IPv6 address belongs to one of the interface indices.

Parameters
• addr – IPv6 address

Returns
>0 if address was found in given network interface index, all other values mean address was not found

struct net_if_addr *net_if_ipv6_addr_add(struct net_if *iface, struct in6_addr *addr, enum net_addr_type addr_type, uint32_t vlifetime)

Add a IPv6 address to an interface.

Parameters
• iface – Network interface
• addr – IPv6 address
• addr_type – IPv6 address type
• vlifetime – Validity time for this address

Returns
Pointer to interface address, NULL if cannot be added

bool net_if_ipv6_addr_add_by_index(int index, struct in6_addr *addr, enum net_addr_type addr_type, uint32_t vlifetime)

Add a IPv6 address to an interface by index.

Parameters
• index – Network interface index
• addr – IPv6 address
• addr_type – IPv6 address type
• vlifetime – Validity time for this address

Returns
True if ok, false if address could not be added

void net_if_ipv6_addr_update_lifetime(struct net_if_addr *ifaddr, uint32_t vlifetime)

Update validity lifetime time of an IPv6 address.

Parameters
• ifaddr – Network IPv6 address
• vlifetime – Validity time for this address
bool net_if_ipv6_addr_rm(struct net_if *iface, const struct in6_addr *addr)
Remove an IPv6 address from an interface.

Parameters
- iface – Network interface
- addr – IPv6 address

Returns
True if successfully removed, false otherwise

bool net_if_ipv6_addr_rm_by_index(int index, const struct in6_addr *addr)
Remove an IPv6 address from an interface by index.

Parameters
- index – Network interface index
- addr – IPv6 address

Returns
True if successfully removed, false otherwise

void net_if_ipv6_addr_foreach(struct net_if *iface, net_if_ip_addr_cb_t cb, void *user_data)
Go through all IPv6 addresses on a network interface and call callback for each used address.

Parameters
- iface – Pointer to the network interface
- cb – User-supplied callback function to call
- user_data – User specified data

struct net_if_mcast_addr *net_if_ipv6_maddr_add(struct net_if *iface, const struct in6_addr *addr)
Add a IPv6 multicast address to an interface.

Parameters
- iface – Network interface
- addr – IPv6 multicast address

Returns
Pointer to interface multicast address, NULL if cannot be added

bool net_if_ipv6_maddr_rm(struct net_if *iface, const struct in6_addr *addr)
Remove an IPv6 multicast address from an interface.

Parameters
- iface – Network interface
- addr – IPv6 multicast address

Returns
True if successfully removed, false otherwise

struct net_if_mcast_addr *net_if_ipv6_maddr_lookup(const struct in6_addr *addr, struct net_if **iface)
Check if this IPv6 multicast address belongs to a specific interface or one of the interfaces.

Parameters
- addr – IPv6 address
• **iface** – If *iface is null, then pointer to interface is returned, otherwise the *iface value needs to be matched.

**Returns**

Pointer to interface multicast address, NULL if not found.

`void net_if_mcast_mon_register(struct net_if_mcast_monitor *mon, struct net_if *iface, net_if_mcast_callback_t cb)`

Register a multicast monitor.

**Parameters**

- **mon** – Monitor handle. This is a pointer to a monitor storage structure which should be allocated by caller, but does not need to be initialized.
- **iface** – Network interface
- **cb** – Monitor callback

`void net_if_mcast_mon_unregister(struct net_if_mcast_monitor *mon)`

Unregister a multicast monitor.

**Parameters**

- **mon** – Monitor handle

`void net_if_mcast_mon(struct net_if *iface, const struct net_addr *addr, bool is_joined)`

Call registered multicast monitors.

**Parameters**

- **iface** – Network interface
- **addr** – Multicast address
- **is_joined** – Is this multicast address group joined (true) or not (false)

`void net_if_ipv6_maddr_join(struct net_if *iface, struct net_if_mcast_addr *addr)`

Mark a given multicast address to be joined.

**Parameters**

- **iface** – Network interface the address belongs to
- **addr** – IPv6 multicast address

`static inline bool net_if_ipv6_maddr_is_joined(struct net_if_mcast_addr *addr)`

Check if given multicast address is joined or not.

**Parameters**

- **addr** – IPv6 multicast address

**Returns**

True if address is joined, False otherwise.

`void net_if_ipv6_maddr_leave(struct net_if *iface, struct net_if_mcast_addr *addr)`

Mark a given multicast address to be left.

**Parameters**

- **iface** – Network interface the address belongs to
- **addr** – IPv6 multicast address

`struct net_if_ipv6_prefix *net_if_ipv6_prefix_get(struct net_if *iface, struct in6_addr *addr)`

Return prefix that corresponds to this IPv6 address.
Parameters

• iface – Network interface
• addr – IPv6 address

Returns

Pointer to prefix, NULL if not found.

struct net_if_ipv6_prefix *net_if_ipv6_prefix_lookup(struct net_if *iface, struct in6_addr *addr, uint8_t len)

Check if this IPv6 prefix belongs to this interface.

Parameters

• iface – Network interface
• addr – IPv6 address
• len – Prefix length

Returns

Pointer to prefix, NULL if not found.

struct net_if_ipv6_prefix *net_if_ipv6_prefix_add(struct net_if *iface, struct in6_addr *prefix, uint8_t len, uint32_t lifetime)

Add a IPv6 prefix to an network interface.

Parameters

• iface – Network interface
• prefix – IPv6 address
• len – Prefix length
• lifetime – Prefix lifetime in seconds

Returns

Pointer to prefix, NULL if the prefix was not added.

bool net_if_ipv6_prefix_rm(struct net_if *iface, struct in6_addr *addr, uint8_t len)

Remove an IPv6 prefix from an interface.

Parameters

• iface – Network interface
• addr – IPv6 prefix address
• len – Prefix length

Returns

True if successfully removed, false otherwise

static inline void net_if_ipv6_prefix_set_lf(struct net_if_ipv6_prefix *prefix, bool is_infinite)

Set the infinite status of the prefix.

Parameters

• prefix – IPv6 address
• is_infinite – Infinite status

void net_if_ipv6_prefix_set_timer(struct net_if_ipv6_prefix *prefix, uint32_t lifetime)

Set the prefix lifetime timer.

Parameters

• prefix – IPv6 address
• lifetime – Prefix lifetime in seconds

void net_if_ipv6_prefix_unset_timer(struct net_if_ipv6_prefix *prefix)
Unset the prefix lifetime timer.

Parameters
• prefix – IPv6 address

bool net_if_ipv6_addr_onlink(struct net_if **iface, struct in6_addr *addr)
Check if this IPv6 address is part of the subnet of our network interface.

Parameters
• iface – Network interface. This is returned to the caller. The iface can be NULL in which case we check all the interfaces.
• addr – IPv6 address

Returns
True if address is part of our subnet, false otherwise

static inline struct in6_addr *net_if_router_ipv6(struct net_if_router *router)
Get the IPv6 address of the given router.

Parameters
• router – a network router

Returns
pointer to the IPv6 address, or NULL if none

struct net_if_router *net_if_ipv6_router_lookup(struct net_if *iface, struct in6_addr *addr)
Check if IPv6 address is one of the routers configured in the system.

Parameters
• iface – Network interface
• addr – IPv6 address

Returns
Pointer to router information, NULL if cannot be found

struct net_if_router *net_if_ipv6_router_find_default(struct net_if *iface, struct in6_addr *addr)
Find default router for this IPv6 address.

Parameters
• iface – Network interface. This can be NULL in which case we go through all the network interfaces to find a suitable router.
• addr – IPv6 address

Returns
Pointer to router information, NULL if cannot be found

void net_if_ipv6_router_update_lifetime(struct net_if_router *router, uint16_t lifetime)
Update validity lifetime time of a router.

Parameters
• router – Network IPv6 address
• lifetime – Lifetime of this router.
Add IPv6 router to the system.

**Parameters**
- `iface` – Network interface
- `addr` – IPv6 address
- `router_lifetime` – Lifetime of the router

**Returns**
Pointer to router information, NULL if could not be added

Remove IPv6 router from the system.

**Parameters**
- `router` – Router information.

**Returns**
True if successfully removed, false otherwise

Get IPv6 hop limit specified for a given interface.

This is the default value but can be overridden by the user.

**Parameters**
- `iface` – Network interface

**Returns**
Hop limit

Set the default IPv6 hop limit of a given interface.

**Parameters**
- `iface` – Network interface
- `hop_limit` – New hop limit

Get IPv6 multicast hop limit specified for a given interface.

This is the default value but can be overridden by the user.

**Parameters**
- `iface` – Network interface

**Returns**
Hop limit

Set the default IPv6 multicast hop limit of a given interface.

**Parameters**
- `iface` – Network interface
- `hop_limit` – New hop limit
static inline void net_if_ipv6_set_base_reachable_time(struct net_if *iface, uint32_t reachable_time)

Set IPv6 reachable time for a given interface.

**Parameters**
- **iface** – Network interface
- **reachable_time** – New reachable time

static inline uint32_t net_if_ipv6_get_reachable_time(struct net_if *iface)

Get IPv6 reachable timeout specified for a given interface.

**Parameters**
- **iface** – Network interface

**Returns**
Reachable timeout

uint32_t net_if_ipv6_calc_reachable_time(struct net_ifIpv6 *ipv6)

Calculate next reachable time value for IPv6 reachable time.

**Parameters**
- **ipv6** – IPv6 address configuration

**Returns**
Reachable time

static inline void net_if_ipv6_set_reachable_time(struct net_ifIpv6 *ipv6)

Set IPv6 reachable time for a given interface.

This requires that base reachable time is set for the interface.

**Parameters**
- **ipv6** – IPv6 address configuration

static inline void net_if_ipv6_set_retrans_timer(struct net_if *iface, uint32_t retrans_timer)

Set IPv6 retransmit timer for a given interface.

**Parameters**
- **iface** – Network interface
- **retrans_timer** – New retransmit timer

static inline uint32_t net_if_ipv6_get_retrans_timer(struct net_if *iface)

Get IPv6 retransmit timer specified for a given interface.

**Parameters**
- **iface** – Network interface

**Returns**
Retransmit timer

static inline const struct in6_addr *net_if_ipv6_select_src_addr(struct net_if *iface, const struct in6_addr *dst)

Get a IPv6 source address that should be used when sending network data to destination.

**Parameters**
- **iface** – Interface that was used when packet was received. If the interface is not known, then NULL can be given.
• dst – IPv6 destination address

Returns
Pointer to IPv6 address to use, NULL if no IPv6 address could be found.

static inline struct net_if *net_if_ipv6_select_src_iface(const struct in6_addr *dst)
Get a network interface that should be used when sending IPv6 network data to destination.

Parameters
• dst – IPv6 destination address

Returns
Pointer to network interface to use, NULL if no suitable interface could be found.

struct in6_addr *net_if_ipv6_get_ll(struct net_if *iface, enum net_addr_state addr_state)
Get a IPv6 link local address in a given state.

Parameters
• iface – Interface to use. Must be a valid pointer to an interface.
• addr_state – IPv6 address state (preferred, tentative, deprecated)

Returns
Pointer to link local IPv6 address, NULL if no proper IPv6 address could be found.

struct in6_addr *net_if_ipv6_get_ll_addr(enum net_addr_state state, struct net_if **iface)
Return link local IPv6 address from the first interface that has a link local address matching give state.

Parameters
• state – IPv6 address state (ANY, TENTATIVE, PREFERRED, DEPRECATED)
• iface – Pointer to interface is returned

Returns
Pointer to IPv6 address, NULL if not found.

void net_if_ipv6_dad_failed(struct net_if *iface, const struct in6_addr *addr)
Stop IPv6 Duplicate Address Detection (DAD) procedure if we find out that our IPv6 address is already in use.

Parameters
• iface – Interface where the DAD was running.
• addr – IPv6 address that failed DAD

struct in6_addr *net_if_ipv6_get_global_addr(enum net_addr_state state, struct net_if **iface)
Return global IPv6 address from the first interface that has a global IPv6 address matching the given state.

Parameters
• state – IPv6 address state (ANY, TENTATIVE, PREFERRED, DEPRECATED)
• iface – Caller can give an interface to check. If iface is set to NULL, then all the interfaces are checked. Pointer to interface where the IPv6 address is defined is returned to the caller.
Returns
   Pointer to IPv6 address, NULL if not found.

int net_if_config_ipv4_get(struct net_if *iface, struct net_if_ipv4 **ipv4)
Allocate network interface IPv4 config.
This function will allocate new IPv4 config.

Parameters
   • iface – Interface to use.
   • ipv4 – Pointer to allocated IPv4 struct is returned to caller.

Returns
   0 if ok, <0 if error

int net_if_config_ipv4_put(struct net_if *iface)
Release network interface IPv4 config.

Parameters
   • iface – Interface to use.

Returns
   0 if ok, <0 if error

uint8_t net_if_ipv4_get_ttl(struct net_if *iface)
Get IPv4 time-to-live value specified for a given interface.

Parameters
   • iface – Network interface

Returns
   Time-to-live

void net_if_ipv4_set_ttl(struct net_if *iface, uint8_t ttl)
Set IPv4 time-to-live value specified to a given interface.

Parameters
   • iface – Network interface
   • ttl – Time-to-live value

uint8_t net_if_ipv4_get_mcast_ttl(struct net_if *iface)
Get IPv4 multicast time-to-live value specified for a given interface.

Parameters
   • iface – Network interface

Returns
   Time-to-live

void net_if_ipv4_set_mcast_ttl(struct net_if *iface, uint8_t ttl)
Set IPv4 multicast time-to-live value specified to a given interface.

Parameters
   • iface – Network interface
   • ttl – Time-to-live value

struct net_addr *net_if_ipv4_addr_lookup(const struct in_addr *addr, struct net_if **iface)
Check if this IPv4 address belongs to one of the interfaces.

Parameters
   • addr – IPv4 address
   • iface – Interface to search through
• addr – IPv4 address
• iface – Interface is returned

Returns
Pointer to interface address, NULL if not found.

struct net_if_addr *net_if_ipv4_addr_add(struct net_if *iface, struct in_addr *addr, enum net_addr_type addr_type, uint32_t vlifetime)

Add a IPv4 address to an interface.

Parameters
• iface – Network interface
• addr – IPv4 address
• addr_type – IPv4 address type
• vlifetime – Validity time for this address

Returns
Pointer to interface address, NULL if cannot be added

bool net_if_ipv4_addr_rm(struct net_if *iface, const struct in_addr *addr)

Remove a IPv4 address from an interface.

Parameters
• iface – Network interface
• addr – IPv4 address

Returns
True if successfully removed, false otherwise

int net_if_ipv4_addr_lookup_by_index(const struct in_addr *addr)
Check if this IPv4 address belongs to one of the interface indices.

Parameters
• addr – IPv4 address

Returns
>0 if address was found in given network interface index, all other values mean address was not found

bool net_if_ipv4_addr_add_by_index(int index, struct in_addr *addr, enum net_addr_type addr_type, uint32_t vlifetime)

Add a IPv4 address to an interface by network interface index.

Parameters
• index – Network interface index
• addr – IPv4 address
• addr_type – IPv4 address type
• vlifetime – Validity time for this address

Returns
True if ok, false if the address could not be added

bool net_if_ipv4_addr_rm_by_index(int index, const struct in_addr *addr)
Remove a IPv4 address from an interface by interface index.

Parameters
• index – Network interface index
• addr – IPv4 address

**Returns**
True if successfully removed, false otherwise

```c
void net_if_ipv4_addr_foreach(struct net_if *iface, net_if_ip_addr_cb_t cb, void *user_data)
```

Go through all IPv4 addresses on a network interface and call callback for each used address.

**Parameters**
- iface – Pointer to the network interface
- cb – User-supplied callback function to call
- user_data – User specified data

```c
struct net_if_mcast_addr *net_if_ipv4_maddr_add(struct net_if *iface, const struct in_addr *addr)
```

Add a IPv4 multicast address to an interface.

**Parameters**
- iface – Network interface
- addr – IPv4 multicast address

**Returns**
Pointer to interface multicast address, NULL if cannot be added

```c
bool net_if_ipv4_maddr_rm(struct net_if *iface, const struct in_addr *addr)
```

Remove an IPv4 multicast address from an interface.

**Parameters**
- iface – Network interface
- addr – IPv4 multicast address

**Returns**
True if successfully removed, false otherwise

```c
struct net_if_mcast_addr *net_if_ipv4_maddr_lookup(const struct in_addr *addr, struct net_if **iface)
```

Check if this IPv4 multicast address belongs to a specific interface or one of the interfaces.

**Parameters**
- addr – IPv4 address
- iface – If *iface is null, then pointer to interface is returned, otherwise the *iface value needs to be matched.

**Returns**
Pointer to interface multicast address, NULL if not found.

```c
void net_if_ipv4_maddr_join(struct net_if *iface, struct net_if_mcast_addr *addr)
```

Mark a given multicast address to be joined.

**Parameters**
- iface – Network interface the address belongs to
- addr – IPv4 multicast address
static inline bool net_if_ipv4_maddr_is Joined(struct net_if_mcast_addr *addr)
    Check if given multicast address is joined or not.

Parameters
  • addr – IPv4 multicast address

Returns
  True if address is joined, False otherwise.

void net_if_ipv4_maddr_leave(struct net_if *iface, struct net_if_mcast_addr *addr)
Mark a given multicast address to be left.

Parameters
  • iface – Network interface the address belongs to
  • addr – IPv4 multicast address

static inline struct in_addr *net_if_router_ipv4(struct net_if_router *router)
Get the IPv4 address of the given router.

Parameters
  • router – a network router

Returns
  pointer to the IPv4 address, or NULL if none

struct net_if_router *net_if_ipv4_router_lookup(struct net_if *iface, struct in_addr *addr)
Check if IPv4 address is one of the routers configured in the system.

Parameters
  • iface – Network interface
  • addr – IPv4 address

Returns
  Pointer to router information, NULL if cannot be found

struct net_if_router *net_if_ipv4_router_find_default(struct net_if *iface, struct in_addr *addr)
Find default router for this IPv4 address.

Parameters
  • iface – Network interface. This can be NULL in which case we go through all the network interfaces to find a suitable router.
  • addr – IPv4 address

Returns
  Pointer to router information, NULL if cannot be found

struct net_if_router *net_if_ipv4_router_add(struct net_if *iface, struct in_addr *addr,
                         bool is_default, uint16_t router_lifetime)
Add IPv4 router to the system.

Parameters
  • iface – Network interface
  • addr – IPv4 address
  • is_default – Is this router the default one
  • router_lifetime – Lifetime of the router
Returns
Pointer to router information, NULL if could not be added

bool net_if_ipv4_router_rm(struct net_if *router)
Remove IPv4 router from the system.

Parameters
• router – Router information.

Returns
True if successfully removed, false otherwise.

bool net_if_ipv4_addr_mask_cmp(struct net_if *iface, const struct in_addr *addr)
Check if the given IPv4 address belongs to local subnet.

Parameters
• iface – Interface to use. Must be a valid pointer to an interface.
• addr – IPv4 address

Returns
True if address is part of local subnet, false otherwise.

bool net_if_ipv4_is_addr_bcast(struct net_if *iface, const struct in_addr *addr)
Check if the given IPv4 address is a broadcast address.

Parameters
• iface – Interface to use. Must be a valid pointer to an interface.
• addr – IPv4 address, this should be in network byte order

Returns
True if address is a broadcast address, false otherwise.

static inline struct net_if *
net_if_ipv4_select_src_iface(const struct in_addr *dst)
Get a network interface that should be used when sending IPv4 network data to destination.

Parameters
• dst – IPv4 destination address

Returns
Pointer to network interface to use, NULL if no suitable interface could be found.

static inline const struct in_addr *
net_if_ipv4_select_src_addr(struct net_if *iface, const struct in_addr *dst)
Get a IPv4 source address that should be used when sending network data to destination.

Parameters
• iface – Interface to use when sending the packet. If the interface is not known, then NULL can be given.
• dst – IPv4 destination address

Returns
Pointer to IPv4 address to use, NULL if no IPv4 address could be found.

struct in_addr *
net_if_ipv4_get_ll(struct net_if *iface, enum net_addr_state addr_state)
Get a IPv4 link local address in a given state.

Parameters
• `iface` – Interface to use. Must be a valid pointer to an interface.
• `addr_state` – IPv4 address state (preferred, tentative, deprecated)

**Returns**
Pointer to link local IPv4 address, NULL if no proper IPv4 address could be found.

```c
struct in_addr *net_if_ipv4_get_global_addr(struct net_if *iface, enum net_addr_state addr_state)
```

Get a IPv4 global address in a given state.

**Parameters**
• `iface` – Interface to use. Must be a valid pointer to an interface.
• `addr_state` – IPv4 address state (preferred, tentative, deprecated)

**Returns**
Pointer to link local IPv4 address, NULL if no proper IPv4 address could be found.

```c
struct in_addr net_if_ipv4_get_netmask(struct net_if *iface)
```

Get IPv4 netmask of an interface.

**Parameters**
• `iface` – Interface to use.

**Returns**
The netmask set on the interface, unspecified address if not found.

```c
void net_if_ipv4_set_netmask(struct net_if *iface, const struct in_addr *netmask)
```

Set IPv4 netmask for an interface.

**Parameters**
• `iface` – Interface to use.
• `netmask` – IPv4 netmask

```c
bool net_if_ipv4_set_netmask_by_index(int index, const struct in_addr *netmask)
```

Set IPv4 netmask for an interface index.

**Parameters**
• `index` – Network interface index
• `netmask` – IPv4 netmask

**Returns**
True if netmask was added, false otherwise.

```c
void net_if_ipv4_set_gw(struct net_if *iface, const struct in_addr *gw)
```

Set IPv4 gateway for an interface.

**Parameters**
• `iface` – Interface to use.
• `gw` – IPv4 address of an gateway

```c
bool net_if_ipv4_set_gw_by_index(int index, const struct in_addr *gw)
```

Set IPv4 gateway for an interface index.

**Parameters**
• `index` – Network interface index
• `gw` – IPv4 address of an gateway
struct net_if *net_if_select_src_iface(const struct sockaddr *dst)
Get a network interface that should be used when sending IPv6 or IPv4 network data to destination.

Parameters
• dst – IPv6 or IPv4 destination address

Returns
True if gateway was added, false otherwise.

void net_if_register_link_cb(struct net_if_link_cb *link, net_if_link_callback_t cb)
Register a link callback.

Parameters
• link – Caller specified handler for the callback.
• cb – Callback to register.

void net_if_unregister_link_cb(struct net_if_link_cb *link)
Unregister a link callback.

Parameters
• link – Caller specified handler for the callback.

void net_if_call_link_cb(struct net_if *iface, struct net_linkaddr *lladdr, int status)
Call a link callback function.

Parameters
• iface – Network interface.
• lladdr – Destination link layer address
• status – 0 is ok, < 0 error

bool net_if_need_calc_rx_checksum(struct net_if *iface)
Check if received network packet checksum calculation can be avoided or not.

For example many ethernet devices support network packet offloading in which case the IP stack does not need to calculate the checksum.

Parameters
• iface – Network interface

Returns
True if checksum needs to be calculated, false otherwise.

bool net_if_need_calc_tx_checksum(struct net_if *iface)
Check if network packet checksum calculation can be avoided or not when sending the packet.

For example many ethernet devices support network packet offloading in which case the IP stack does not need to calculate the checksum.

Parameters
• iface – Network interface

Returns
True if checksum needs to be calculated, false otherwise.
struct net_if *net_if_get_by_index(int index)
Get interface according to index.
This is a syscall only to provide access to the object for purposes of assigning permissions.

Parameters
• index – Interface index

Returns
Pointer to interface or NULL if not found.

int net_if_get_by_iface(struct net_if *iface)
Get interface index according to pointer.

Parameters
• iface – Pointer to network interface

Returns
Interface index

void net_if_foreach(net_if_cb_t cb, void *user_data)
Go through all the network interfaces and call callback for each interface.

Parameters
• cb – User-supplied callback function to call
• user_data – User specified data

int net_if_up(struct net_if *iface)
Bring interface up.

Parameters
• iface – Pointer to network interface

Returns
0 on success

static inline bool net_if_is_up(struct net_if *iface)
Check if interface is is up and running.

Parameters
• iface – Pointer to network interface

Returns
True if interface is up, False if it is down.

int net_if_down(struct net_if *iface)
Bring interface down.

Parameters
• iface – Pointer to network interface

Returns
0 on success

static inline bool net_if_is_admin_up(struct net_if *iface)
Check if interface was brought up by the administrator.

Parameters
• iface – Pointer to network interface

Returns
True if interface is admin up, false otherwise.
void net_if_carrier_on(struct net_if *iface)
Underlying network device has detected the carrier (cable connected).
The function should be used by the respective network device driver or L2 implementation to update its state on a network interface.

Parameters
  • iface – Pointer to network interface

void net_if_carrier_off(struct net_if *iface)
Underlying network device has lost the carrier (cable disconnected).
The function should be used by the respective network device driver or L2 implementation to update its state on a network interface.

Parameters
  • iface – Pointer to network interface

static inline bool net_if_is_carrier_ok(struct net_if *iface)
Check if carrier is present on network device.

Parameters
  • iface – Pointer to network interface

Returns
  True if carrier is present, false otherwise.

void net_if_dormant_on(struct net_if *iface)
Mark interface as dormant.
Dormant state indicates that the interface is not ready to pass packets yet, but is waiting for some event (for example Wi-Fi network association).
The function should be used by the respective network device driver or L2 implementation to update its state on a network interface.

Parameters
  • iface – Pointer to network interface

void net_if_dormant_off(struct net_if *iface)
Mark interface as not dormant.
The function should be used by the respective network device driver or L2 implementation to update its state on a network interface.

Parameters
  • iface – Pointer to network interface

static inline bool net_if_is_dormant(struct net_if *iface)
Check if the interface is dormant.

Parameters
  • iface – Pointer to network interface

Returns
  True if interface is dormant, false otherwise.

static inline int net_if_set_promisc(struct net_if *iface)
Set network interface into promiscuous mode.
Note that not all network technologies will support this.

Parameters
• iface – Pointer to network interface

Returns
0 on success, <0 if error
static inline void net_if_unset_promisc(struct net_if *iface)
Set network interface into normal mode.

Parameters
• iface – Pointer to network interface

static inline bool net_if_is_promisc(struct net_if *iface)
Check if promiscuous mode is set or not.

Parameters
• iface – Pointer to network interface

Returns
True if interface is in promisc mode, False if interface is not in promiscuous mode.

static inline bool net_if_are_pending_tx_packets(struct net_if *iface)
Check if there are any pending TX network data for a given network interface.

Parameters
• iface – Pointer to network interface

Returns
True if there are pending TX network packets for this network interface, False otherwise.

bool net_if_is_wifi(struct net_if *iface)
Check if the network interface supports Wi-Fi.

Parameters
• iface – Pointer to network interface

Returns
True if interface supports Wi-Fi, False otherwise.

struct net_if *net_if_get_first_wifi(void)
Get first Wi-Fi network interface.

Returns
Pointer to network interface, NULL if not found.

int net_if_get_name(struct net_if *iface, char *buf, int len)
Get network interface name.
If interface name support is not enabled, empty string is returned.

Parameters
• iface – Pointer to network interface
• buf – User supplied buffer
• len – Length of the user supplied buffer

Returns
Length of the interface name copied to buf, -EINVAL if invalid parameters, -ERANGE if name cannot be copied to the user supplied buffer, -ENOTSUP if interface name support is disabled,
int net_if_set_name(struct net_if *iface, const char *buf)
    Set network interface name.
    Normally this function is not needed to call as the system will automatically assign a
    name to the network interface.

    Parameters
    • iface – Pointer to network interface
    • buf – User supplied name

    Returns
    0 name is set correctly -ENOTSUP interface name support is disabled -
    EINVAL if invalid parameters are given, -ENAMETOOLONG if name is too
    long

int net_if_get_by_name(const char *name)
    Get interface index according to its name.

    Parameters
    • name – Name of the network interface

    Returns
    Interface index

struct net_if_addr
    #include <net_if.h> Network Interface unicast IP addresses.
    Stores the unicast IP addresses assigned to this network interface.

    Public Members

    struct net_addr address
        IP address.

    enum net_addr_type addr_type
        How the IP address was set.

    enum net_addr_state addr_state
        What is the current state of the address.

    uint8_t is_infinite
        Is the IP address valid forever.

    uint8_t is_used
        Is this IP address used or not.

    uint8_t is_mesh_local
        Is this IP address usage limited to the subnet (mesh) or not.

struct net_if_mcast_addr
    #include <net_if.h> Network Interface multicast IP addresses.
    Stores the multicast IP addresses assigned to this network interface.
**Public Members**

struct net_addr address  
IP address.

uint8_t is_used  
Is this multicast IP address used or not.

uint8_t is_joined  
Did we join to this group.

struct net_if_ipv6_prefix  
#include <net_if.h> Network Interface IPv6 prefixes.
Stores the IPV6 prefixes assigned to this network interface.

**Public Members**

struct net_timeout lifetime  
Prefix lifetime.

struct in6_addr prefix  
IPv6 prefix.

struct net_if *iface  
Backpointer to network interface where this prefix is used.

uint8_t len  
Prefix length.

uint8_t is_infinite  
Is the IP prefix valid forever.

uint8_t is_used  
Is this prefix used or not.

struct net_if_router  
#include <net_if.h> Information about routers in the system.
Stores the router information.

**Public Members**

sys_snode_t node  
Slist lifetime timer node.

struct net_addr address  
IP address.

6.3. Networking
struct *iface

Network interface the router is connected to.

uint32_t life_start

Router life timer start.

uint16_t lifetime

Router lifetime.

uint8_t is_used

Is this router used or not.

uint8_t is_default

Is default router.

uint8_t is_infinite

Is the router valid forever.

struct net_if_ipv6

#include <net_if.h>

Public Members

struct net_if_addr unicast[NET_IF_MAX_IPV6_ADDR]

Unicast IP addresses.

struct net_if_mcast_addr mcast[NET_IF_MAX_IPV6_MADDR]

Multicast IP addresses.

struct net_if_ipv6_prefix prefix[NET_IF_MAX_IPV6_PREFIX]

Prefixes.

uint32_t base_reachable_time

Default reachable time (RFC 4861, page 52)

uint32_t reachable_time

Reachable time (RFC 4861, page 20)

uint32_t retrans_timer

Retransmit timer (RFC 4861, page 52)

uint8_t hop_limit

IPv6 hop limit.

uint8_t mcast_hop_limit

IPv6 multicast hop limit.
Public Members

```c
struct net_if_addr unicast[NET_IF_MAX_IPV4_ADDR]
    Unicast IP addresses.

struct net_if_mcast_addr mcast[NET_IF_MAX_IPV4_MADDR]
    Multicast IP addresses.

struct in_addr gw
    Gateway.

struct in_addr netmask
    Netmask.

uint8_t ttl
    IPv4 time-to-live.

uint8_t mcast_ttl
    IPv4 time-to-live for multicast packets.
```

```c
struct net_if_ip
    #include <net_if.h> Network interface IP address configuration.

struct net_if_config
    #include <net_if.h> IP and other configuration related data for network interface.

struct net_traffic_class
    #include <net_if.h> Network traffic class.
    Traffic classes are used when sending or receiving data that is classified with different priorities. So some traffic can be marked as high priority and it will be sent or received first. Each network packet that is transmitted or received goes through a fifo to a thread that will transmit it.

Public Members

```c
struct k_fifo fifo
    Fifo for handling this Tx or Rx packet.

struct k_thread handler
    Traffic class handler thread.

k_thread_stack_t *stack
    Stack for this handler.

struct net_if_dev
    #include <net_if.h> Network Interface Device structure.
    Used to handle a network interface on top of a device driver instance. There can be many net_if_dev instance against the same device.
Such interface is mainly to be used by the link layer, but is also tight to a network context: it then makes the relation with a network context and the network device. Because of the strong relationship between a device driver and such network interface, each `net_if_dev` should be instantiated by one of the network device init macros found in net_if.h.

**Public Members**

```c
const struct device *dev
    The actually device driver instance the `net_if` is related to.

const struct net_l2 *const l2
    Interface's L2 layer.

void *l2_data
    Interface's private L2 data pointer.

struct net_linkaddr link_addr
    The hardware link address.

uint16_t mtu
    The hardware MTU.

enum net_if_oper_state oper_state
    RFC 2863 operational status.
```

```c
struct net_if
    #include <net_if.h> Network Interface structure.
    Used to handle a network interface on top of a `net_if_dev` instance. There can be many `net_if` instance against the same `net_if_dev` instance.

**Public Members**

```c
struct net_if_dev *if_dev
    The `net_if_dev` instance the `net_if` is related to.

struct net_if_config config
    Network interface instance configuration.

struct net_if_mcast_monitor
    #include <net_if.h> Multicast monitor handler struct.
    Stores the multicast callback information. Caller must make sure that the variable pointed by this is valid during the lifetime of registration. Typically this means that the variable cannot be allocated from stack.
```
Public Members

```c
sys_snodi node
   Node information for the slist.

struct net_if *iface
   Network interface.

net_if_mcast_callback_t cb
   Multicast callback.
```

```c
struct net_if_link_cb
   #include <net_if.h> Link callback handler struct.
   Stores the link callback information. Caller must make sure that the variable pointed by this is valid during the lifetime of registration. Typically this means that the variable cannot be allocated from stack.
```

Public Members

```c
sys_snodi node
   Node information for the slist.

net_if_link_callback_t cb
   Link callback.
```

L2 Layer Management

- **Overview**
- **L2 layer API**
- **Network Device drivers**
  - Ethernet device driver
  - IEEE 802.15.4 device driver
- **API Reference**

**Overview**  The L2 stack is designed to hide the whole networking link-layer part and the related device drivers from the upper network stack. This is made through a `net_if` declared in include/zephyr/net/net_if.h.

The upper layers are unaware of implementation details beyond the `net_if` object and the generic API provided by the L2 layer in include/zephyr/net/net_l2.h as `net_l2`.

Only the L2 layer can talk to the device driver, linked to the `net_if` object. The L2 layer dictates the API provided by the device driver, specific for that device, and optimized for working together.

Currently, there are L2 layers for Ethernet, IEEE 802.15.4 Soft-MAC, Bluetooth IPSP, CANBUS, OpenThread, Wi-Fi, and a dummy layer example that can be used as a template for writing a new one.
L2 layer API  In order to create an L2 layer, or a driver for a specific L2 layer, one needs to understand how the L3 layer interacts with it and how the L2 layer is supposed to behave. See also network stack architecture for more details. The generic L2 API has these functions:

-recv(): All device drivers, once they receive a packet which they put into a net_pkt, will push this buffer to the network stack via net_recv_data(). At this point, the network stack does not know what to do with it. Instead, it passes the buffer along to the L2 stack’s recv() function for handling. The L2 stack does what it needs to do with the packet, for example, parsing the link layer header, or handling link-layer only packets. The recv() function will return NET_DROP in case of an erroneous packet, NET_OK if the packet was fully consumed by the L2, or NET_CONTINUE if the network stack should then handle it.

-send(): Similar to receive function, the network stack will call this function to actually send a network packet. All relevant link-layer content will be generated and added by this function. The send() function returns the number of bytes sent, or a negative error code if there was a failure sending the network packet.

-enable(): This function is used to enable/disable traffic over a network interface. The function returns <0 if error and >=0 if no error.

-get_flags(): This function will return the capabilities of an L2 driver, for example whether the L2 supports multicast or promiscuous mode.

Network Device drivers  Network device drivers fully follows Zephyr device driver model as a basis. Please refer to Device Driver Model.

There are, however, two differences:

- The driver_api pointer must point to a valid net_if_api pointer.

- The network device driver must use NET_DEVICE_INIT_INSTANCE() or ETH_NET_DEVICE_INIT() for Ethernet devices. These macros will call the DEVICE_DEFINE() macro, and also instantiate a unique net_if related to the created device driver instance.

Implementing a network device driver depends on the L2 stack it belongs to: Ethernet, IEEE 802.15.4, etc. In the next section, we will describe how a device driver should behave when receiving or sending a network packet. The rest is hardware dependent and is not detailed here.

Ethernet device driver  On reception, it is up to the device driver to fill-in the network packet with as many data buffers as required. The network packet itself is a net_pkt and should be allocated through net_pkt_rx_alloc_with_buffer(). Then all data buffers will be automatically allocated and filled by net_pkt_write().

After all the network data has been received, the device driver needs to call net_recv_data(). If that call fails, it will be up to the device driver to unreference the buffer via net_pkt_unref().

On sending, the device driver send function will be called, and it is up to the device driver to send the network packet all at once, with all the buffers.

Each Ethernet device driver will need, in the end, to call ETH_NET_DEVICE_INIT() like this:

```
ETH_NET_DEVICE_INIT(..., CONFIG_ETH_INIT_PRIORITY,
                         &the_valid_net_if_api_instance, 1500);
```

IEEE 802.15.4 device driver  Device drivers for IEEE 802.15.4 L2 work basically the same as for Ethernet. What has been described above, especially for recv(), applies here as well. There are two specific differences however:

- It requires a dedicated device driver API: ieee802154_radio_api, which overloads net_if_api. This is because 802.15.4 L2 needs more from the device driver
than just send() and recv() functions. This dedicated API is declared in include/zephyr/net/ieee802154_radio.h. Each and every IEEE 802.15.4 device driver must provide a valid pointer on such relevantly filled-in API structure.

- Sending a packet is slightly different than in Ethernet. Most IEEE 802.15.4 PHYs support relatively small frames only, 127 bytes all inclusive: frame header, payload and frame checksum. Buffers to be sent over the radio will often not fit this frame size limitation, e.g. a buffer containing an IPv6 packet will often have to be split into several fragments and IP6 packet headers and fragments need to be compressed using a protocol like 6LoWPAN before being passed on to the radio driver. Additionally the IEEE 802.15.4 standard defines medium access (e.g. CSMA/CA), frame retransmission, encryption and other pre-processing procedures (e.g. addition of information elements) that individual radio drivers should not have to care about. This is why the ieee802154_radio_api requires a tx function pointer which differs from the net_if_api send function pointer. Zephyr's native IEEE 802.15.4 L2 implementation provides a generic ieee802154_send() instead, meant to be given as net_if send function. The implementation of ieee802154_send() takes care of IEEE 802.15.4 standard packet preparation procedures, splitting the packet into possibly compressed, encrypted and otherwise pre-processed fragment buffers, sending one buffer at a time through ieee802154_radio_api tx function and unreferencing the network packet only when the transmission as a whole was either successful or failed.

Interaction between IEEE 802.15.4 radio device drivers and L2 is bidirectional:

- **L2 -> L1:** Methods as ieee802154_send() and several IEEE 802.15.4 net management calls will call into the driver, e.g. to send a packet over the radio link or re-configure the driver at runtime. These incoming calls will all be handled by the methods in the ieee802154_radio_api.

- **L1 -> L2:** There are several situations in which the driver needs to initiate calls into the L2/MAC layer. Zephyr's IEEE 802.15.4 L1 -> L2 adaptation API employs an “inversion-of-control” pattern in such cases avoids duplication of complex logic across independent driver implementations and ensures implementation agnostic loose coupling and clean separation of concerns between MAC (L2) and PHY (L1) whenever reverse information transfer or close co-operation between hardware and L2 is required. During driver initialization, for example, the driver calls ieee802154_init() to pass the interface's MAC address as well as other hardware-related configuration to L2. Similarly, drivers may indicate performance or timing critical radio events to L2 that require close integration with the hardware (e.g. ieee802154_handle_ack()). Calls from L1 into L2 are not implemented as methods in ieee802154_radio_api but are standalone functions declared and documented as such in include/zephyr/net/ieee802154_radio.h. The API documentation will clearly state which functions must be implemented by all L2 stacks as part of the L1 -> L2 “inversion-of-control” adaptation API.

Note: Standalone functions in include/zephyr/net/ieee802154_radio.h that are not explicitly documented as callbacks are considered to be helper functions within the PHY (L1) layer implemented independently of any specific L2 stack, see for example ieee802154_is_ar_flag_set().

As all net interfaces, IEEE 802.15.4 device driver implementations will have to call NET_DEVICE_INIT_INSTANCE() in the end:

```c
NET_DEVICE_INIT_INSTANCE(...,
    the_device_init_prio,
    &the_valid_ieee802154_radio_api_instance,
    IEEE802154_L2,
    NET_L2_GET_CTX_TYPE(IEEE802154_L2), 125);
```

**API Reference**

**Related code samples**

**Link Layer Discovery Protocol (LLDP)**

Enable LLDP support and setup VLANs.

---

6.3. Networking 2733
Virtual LAN
Setup two virtual LAN networks and use net-shell to view the networks’ settings.

`group net_12`
Network Layer 2 abstraction layer.

**Enums**

`enum net_12_flags`
L2 flags.

*Values:*

- Enumerator `NET_L2_MULTICAST = BIT(0)`
  IP multicast supported.

- Enumerator `NET_L2_MULTICAST_SKIP_JOIN_SOLICIT_NODE = BIT(1)`
  Do not join solicited node multicast group.

- Enumerator `NET_L2_PROMISC_MODE = BIT(2)`
  Is promiscuous mode supported.

- Enumerator `NET_L2_POINT_TO_POINT = BIT(3)`
  Is this L2 point-to-point with tunneling so no need to have IP address etc to network interface.

`struct net_12`

*#include <net_l2.h>* Network L2 structure.

Used to provide an interface to lower network stack.

**Public Members**

`enum net_verdict (*recv)(struct net_if *iface, struct net_pkt *pkt)`
This function is used by net core to get iface’s L2 layer parsing what’s relevant to itself.

`int (*send)(struct net_if *iface, struct net_pkt *pkt)`
This function is used by net core to push a packet to lower layer (interface’s L2), which in turn might work on the packet relevantly.

(adding proper header etc...) Returns a negative error code, or the number of bytes sent otherwise.

`int (*enable)(struct net_if *iface, bool state)`
This function is used to enable/disable traffic over a network interface.

The function returns <0 if error and >=0 if no error:

`enum net_l2_flags (*get_flags)(struct net_if *iface)`
Return L2 flags for the network interface.
Network Traffic Offloading

- **Network Offloading**
  - Overview
  - API Reference
- **Socket Offloading**
  - Overview

Network Offloading

**Overview** The network offloading API provides hooks that a device vendor can use to provide an alternate implementation for an IP stack. This means that the actual network connection creation, data transfer, etc., is done in the vendor HAL instead of the Zephyr network stack.

**API Reference**

*group net_offload*

Network offloading interface.

Socket Offloading

**Overview** In addition to the network offloading API, Zephyr allows offloading of networking functionality at the socket API level. With this approach, vendors who provide an alternate implementation of the networking stack, exposing socket API for their networking devices, can easily integrate it with Zephyr.

See [drivers/wifi/simplelink/simplelink_sockets.c](#) for a sample implementation on how to integrate network offloading at socket level.

Link Layer Address Handling

- **Overview**
- **API Reference**

**Overview** The link layer addresses are set for network interfaces so that L2 connectivity works correctly in the network stack. Typically the link layer addresses are 6 bytes long like in Ethernet but for IEEE 802.15.4 the link layer address length is 8 bytes.

**API Reference**

*group net_linkaddr*

Network link address library.
Defines

**NET_LINK_ADDR_MAX_LENGTH**

Maximum length of the link address.

Enums

```c
enum net_link_type
{
    NET_LINK_UNKNOWN = 0,
    NET_LINK_IEEE802154,
    NET_LINK_BLUETOOTH,
    NET_LINK_ETHERNET,
    NET_LINK_DUMMY,
    NET_LINK_CANBUS_RAW,
}
```

*Type of the link address. This indicates the network technology that this address is used in. Note that in order to save space we store the value into a uint8_t variable, so please do not introduce any values > 255 in this enum.*

*Values:*

- **NET_LINK_UNKNOWN**
  - Unknown link address type.
- **NET_LINK_IEEE802154**
  - IEEE 802.15.4 link address.
- **NET_LINK_BLUETOOTH**
  - Bluetooth IPSP link address.
- **NET_LINK_ETHERNET**
  - Ethernet link address.
- **NET_LINK_DUMMY**
  - Dummy link address.
  - Used in testing apps and loopback support.
- **NET_LINK_CANBUS_RAW**
  - CANBUS link address.

Functions

```c
static inline bool net_linkaddr_cmp(struct net_linkaddr *lladdr1, struct net_linkaddr *lladdr2)
```

*Compare two link layer addresses.*

**Parameters**

- **lladdr1** – Pointer to a link layer address
- **lladdr2** – Pointer to a link layer address

**Returns**

*True if the addresses are the same, false otherwise.*
static inline int net_linkaddr_set(struct net_linkaddr_storage *lladdr_store, uint8_t *new_addr, uint8_t new_len)

Set the member data of a link layer address storage structure.

**Parameters**

- `lladdr_store` – The link address storage structure to change.
- `new_addr` – Array of bytes containing the link address.
- `new_len` – Length of the link address array. This value should always be <= NET_LINK_ADDR_MAX_LENGTH.

**Public Members**

uint8_t *addr
The array of byte representing the address.

uint8_t len
Length of that address array.

uint8_t type
What kind of address is this for.

**Public Members**

uint8_t type
What kind of address is this for.

uint8_t len
The real length of the ll address.

uint8_t addr[6]
The array of bytes representing the address.
Ethernet Management

- Overview
- API Reference

**Overview** Ethernet management API provides functions to manage the Ethernet network interface low level status. The caller of these functions can:

- raise carrier ON or carrier OFF management events
- raise VLAN enabled or VLAN disabled management events

Typically the carrier OFF event would be generated by the Ethernet device driver when it notices that the Ethernet cable is disconnected. The carrier ON event would be generated if the Ethernet device driver notices that the Ethernet cable is re-connected.

Currently the VLAN events are generated by the Ethernet L2 layer when a specific VLAN tag is either enabled or disabled.

The user application can monitor these events if it needs to act when the corresponding status changes.

**API Reference**

*group ethernet_mgmt*

Ethernet library.

**Functions**

- **void ethernet_mgmt_raise_carrier_on_event(struct net_if *iface)**
  
  Raise CARRIER_ON event when Ethernet is connected.

  **Parameters**
  - *iface* – Ethernet network interface.

- **void ethernet_mgmt_raise_carrier_off_event(struct net_if *iface)**
  
  Raise CARRIER_OFF event when Ethernet is disconnected.

  **Parameters**
  - *iface* – Ethernet network interface.

- **void ethernet_mgmt_raise_vlan_enabled_event(struct net_if *iface, uint16_t tag)**
  
  Raise VLAN_ENABLED event when VLAN is enabled.

  **Parameters**
  - *iface* – Ethernet network interface.
  - *tag* – VLAN tag which is enabled.

- **void ethernet_mgmt_raise_vlan_disabled_event(struct net_if *iface, uint16_t tag)**
  
  Raise VLAN_DISABLED event when VLAN is disabled.

  **Parameters**
  - *iface* – Ethernet network interface.
  - *tag* – VLAN tag which is disabled.
Traffic Classification

Overview  Traffic classification is an automated process that categorizes computer network traffic according to various parameters. For Zephyr, the VLAN priority code point (PCP) is used to classify both received and sent network packets. See more information about VLAN priority at IEEE 802.1Q.

By default, all network traffic is treated equal in Zephyr. If desired, the option CONFIG_NET_TC_TX_COUNT can be used to set the number of transmit queues. The option CONFIG_NET_TC_RX_COUNT can be used to set the number of receive queues. Each traffic class queue corresponds to a specific kernel work queue. Each kernel work queue has a priority. The VLAN priority is mapped to a certain traffic class according to rules specified in IEEE 802.1Q spec chapter I.3, chapter 8.6.6 table 8-4, and chapter 34.5 table 34-1. Each traffic class is in turn mapped to a certain kernel work queue. The maximum number of traffic classes for both Rx and Tx is 8.

See subsys/net/ip/net_tc.c for details of how various mappings are done.

Network Packet Filtering

Overview  The Network Packet Filtering facility provides the infrastructure to construct custom rules for accepting and/or denying packet transmission and reception. This can be used to create a basic firewall, control network traffic, etc.

The CONFIG_NET_PKT_FILTER must be set in order to enable the relevant APIs.

Both the transmission and reception paths may have a list of filter rules. Each rule is made of a set of conditions and a packet outcome. Every packet is subjected to the conditions attached to a rule. When all the conditions for a given rule are true then the packet outcome is immediately determined as specified by the current rule and no more rules are considered. If one condition is false then the next rule in the list is considered.

Packet outcome is either NET_OK to accept the packet or NET_DROP to drop it.

A rule is represented by a npf_rule object. It can be inserted to, appended to or removed from a rule list contained in a npf_rule_list object using npf_insert_rule(), npf_append_rule(), and npf_remove_rule(). Currently, two such rule lists exist: npf_send_rules for outgoing packets, and npf_recv_rules for incoming packets.

If a filter rule list is empty then NET_OK is assumed. If a non-empty rule list runs to the end then NET_DROP is assumed. However it is recommended to always terminate a non-empty rule list with an explicit default termination rule, either npf_default_ok or npf_default_drop.

Rule conditions are represented by a npf_test. This structure can be embedded into a larger structure when a specific condition requires extra test data. It is up to the test function for such conditions to retrieve the outer structure from the provided npf_test structure pointer.

Convenience macros are provided in include/zephyr/net/net_pkt_filter.h to statically define condition instances for various conditions, and NPF_RULE() to create a rule instance to tie them.

Examples  Here’s an example usage:
static NPF_SIZE_MAX(maxsize_200, 200);
static NPF_ETH_TYPE_MATCH(ip_packet, NET_ETH_PTYPE_IP);
static NPF_RULE(small_ip_pkt, NET_OK, ip_packet, maxsize_200);

void install_my_filter(void)
{
  npf_insert_recv_rule(&npf_default_drop);
  npf_insert_recv_rule(&small_ip_pkt);
}

The above would accept IP packets that are 200 bytes or smaller, and drop all other packets.

Another (less efficient) way to achieve the same result could be:

static NPF_SIZE_MIN(minsize_201, 201);
static NPF_ETH_TYPE_UNMATCH(not_ip_packet, NET_ETH_PTYPE_IP);
static NPF_RULE(reject_big_pkts, NET_DROP, minsize_201);
static NPF_RULE(reject_non_ip, NET_DROP, not_ip_packet);

void install_my_filter(void) {
  npf_append_recv_rule(&reject_big_pkts);
  npf_append_recv_rule(&reject_non_ip);
  npf_append_recv_rule(&npf_default_ok);
}

API Reference

group net_pkt_filter

Network Packet Filter API.

Defines

npf_insert_send_rule(rule)
npf_insert_recv_rule(rule)
npf_append_send_rule(rule)
npf_append_recv_rule(rule)
npf_remove_send_rule(rule)
npf_remove_recv_rule(rule)
npf_remove_all_send_rules()
npf_remove_all_recv_rules()

NPF_RULE(_name, _result, ...)

Statically define one packet filter rule.

This creates a rule from a variable amount of filter conditions. This rule can then be inserted or appended to the rule list for a given network packet path.

Example:
The above would accept IP packets that are 200 bytes or smaller, and drop all other packets.

Another (less efficient) way to create the same result could be:

```
static NPF_SIZE_MIN(minsize_201, 201);
static NPF_ETH_TYPE_UNMATCH(not_ip_packet, NET_ETH_PTYPE_IP);
static NPF_RULE(reject_big_pkts, NET_DROP, minsize_201);
static NPF_RULE(reject_non_ip, NET_DROP, not_ip_packet);
void install_my_filter(void) {
    npf_append_recv_rule(&reject_big_pkts);
    npf_append_recv_rule(&reject_non_ip);
    npf_append_recv_rule(&npf_default_ok);
}
```

The first rule in the list for which all conditions are true determines the fate of the packet. If one condition is false then the next rule in the list is evaluated.

**Parameters**

- `_name` – Name for this rule.
- `_result` – Fate of the packet if all conditions are true, either `NET_OK` or `NET_DROP`.
- `...` – List of conditions for this rule.

**Functions**

`void npf_insert_rule(struct npf_rule_list *rules, struct npf_rule *rule)`

Insert a rule at the front of given rule list.

**Parameters**

- `rules` – the affected rule list
- `rule` – the rule to be inserted

`void npf_append_rule(struct npf_rule_list *rules, struct npf_rule *rule)`

Append a rule at the end of given rule list.

**Parameters**

- `rules` – the affected rule list
- `rule` – the rule to be appended

`bool npf_remove_rule(struct npf_rule_list *rules, struct npf_rule *rule)`

Remove a rule from the given rule list.

**Parameters**
• rules – the affected rule list
• rule – the rule to be removed

Return values
true – if given rule was found in the rule list and removed

bool npf_remove_all_rules(struct npf_rule_list *rules)
Remove all rules from the given rule list.

Parameters
• rules – the affected rule list

Return values
true – if at least one rule was removed from the rule list

Variables

struct npf_rule npf_default_ok
Default rule list termination for accepting a packet.

struct npf_rule npf_default_drop
Default rule list termination for rejecting a packet.

struct npf_rule_list npf_send_rules
rule list applied to outgoing packets

struct npf_rule_list npf_recv_rules
rule list applied to incoming packets

struct npf_rule_list npf_local_in_recv_rules
rule list applied for local incoming packets

struct npf_rule_list npf_ipv4_recv_rules
rule list applied for IPv4 incoming packets

struct npf_rule_list npf_ipv6_recv_rules
rule list applied for IPv6 incoming packets

struct npf_test
#include <net_pkt_filter.h> common filter test structure to be embedded into larger structures

Public Members

npf_test_fn_t *fn
packet condition test function

struct npf_rule
#include <net_pkt_filter.h> filter rule structure
Public Members

defined net_verdict result
result if all tests pass

defined uint32_t nb_tests
number of tests for this rule

struct npf_test *tests[]
pointers to npf_test instances

struct npf_rule_list
#include <net_pkt_filter.h> rule set for a given test location

group npf_basic_cond

Defines

#define NPF_IFACE_MATCH(_name, _iface)
Statically define an “interface match” packet filter condition.

Parameters
• _name – Name of the condition
• _iface – Interface to match

#define NPF_IFACE_UNMATCH(_name, _iface)
Statically define an “interface unmatch” packet filter condition.

Parameters
• _name – Name of the condition
• _iface – Interface to exclude

#define NPF_ORIG_IFACE_MATCH(_name, _iface)
Statically define an “orig interface match” packet filter condition.

Parameters
• _name – Name of the condition
• _iface – Interface to match

#define NPF_ORIG_IFACE_UNMATCH(_name, _iface)
Statically define an “orig interface unmatch” packet filter condition.

Parameters
• _name – Name of the condition
• _iface – Interface to exclude

#define NPF_SIZE_MIN(_name, _size)
Statically define a “data minimum size” packet filter condition.

Parameters
• _name – Name of the condition
• _size – Lower bound of the packet’s data size
NPF_SIZE_MAX(_name, _size)
Statically define a “data maximum size” packet filter condition.

Parameters
- _name – Name of the condition
- _size – Higher bound of the packet’s data size

NPF_SIZE_BOUNDS(_name, _min_size, _max_size)
Statically define a “data bounded size” packet filter condition.

Parameters
- _name – Name of the condition
- _min_size – Lower bound of the packet’s data size
- _max_size – Higher bound of the packet’s data size

NPF_IP_SRC_ADDR_ALLOWLIST(_name, _ip_addr_array, _ip_addr_num, _af)
Statically define a “ip address allowlist” packet filter condition.
This tests if the packet source ip address matches any of the ip addresses contained in the provided set.

Parameters
- _name – Name of the condition
- _ip_addr_array – Array of struct in_addr or struct in6_addr items to test against
- _ip_addr_num – number of IP addresses in the array
- _af – Addresses family type (AF_INET / AF_INET6) in the array

NPF_IP_SRC_ADDR_BLOCKLIST(_name, _ip_addr_array, _ip_addr_num, _af)
Statically define a “ip address blocklist” packet filter condition.
This tests if the packet source ip address matches any of the ip addresses contained in the provided set.

Parameters
- _name – Name of the condition
- _ip_addr_array – Array of struct in_addr or struct in6_addr items to test against
- _ip_addr_num – number of IP addresses in the array
- _af – Addresses family type (AF_INET / AF_INET6) in the array

group npf_eth_cond

Defines

NPF_ETH_SRC_ADDR_MATCH(_name, _addr_array)
Statically define a “source address match” packet filter condition.
This tests if the packet source address matches any of the Ethernet addresses contained in the provided set.

Parameters
- _name – Name of the condition
• `_addr_array` – Array of `struct net_eth_addr` items to test against

NPF_ETH_SRC_ADDR_UNMATCH(\_name, \_addr\_array)

Statically define a “source address unmatch” packet filter condition.

This tests if the packet source address matches none of the Ethernet addresses contained in the provided set.

**Parameters**

- `_name` – Name of the condition
- `_addr_array` – Array of `struct net_eth_addr` items to test against

NPF_ETH_DST_ADDR_MATCH(\_name, \_addr\_array)

Statically define a “destination address match” packet filter condition.

This tests if the packet destination address matches any of the Ethernet addresses contained in the provided set.

**Parameters**

- `_name` – Name of the condition
- `_addr_array` – Array of `struct net_eth_addr` items to test against

NPF_ETH_DST_ADDR_UNMATCH(\_name, \_addr\_array)

Statically define a “destination address unmatch” packet filter condition.

This tests if the packet destination address matches none of the Ethernet addresses contained in the provided set.

**Parameters**

- `_name` – Name of the condition
- `_addr_array` – Array of `struct net_eth_addr` items to test against

NPF_ETH_SRC_ADDR_MASK_MATCH(\_name, \_addr\_array, ...)

Statically define a “source address match with mask” packet filter condition.

This tests if the packet source address matches any of the Ethernet addresses contained in the provided set after applying specified mask.

**Parameters**

- `_name` – Name of the condition
- `_addr_array` – Array of `struct net_eth_addr` items to test against
- ... – up to 6 mask bytes

NPF_ETH_DST_ADDR_MASK_MATCH(\_name, \_addr\_array, ...)

Statically define a “destination address match with mask” packet filter condition.

This tests if the packet destination address matches any of the Ethernet addresses contained in the provided set after applying specified mask.

**Parameters**

- `_name` – Name of the condition
- `_addr_array` – Array of `struct net_eth_addr` items to test against
- ... – up to 6 mask bytes

NPF_ETH_TYPE_MATCH(\_name, \_type)

Statically define an “Ethernet type match” packet filter condition.

**Parameters**

- `_name` – Name of the condition
- **_type** – Ethernet type to match

```c
NPF_ETH_TYPE_UNMATCH(_name, _type)
```

Statically define an “Ethernet type unmatch” packet filter condition.

**Parameters**

- **_name** – Name of the condition
- **_type** – Ethernet type to exclude

**Network Shell**

Network shell provides helpers for figuring out network status, enabling/disabling features, and issuing commands like ping or DNS resolving. Note that net-shell should probably not be used in production code as it will require extra memory. See also *generic shell* for detailed shell information.

The following net-shell commands are implemented:

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>net allocs</td>
<td>Print network memory allocations. Only available if CONFIG_NET_DEBUG_NET_PKT_ALLOC is set.</td>
</tr>
<tr>
<td>net arp</td>
<td>Print information about IPv4 ARP cache. Only available if CONFIG_NET_ARP is set in IPv4 enabled networks.</td>
</tr>
<tr>
<td>net capture</td>
<td>Monitor network traffic. See <em>Monitor Network Traffic</em> for details.</td>
</tr>
<tr>
<td>net conn</td>
<td>Print information about network connections.</td>
</tr>
<tr>
<td>net dns</td>
<td>Show how DNS is configured. The command can also be used to resolve a DNS name. Only available if CONFIG_DNS_RESOLVER is set.</td>
</tr>
<tr>
<td>net events</td>
<td>Enable network event monitoring. Only available if CONFIG_NET_MGMT_EVENT_MONITOR is set.</td>
</tr>
<tr>
<td>net gptp</td>
<td>Print information about gPTP support. Only available if CONFIG_NET_GPTP is set.</td>
</tr>
<tr>
<td>net iface</td>
<td>Print information about network interfaces.</td>
</tr>
<tr>
<td>net ipv6</td>
<td>Print IPv6 specific information and configuration. Only available if CONFIG_NET_IPV6 is set.</td>
</tr>
<tr>
<td>net mem</td>
<td>Print information about network memory usage. The command will print more information if CONFIG_NET_BUF_POOL_USAGE is set.</td>
</tr>
<tr>
<td>net nbr</td>
<td>Print neighbor information. Only available if CONFIG_NET_IPV6 is set.</td>
</tr>
<tr>
<td>net ping</td>
<td>Ping a network host.</td>
</tr>
<tr>
<td>net route</td>
<td>Show IPv6 network routes. Only available if CONFIG_NET_ROUTE is set.</td>
</tr>
<tr>
<td>net sockets</td>
<td>Show network socket information and statistics. Only available if CONFIG_NET_SOCKETS_OBJ_CORE and CONFIG_OBJ_CORE are set.</td>
</tr>
<tr>
<td>net stats</td>
<td>Show network statistics.</td>
</tr>
<tr>
<td>net tcp</td>
<td>Connect/send data/close TCP connection. Only available if CONFIG_NET_TCP is set.</td>
</tr>
<tr>
<td>net vlan</td>
<td>Show Ethernet virtual LAN information. Only available if CONFIG_NET_VLAN is set.</td>
</tr>
</tbody>
</table>

**TLS Credentials Shell**

The TLS Credentials shell provides a command-line interface for managing installed TLS credentials.

**Commands**

**Buffer Credential (buf)**

Buffer data incrementally into the credential buffer so that it can be added using the *Add Credential (add)* command.

Alternatively, clear the credential buffer.
Usage To append `<DATA>` to the credential buffer, use:

```
cred buf <DATA>
```

Use this as many times as needed to load the full credential into the credential buffer, then use the `Add Credential (add)` command to store it.

To clear the credential buffer, use:

```
cred buf clear
```

**Arguments**

<table>
<thead>
<tr>
<th>Argument</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>&lt;DATA&gt;</code></td>
<td>Text data to be appended to credential buffer. It can be either text, or base64-encoded binary. See <code>Add Credential (add)</code> and <code>Storage/Retrieval Formats</code> for details.</td>
</tr>
</tbody>
</table>

**Add Credential (add)** Add a TLS credential to the TLS Credential store.

Credential contents can be provided in-line with the call to `cred add`, or will otherwise be sourced from the credential buffer.

Usage To add a TLS credential using the data from the credential buffer, use:

```
cred add <SECTAG> <TYPE> <BACKEND> <FORMAT>
```

To add a TLS credential using data provided with the same command, use:

```
cred add <SECTAG> <TYPE> <BACKEND> <FORMAT> <DATA>
```

**Arguments**

<table>
<thead>
<tr>
<th>Argument</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>&lt;SECTAG&gt;</code></td>
<td>The sectag to use for the new credential. Can be any non-negative integer.</td>
</tr>
<tr>
<td><code>&lt;TYPE&gt;</code></td>
<td>The type of credential to add. See <code>Credential Types</code> for valid values.</td>
</tr>
<tr>
<td><code>&lt;BACKEND&gt;</code></td>
<td>Reserved. Must always be <code>DEFAULT</code> (case-insensitive).</td>
</tr>
<tr>
<td><code>&lt;FORMAT&gt;</code></td>
<td>Specifies the storage format of the provided credential. See <code>Storage/Retrieval Formats</code> for valid values.</td>
</tr>
<tr>
<td><code>&lt;DATA&gt;</code></td>
<td>If provided, this argument will be used as the credential data, instead of any data in the credential buffer. Can be either text, or base64-encoded binary.</td>
</tr>
</tbody>
</table>

**Delete Credential (del)** Delete a specified credential from the credential store.

Usage To delete a credential matching a specified sectag and credential type (if it exists), use:

```
cred del <SECTAG> <TYPE>
```

6.3. Networking
Arguments

<table>
<thead>
<tr>
<th>Argument</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&lt;SECTAG&gt;</td>
<td>The sectag of the credential to delete. Can be any non-negative integer.</td>
</tr>
<tr>
<td>&lt;TYPE&gt;</td>
<td>The type of credential to delete. See Credential Types for valid values.</td>
</tr>
</tbody>
</table>

Get Credential Contents (get)  Retrieve and print the contents of a specified credential.

Usage  To retrieve and print a credential matching a specified sectag and credential type (if it exists), use:

```
cred get <SECTAG> <TYPE> <FORMAT>
```

Arguments

<table>
<thead>
<tr>
<th>Argument</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&lt;SECTAG&gt;</td>
<td>The sectag of the credential to get. Can be any non-negative integer.</td>
</tr>
<tr>
<td>&lt;TYPE&gt;</td>
<td>The type of credential to get. See Credential Types for valid values.</td>
</tr>
<tr>
<td>&lt;FORMAT&gt;</td>
<td>Specifies the retrieval format for the provided credential. See Storage/Retrieval Formats for valid values.</td>
</tr>
</tbody>
</table>

List Credentials (list)  List TLS credentials in the credential store.

Usage  To list all available credentials, use:

```
cred list
```

To list all credentials with a specified sectag, use:

```
cred list <SECTAG>
```

To list all credentials with a specified credential type, use:

```
cred list any <TYPE>
```

To list all credentials with a specified credential type and sectag, use:

```
cred list <SECTAG> <TYPE>
```

Arguments

<table>
<thead>
<tr>
<th>Argument</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&lt;SECTAG&gt;</td>
<td>Optional. If provided, only list credentials with this sectag. Pass any or omit to allow any sectag. Otherwise, can be any non-negative integer.</td>
</tr>
<tr>
<td>&lt;TYPE&gt;</td>
<td>Optional. If provided, only list credentials with this credential type. Pass any or omit to allow any credential type. Otherwise, see Credential Types for valid values.</td>
</tr>
</tbody>
</table>
**Output**  The command outputs all matching credentials in the following (CSV-compliant) format:

```
<SECTAG>,<TYPE>,<DIGEST>,<STATUS>
```

Where:

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>&lt;SECTAG&gt;</td>
<td>The sectag of the listed credential. A non-negative integer.</td>
</tr>
<tr>
<td>&lt;TYPE&gt;</td>
<td>Credential type short-code (see <strong>Credential Types</strong> for details) of the listed credential.</td>
</tr>
<tr>
<td>&lt;DIGEST&gt;</td>
<td>A string digest representing the credential contents. The exact nature of this digest may vary depending on credentials storage backend, but currently for all backends this is a base64 encoded SHA256 hash of the raw credential contents (so different storage formats for essentially identical credentials will have different digests).</td>
</tr>
<tr>
<td>&lt;STATUS&gt;</td>
<td>Status code indicating success or failure with generating a digest of the listed credential. 0 if successful, negative error code specific to the storage backend otherwise. Lines for which status is not zero will be printed with error formatting.</td>
</tr>
</tbody>
</table>

After the list is printed, a final summary of the found credentials will be printed in the form:

```
<N> credentials found.
```

Where <N> is the number of credentials found, and is zero if none are found.

**Credential Types**  The following keywords (case-insensitive) may be used to specify a credential type:

<table>
<thead>
<tr>
<th>Keyword(s)</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>CA_CERT, CA</td>
<td>A trusted CA certificate.</td>
</tr>
<tr>
<td>SERVER_CERT, SELF_CERT, CLIENT_CERT, CLIENT, SELF, SERV</td>
<td>Self or server certificate.</td>
</tr>
<tr>
<td>PRI- VATE_KEY, PK</td>
<td>A private key.</td>
</tr>
<tr>
<td>PRE_SHARED_ , PSK</td>
<td>A pre-shared key.</td>
</tr>
<tr>
<td>PRE_SHARED_ , PSK_ID</td>
<td>ID for pre-shared key.</td>
</tr>
</tbody>
</table>

**Storage/Retrieval Formats**  The *tls_credentials* module treats stored credentials as arbitrary binary buffers.

For convenience, the TLS credentials shell offers four formats for providing and later retrieving these buffers using the shell.

These formats and their (case-insensitive) keywords are as follows:
### Key-word Meaning

<table>
<thead>
<tr>
<th>Key-word</th>
<th>Meaning</th>
<th>Behavior during storage</th>
<th>Behavior during retrieval</th>
</tr>
</thead>
<tbody>
<tr>
<td>BIN</td>
<td>Credential is handled by shell as base64 and stored without NULL termination.</td>
<td>Data entered into shell will be decoded from base64 into raw binary before storage. No terminator will be appended.</td>
<td>Stored data will be encoded into base64 before being printed.</td>
</tr>
<tr>
<td>BINT</td>
<td>Credential is handled by shell as base64 and stored with NULL termination.</td>
<td>Data entered into shell will be decoded from base64 into raw binary and a NULL terminator will be appended before storage.</td>
<td>NULL terminator will be truncated from stored data before said data is encoded into base64 and then printed.</td>
</tr>
<tr>
<td>STR</td>
<td>Credential is handled by shell as literal string and stored without NULL termination.</td>
<td>Text data entered into shell will be passed into storage as-written, without a NULL terminator.</td>
<td>Stored data will be printed as text. Non-printable characters will be printed as ?</td>
</tr>
<tr>
<td>STRT</td>
<td>Credential is handled by shell as literal string and stored with NULL termination.</td>
<td>Text data entered into shell will be passed into storage as-written, with a NULL terminator.</td>
<td>NULL terminator will be truncated from stored data before said data is printed as text. Non-printable characters will be printed as ?</td>
</tr>
</tbody>
</table>

The BIN format can be used to install credentials of any type, since base64 can be used to encode any conceivable binary buffer. The remaining three formats are provided for convenience in special use-cases.

For example:

- To install printable pre-shared-keys, use STR to enter the PSK without first encoding it. This ensures it is stored without a NULL terminator.
- To install DER-formatted X.509 certificates (or other raw-binary credentials, such as non-printable PSKs) base64-encode the binary and use the BIN format.
- To install PEM-formatted X.509 certificates or certificate chains, base64 encode the full PEM string (including new-lines and -----BEGIN X ----- / -----END X----- markers), and then use the BINT format to make sure the stored string is NULL-terminated. This is required because Zephyr does not support multi-line strings in the shell. Otherwise, the STRT format could be used for this purpose without base64 encoding. It is possible to use BIN instead if you manually encode a NULL terminator into the base64.

### Time Sensitive Networking

#### generic Precision Time Protocol (gPTP)

- **Overview**
- **Supported features**
- **Supported hardware**
- **Enabling the stack**
- **Application interfaces**
- **Testing**
- **API Reference**
Overview   This gPTP stack supports the protocol and procedures as defined in the IEEE 802.1AS-2011 standard (Timing and Synchronization for Time-Sensitive Applications in Bridged Local Area Networks).

Supported features The stack handles communications and state machines defined in the IEEE 802.1AS-2011 standard. Mandatory requirements for a full-duplex point-to-point link endpoint, as defined in Annex A of the standard, are supported.

The stack is in principle capable of handling communications on multiple network interfaces (also defined as “ports” in the standard) and thus act as a 802.1AS bridge. However, this mode of operation has not been validated on the Zephyr OS.

Supported hardware Although the stack itself is hardware independent, Ethernet frame timestamping support must be enabled in ethernet drivers.

Boards supported:
- frdm_k64f
- nucleo_h743zi_board
- nucleo_h745zi_q_board
- nucleo_f767zi_board
- sam_e70_xplained
- native_sim (only usable for simple testing, limited capabilities due to lack of hardware clock)
- qemu_x86 (emulated, limited capabilities due to lack of hardware clock)

Enabling the stack The following configuration option must me enabled in prj.conf file.
- CONFIG_NET_GPTP

Application interfaces Only two Application Interfaces as defined in section 9 of the standard are available:
- ClockTargetPhaseDiscontinuity interface (gptp_register_phase_dis_cb())
- ClockTargetEventCapture interface (gptp_event_capture())

Testing The stack has been informally tested using the OpenAVnu gPTP and Linux ptp4l daemons. The gPTP sample application from the Zephyr source distribution can be used for testing.

API Reference Related code samples
gPTP Enable gPTP support and monitor functionality using net-shell.

-group gptp
generic Precision Time Protocol (gPTP) support
**Typedefs**

typedef void (*gptp_phase_dis_callback_t)(uint8_t *gm_identity, uint16_t *time_base, struct gptp_scaled_ns *last_gm_ph_change, double *last_gm_freq_change)

Define callback that is called after a phase discontinuity has been sent by the grandmaster.

**Param gm_identity**
A pointer to first element of a ClockIdentity array. The size of the array is GPTP_CLOCK_ID_LEN.

**Param time_base**
A pointer to the value of timeBaseIndicator of the current grandmaster.

**Param last_gm_ph_change**
A pointer to the value of lastGmPhaseChange received from grandmaster.

**Param last_gm_freq_change**
A pointer to the value of lastGmFreqChange received from the grandmaster.

typedef void (*gptp_port_cb_t)(int port, struct net_if *iface, void *user_data)

Callback used while iterating over gPTP ports.

**Param port**
Port number

**Param iface**
Pointer to network interface

**Param user_data**
A valid pointer to user data or NULL

**Functions**

void gptp_register_phase_dis_cb(struct gptp_phase_dis_cb *phase_dis, gptp_phase_dis_callback_t cb)

Register a phase discontinuity callback.

**Parameters**
- **phase_dis** – Caller specified handler for the callback.
- **cb** – Callback to register.

void gptp_unregister_phase_dis_cb(struct gptp_phase_dis_cb *phase_dis)

Unregister a phase discontinuity callback.

**Parameters**
- **phase_dis** – Caller specified handler for the callback.

void gptp_call_phase_dis_cb(void)

Call a phase discontinuity callback function.

int gptp_event_capture(struct net_ptp_time *slave_time, bool *gm_present)

Get gPTP time.

**Parameters**
- **slave_time** – A pointer to structure where timestamp will be saved.
• **gm_present** – A pointer to a boolean where status of the presence of a grand master will be saved.

**Returns**
Error code. 0 if no error.

```c
char *gptp_sprint_clock_id(const uint8_t *clk_id, char *output, size_t output_len)
```
Utility function to print clock id to a user supplied buffer.

**Parameters**
- `clk_id` – Clock id
- `output` – Output buffer
- `output_len` – Output buffer len

**Returns**
Pointer to output buffer

```c
void gptp_foreach_port(gptp_port_cb_t cb, void *user_data)
```
Go through all the gPTP ports and call callback for each of them.

**Parameters**
- `cb` – User-supplied callback function to call
- `user_data` – User specified data

```c
struct gptp_domain *gptp_get_domain(void)
```
Get gPTP domain.

This contains all the configuration / status of the gPTP domain.

**Returns**
Pointer to domain or NULL if not found.

```c
void gptp_clk_src_time_invoke(struct gptp_clk_src_time_invoke_params *arg)
```
This interface is used by the ClockSource entity to provide time to the ClockMaster entity of a time-aware system.

**Parameters**
- `arg` – Current state and parameters of the ClockSource entity.

```c
struct gptp_hdr *gptp_get_hdr(struct net_pkt *pkt)
```
Return pointer to gPTP packet header in network packet.

**Parameters**
- `pkt` – Network packet (received or sent)

**Returns**
Pointer to gPTP header.

```c
struct gptp_scaled_ns
```

```
#include <gptp.h> Scaled Nanoseconds.
```

**Public Members**

```c
int32_t high
```
High half.
int64_t low
    Low half.

struct gptp_uscaled_ns
    #include <gptp.h> UScaled Nanoseconds.

Public Members

    uint32_t high
        High half.

    uint64_t low
        Low half.

struct gptp_port_identity
    #include <gptp.h> Port Identity.

Public Members

    uint8_t clk_id[GPTP_CLOCK_ID_LEN]
        Clock identity of the port.

    uint16_t port_number
        Number of the port.

struct gptp_flags
    #include <gptp.h>

Public Members

    uint8_t octets[2]
        Byte access.

    uint16_t all
        Whole field access.

struct gptp_hdr
    #include <gptp.h>

Public Members

    uint8_t message_type
        Type of the message.
uint8_t transport_specific
   Transport specific, always 1.

uint8_t ptp_version
   Version of the PTP, always 2.

uint8_t reserved0
   Reserved field.

uint8_t reserved1
   Reserved field.

struct gptp_flags flags
   Message flags.

int64_t correction_field
   Correction Field.
   The content depends of the message type.

uint32_t reserved2
   Reserved field.

struct gptp_port_identity port_id
   Port Identity of the sender.

uint16_t sequence_id
   Sequence Id.

uint8_t control
   Control value.
   Sync: 0, Follow-up: 2, Others: 5.

int8_t log_msg_interval
   Message Interval in Log2 for Sync and Announce messages.

struct gptp_phase_dis_cb
   #include <gptp.h> Phase discontinuity callback structure.
   Stores the phase discontinuity callback information. Caller must make sure that the
   variable pointed by this is valid during the lifetime of registration. Typically this means
   that the variable cannot be allocated from stack.
Public Members

`sys_snodet` node
Node information for the slist.

`gptp_phase_dis_callback_t` cb
Phase discontinuity callback.

```c
#include <gptp.h>
ClockSourceTime invoke function parameters.
Parameters passed by ClockSourceTime.invoke function.
```

Public Members

double last_gm_freq_change
Frequency change on the last Time Base Indicator Change.

```c
struct net_ptp_extended_time src_time
The time this function is invoked.
```

```c
struct gptp_scaled_ns last_gm_phase_change
Phase change on the last Time Base Indicator Change.
```

```c
uint16_t time_base_indicator
Time Base - changed only if Phase or Frequency changes.
```

Network time representation in the network stack

API Reference

`group net_time`

Defines

```c
NET_TIME_MAX
The largest positive time value that can be represented by net_time_t.
```

```c
NET_TIME_MIN
The smallest negative time value that can be represented by net_time_t.
```

```c
NET_TIME_SEC_MAX
The largest positive number of seconds that can be safely represented by net_time_t.
```

```c
NET_TIME_SEC_MIN
The smallest negative number of seconds that can be safely represented by net_time_t.
```
**Typedefs**

typedef int64_t net_time_t

Any occurrence of net_time_t specifies a concept of nanosecond resolution scalar time span, future (positive) or past (negative) relative time or absolute timestamp referred to some local network uptime reference clock that does not wrap during uptime and is - in a certain, well-defined sense - common to all local network interfaces, sometimes even to remote interfaces on the same network.

This type is EXPERIMENTAL. Usage is currently restricted to representation of time within the network subsystem.

Timed network protocols (PTP, TDMA, ...) usually require several local or remote interfaces to share a common notion of elapsed time within well-defined tolerances. Network uptime therefore differs from time represented by a single hardware counter peripheral in that it will need to be represented in several distinct hardware peripherals with different frequencies, accuracy and precision. To co-operate, these hardware counters will have to be "syntonized" or "disciplined" (i.e. frequency and phase locked) with respect to a common local or remote network reference time signal. Be aware that while syntonized clocks share the same frequency and phase, they do not usually share the same epoch (zero-point).

This also explains why network time, if represented as a cycle value of some specific hardware counter, will never be “precise” but only can be “good enough” with respect to the tolerances (resolution, drift, jitter) required by a given network protocol. All counter peripherals involved in a timed network protocol must comply with these tolerances.

Please use specific cycle/tick counter values rather than net_time_t whenever possible especially when referring to the kernel system clock or values of any single counter peripheral.

net_time_t cannot represent general clocks referred to an arbitrary epoch as it only covers roughly +/- ~290 years. It also cannot be used to represent time according to a more complex timescale (e.g. including leap seconds, time adjustments, complex calendars or time zones). In these cases you may use timespec (C11, POSIX.1-2001), timeval (POSIX.1-2001) or broken down time as in tm (C90). The advantage of net_time_t over these structured time representations is lower memory footprint, faster and simpler scalar arithmetics and easier conversion from/to low-level hardware counter values. Also net_time_t can be used in the network stack as well as in applications while POSIX concepts cannot. Converting net_time_t from/to structured time representations is possible in a limited way but - except for timespec - requires concepts that must be implemented by higher-level APIs. Utility functions converting from/to timespec will be provided as part of the net_time_t API as and when needed.

If you want to represent more coarse grained scalar time in network applications, use time_t (C99, POSIX.1-2001) which is specified to represent seconds or suseconds_t (POSIX.1-2001) for microsecond resolution. Kernel k_ticks_t and cycles (both specific to Zephyr) have an unspecified resolution but are useful to represent kernel timer values and implement high resolution spinning.

If you need even finer grained time resolution, you may want to look at (g)PTP concepts, see net_ptp_extended_time.

The reason why we don’t use int64_t directly to represent scalar nanosecond resolution times in the network stack is that it has been shown in the past that fields using generic type will often not be used correctly (e.g. with the wrong resolution or to represent underspecified concepts of time with unclear syntonization semantics).
Any API that exposes or consumes net_time_t values SHALL ensure that it maintains the specified contract including all protocol specific tolerances and therefore clients can rely on common semantics of this type. This makes times coming from different hardware peripherals and even from different network nodes comparable within well-defined limits and therefore net_time_t is the ideal intermediate building block for timed network protocols.

### Precision Time Protocol (PTP) time format

- **Overview**
- **API Reference**

**Overview** The PTP time struct can store time information in high precision format (nanoseconds). The extended timestamp format can store the time in fractional nanoseconds accuracy. The PTP time format is used in *generic Precision Time Protocol (gPTP)* implementation.

**API Reference**

**Related code samples**

**gPTP**

Enable gPTP support and monitor functionality using net-shell.

**group ptp_time**

Precision Time Protocol time specification.

**Functions**

static inline net_time_t net_ptp_time_to_ns(struct net_ptp_time *ts)

Convert a PTP timestamp to a nanosecond precision timestamp, both related to the local network reference clock.

**Note:** Only timestamps representing up to ~290 years can be converted to nanosecond timestamps. Larger timestamps will return the maximum representable nanosecond precision timestamp.

**Parameters**

- ts – the PTP timestamp

**Returns**

the corresponding nanosecond precision timestamp

static inline struct net_ptp_time ns_to_net_ptp_time(net_time_t nsec)

Convert a nanosecond precision timestamp to a PTP timestamp, both related to the local network reference clock.

**Parameters**

- nsec – a nanosecond precision timestamp

**Returns**

the corresponding PTP timestamp
struct net_ptp_time

#include <ptp_time.h> (Generalized) Precision Time Protocol Timestamp format.

This structure represents a timestamp according to the Precision Time Protocol standard (“PTP”, IEEE 1588, section 5.3.3), the Generalized Precision Time Protocol standard (“gPTP”, IEEE 802.1AS, section 6.4.3.4), or any other well-defined context in which precision structured timestamps are required on network messages in Zephyr.

Seconds are encoded as a 48 bits unsigned integer. Nanoseconds are encoded as a 32 bits unsigned integer.

In the context of (g)PTP, timestamps designate the time, relative to a local clock (“LocalClock”) at which the message timestamp point passes a reference plane marking the boundary between the PTP Instance and the network medium (IEEE 1855, section 7.3.4.2; IEEE 802.1AS, section 8.4.3).

The exact definitions of the message timestamp point and reference plane depends on the network medium and use case.

For (g)PTP the media-specific message timestamp points and reference planes are defined in the standard. In non-PTP contexts specific to Zephyr, timestamps are measured relative to the same local clock but with a context-specific message timestamp point and reference plane, defined below per use case.

A “LocalClock” is a freerunning clock, embedded into a well-defined entity (e.g. a PTP Instance) and provides a common time to that entity relative to an arbitrary epoch (IEEE 1855, section 3.1.26, IEEE 802.1AS, section 3.16).

In Zephyr, the local clock is usually any instance of a kernel system clock driver, counter driver, RTC API driver or low-level counter/timer peripheral (e.g. an ethernet peripheral with hardware timestamp support or a radio timer) with sufficient precision for the context in which it is used.

See IEEE 802.1AS, Annex B for specific performance requirements regarding conformance of local clocks in the gPTP context. See IEEE 1588, Annex A, section A5.4 for general performance requirements regarding PTP local clocks. See IEEE 802.15.4-2020, section 15.7 for requirements in the context of ranging applications and ibid., section 6.7.6 for the relation between guard times and clock accuracy which again influence the precision required for subprotocols like CSL, TSCH, RIT, etc.

Applications that use timestamps across different subsystems or media must ensure that they understand the definition of the respective reference planes and interpret timestamps accordingly. Applications must further ensure that timestamps are either all referenced to the same local clock or convert between clocks based on sufficiently precise conversion algorithms.

Timestamps may be measured on ingress (RX timestamps) or egress (TX timestamps) of network messages. Timestamps can also be used to schedule a network message to a well-defined point in time in the future at which it is to be sent over the medium (timed TX). A future timestamp and a duration, both referenced to the local clock, may be given to specify a time window at which a network device should expect incoming messages (RX window).

In Zephyr this timestamp structure is currently used in the following contexts:

- gPTP for Full Duplex Point-to-Point IEEE 802.3 links (IEEE 802.1AS, section 11): the reference plane and message timestamp points are as defined in the standard.
- IEEE 802.15.4 timed TX and RX: Timestamps designate the point in time at which the end of the last symbol of the start-of-frame delimiter (SFD) (or equivalently, the start of the first symbol of the PHY header) is at the local antenna. The standard also refers to this as the “RMARKER” (IEEE 802.15.4-2020, section 6.9.1) or “symbol boundary” (ibid., section 6.5.2), depending on the context. In the context of beacon timestamps, the difference between the timestamp measurement plane and the...
reference plane is defined by the MAC PIB attribute “macSyncSymbolOffset”, ibid., section 8.4.3.1, table 8-94.

If further use cases are added to Zephyr using this timestamp structure, their clock performance requirements, message timestamp points and reference plane definition SHALL be added to the above list.

**Public Members**

```c
union net_ptp_time
  Seconds encoded on 48 bits.

uint32_t nanosecond
  Nanoseconds.
```

```c
struct net_ptp_extended_time

#include <ptp_time.h> Generalized Precision Time Protocol Extended Timestamp format.

This structure represents an extended timestamp according to the Generalized Precision Time Protocol standard (IEEE 802.1AS), see section 6.4.3.5.

Seconds are encoded as 48 bits unsigned integer. Fractional nanoseconds are encoded as 48 bits, their unit is 2*(-16) ns.

A precise definition of PTP timestamps and their uses in Zephyr is given in the description of net_ptp_time.

**Public Members**

```c
union net_ptp_extended_time
  Seconds encoded on 48 bits.

union net_ptp_extended_time
  Fractional nanoseconds on 48 bits.
```

**Generic GSM Modem**

**Overview**  The generic GSM modem driver allows the user to connect Zephyr to a GSM modem which provides a data connection to cellular operator’s network. The Zephyr uses PPP (Point-to-Point Protocol) to connect to the GSM modem using UART. Note that some cellular modems have proprietary offloading support using AT commands, but usually those modems also support 3GPP standards and provide PPP connection to them. See GSM modem sample application how to setup Zephyr to use the GSM modem.

The GSM muxing, that is defined in GSM 07.10, and which allows mixing of AT commands and PPP traffic, is also supported in this version of Zephyr. One needs to enable CONFIG_GSM_MUX and CONFIG_UART_MUX configuration options to enable muxing.

**zperf: Network Traffic Generator**
Overview  
zperf is a shell utility which allows to generate network traffic in Zephyr. The tool may be used to evaluate network bandwidth.

zperf is compatible with iPerf_2.0.5. Note that in newer iPerf versions, an error message like this is printed and the server reported statistics are missing.

LAST PACKET NOT RECEIVED!!!

zperf can be enabled in any application, a dedicated sample is also present in Zephyr. See zperf sample application for details.

Sample Usage  
If Zephyr acts as a client, iPerf must be executed in server mode. For example, the following command line must be used for UDP testing:

```
$ iperf -s -l 1K -u -V -B 2001:db8::2
```

For TCP testing, the command line would look like this:

```
$ iperf -s -l 1K -V -B 2001:db8::2
```

In the Zephyr console, zperf can be executed as follows:

```
zperf udp upload 2001:db8::2 5001 10 1K 1M
```

For TCP the zperf command would look like this:

```
zperf tcp upload 2001:db8::2 5001 10 1K 1M
```

If the IP addresses of Zephyr and the host machine are specified in the config file, zperf can be started as follows:

```
zperf udp upload2 v6 10 1K 1M
```

or like this if you want to test TCP:

```
zperf tcp upload2 v6 10 1K 1M
```

If Zephyr is acting as a server, set the download mode as follows for UDP:

```
zperf udp download 5001
```

or like this for TCP:

```
zperf tcp download 5001
```

and in the host side, iPerf must be executed with the following command line if you are testing UDP:

```
$ iperf -l 1K -u -V -c 2001:db8::1 -p 5001
```

and this if you are testing TCP:

```
$ iperf -l 1K -V -c 2001:db8::1 -p 5001
```

iPerf output can be limited by using the -b option if Zephyr is not able to receive all the packets in orderly manner.
6.3.7 Connection Manager

Overview

Connection Manager is a collection of optional Zephyr features that aim to allow applications to monitor and control connectivity (access to IP-capable networks) with minimal concern for the specifics of underlying network technologies.

Using Connection Manager, applications can use a single abstract API to control network association and monitor Internet access, and avoid excessive use of technology-specific boilerplate.

This allows an application to potentially support several very different connectivity technologies (for example, Wi-Fi and LTE) with a single codebase.

Applications can also use Connection Manager to generically manage and use multiple connectivity technologies simultaneously.

Structure  Connection Manager is split into the following two subsystems:

- **Connectivity monitoring** (header file include/zephyr/net/conn_mgr_monitoring.h) monitors all available Zephyr network interfaces (ifaces) and triggers network management events indicating when IP connectivity is gained or lost.

- **Connectivity control** (header file include/zephyr/net/conn_mgr_connectivity.h) provides an abstract API for controlling iface network association.

![Fig. 18: A simplified view of how Connection Manager integrates with Zephyr and the application. See here for a more detailed version.](image)

See here for a more detailed version.
Connectivity monitoring

Connectivity monitoring tracks all available ifaces (whether or not they support Connectivity control) as they transition through various operational states and acquire or lose assigned IP addresses.

Each available iface is considered ready if it meets the following criteria:

- The iface is admin-up
  - This means the iface has been instructed to become operational-up (ready for use). This is done by a call to `net_if_up()`.
- The iface is oper-up
  - This means the interface is completely ready for use; It is online, and if applicable, has associated with a network.
  - See Network interface state management for details.
- The iface has at least one assigned IP address
  - Both IPv4 and IPv6 addresses are acceptable. This condition is met as soon as one or both of these is assigned.
  - See Network Interface for details on iface IP assignment.
- The iface has not been ignored
  - Ignored ifaces are always treated as unready.
  - See Ignoring ifaces for more details.

Note: Typically, iface state and IP assignment are updated either by the iface's L2 implementation or bound connectivity implementation.

See Implement iface state reporting for details.

A ready iface ceases to be ready the moment any of the above conditions is lost.

When at least one iface is ready, the NET_EVENT_L4_CONNECTED network management event is triggered, and IP connectivity is said to be ready.

Afterwards, ifaces can become ready or unready without firing additional events, so long as there always remains at least one ready iface.

When there are no longer any ready ifaces left, the NET_EVENT_L4_DISCONNECTED network management event is triggered, and IP connectivity is said to be unready.

Usage Connectivity monitoring is enabled if the CONFIG_NET_CONNECTION_MANAGER Kconfig option is enabled.

To receive connectivity updates, create and register a listener for the NET_EVENT_L4_CONNECTED and NET_EVENT_L4_DISCONNECTED network management events:

```c
/* Callback struct where the callback will be stored */
struct net_mgmt_event_callback l4_callback;

/* Callback handler */
static void l4_event_handler(struct net_mgmt_event_callback *cb,
                             uint32_t event, struct net_if *iface)
{
    if (event == NET_EVENT_L4_CONNECTED) {
        LOG_INF("Network connectivity gained!");
    } else if (event == NET_EVENT_L4_DISCONNECTED) {
```

(continues on next page)
LOG_INF("Network connectivity lost!");
}

/* Otherwise, it's some other event type we didn't register for. */
}

/* Call this before Connection Manager monitoring initializes */
static void my_application_setup(void)
{
    /* Configure the callback struct to respond to (at least) the L4_CONNECTED
     * and L4_DISCONNECTED events.
     * *
     * Note that the callback may also be triggered for events other than those
     * specified here!
     * (See the net_mgmt documentation)
     */
    net_mgmt_init_event_callback(&l4_callback, l4_event_handler,
        NET_EVENT_L4_CONNECTED | NET_EVENT_L4_DISCONNECTED);

    /* Register the callback */
    net_mgmt_add_event_callback(&l4_callback);
}

See Listening to network events for more details on listening for net_mgmt events.

**Note:** To avoid missing initial connectivity events, you should register your listener(s) before Connection Manager monitoring initializes. See Avoiding missed notifications for strategies to ensure this.

**Avoiding missed notifications** Connectivity monitoring may trigger events immediately upon initialization.

If your application registers its event listeners after connectivity monitoring initializes, it is possible to miss this first wave of events, and not be informed the first time network connectivity is gained.

If this is a concern, your application should register its event listeners before connectivity monitoring initializes.

Connectivity monitoring initializes using the SYS_INIT APPLICATION initialization priority specified by the CONFIG_NET_CONNECTION_MANAGER_MONITOR_PRIORITY Kconfig option.

You can register your callbacks before this initialization by using SYS_INIT with an earlier initialization priority than this value, for instance priority 0:

```c
static int my_application_setup(void)
{
    /* Register callbacks here */
    return 0;
}

SYS_INIT(my_application_setup, APPLICATION, 0);
```

If this is not feasible, you can instead request that connectivity monitoring resend the latest connectivity events at any time by calling `conn_mg_mon_resend_status()`:

```c
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```
Ignoring ifaces  
Applications can request that ifaces be ignored by Connection Manager by calling `conn_mgr_ignore_iface()` with the iface to be ignored.

Alternatively, an entire L2 implementation can be ignored by calling `conn_mgr_ignore_l2()`.

This has the effect of individually ignoring all the ifaces using that L2 implementation.

While ignored, the iface is treated by Connection Manager as though it were unready for network traffic, no matter its actual state.

This may be useful, for instance, if your application has configured one or more ifaces that cannot (or for whatever reason should not) be used to contact the wider Internet.

*Bulk convenience functions* optionally skip ignored ifaces.

See `conn_mgr_ignore_iface()` and `conn_mgr_watch_iface()` for more details.

**Connectivity monitoring API** Include header file `include/zephyr/net/conn_mgr_monitoring.h` to access these.

*group* conn_mgr

Connection Manager API.

**Functions**

void *conn mgr_mon_resend_status*(void)

Resend either NET_L4_CONNECTED or NET_L4_DISCONNECTED depending on whether connectivity is currently available.

void *conn mgr_ignore_iface*(struct net if *iface)

Mark an iface to be ignored by conn_mgr.

Ignoring an iface forces conn_mgr to consider it unready/disconnected.

This means that events related to the iface connecting/disconnecting will not be fired, and if the iface was connected before being ignored, events will be fired as though it disconnected at that moment.

**Parameters**

- iface – iface to be ignored.

void *conn mgr_watch_iface*(struct net if *iface)

Watch (stop ignoring) an iface.

conn_mgr will no longer be forced to consider the iface unready/disconnected.

Events related to the iface connecting/disconnecting will no longer be blocked, and if the iface was connected before being watched, events will be fired as though it connected in that moment.

All ifaces default to watched at boot.
Parameters

• iface – iface to no longer ignore.

bool conn_mgr_is_iface_ignored(struct net_if *iface)
Check whether the provided iface is currently ignored.

Parameters

• iface – The iface to check.

Return values

• true – if the iface is being ignored by conn_mgr.
• false – if the iface is being watched by conn_mgr.

void conn_mgr_ignore_l2(const struct net_l2 *l2)
Mark an L2 to be ignored by conn_mgr.

This is a wrapper for conn_mgr_ignore_iface that ignores all ifaces that use the L2.

Parameters

• l2 – L2 to be ignored.

void conn_mgr_watch_l2(const struct net_l2 *l2)
Watch (stop ignoring) an L2.

This is a wrapper for conn_mgr_watch_iface that watches all ifaces that use the L2.

Parameters

• l2 – L2 to watch.

Connectivity control

Many network interfaces require a network association procedure to be completed before being usable.

For such ifaces, connectivity control can provide a generic API to request network association (conn_mgr_if_connect()) and disassociation (conn_mgr_if_disconnect()). Network interfaces implement support for this API by binding themselves to a connectivity implementation.

Using this API, applications can associate with networks with minimal technology-specific boilerplate.

Connectivity control also provides the following additional features:

• Standardized persistence and timeout behaviors during association.

• Bulk functions for controlling the admin state and network association of all available ifaces simultaneously.

• Optional convenience automations for common connectivity actions.

Basic operation The following sections outline the basic operation of Connection Manager’s connectivity control.

Binding Before an iface can be commanded to associate or disassociate using Connection Manager, it must first be bound to a connectivity implementation. Binding is performed by the provider of the iface, not by the application (see Binding an iface to an implementation), and can be thought of as an extension of the iface declaration.
Once an iface is bound, all connectivity commands passed to it (such as `conn mgr if connect()` or `conn mgr if disconnect()` will be routed to the corresponding implementation function in the connectivity implementation.

**Note:** To avoid inconsistent behavior, all connectivity implementations must adhere to the implementation guidelines.

**Connecting** Once a bound iface is admin-up (see Network interface state management), `conn mgr if connect()` can be called to cause it to associate with a network.

If association succeeds, the connectivity implementation will mark the iface as operational-up (see Network interface state management).

If association fails unrecoverably, the fatal error event will be triggered.

You can configure an optional timeout for this process.

**Note:** The `conn mgr if connect()` function is intentionally minimalistic, and does not take any kind of configuration. Each connectivity implementation should provide a way to pre-configure or automatically configure any required association settings or credentials. See Allow connectivity pre-configuration for details.

**Connection loss** If connectivity is lost due to external factors, the connectivity implementation will mark the iface as operational-down.

Depending on whether persistence is set, the iface may then attempt to reconnect.

**Manual disconnection** The application can also request that connectivity be intentionally abandoned by calling `conn mgr if disconnect()`.

In this case, the connectivity implementation will disassociate the iface from its network and mark the iface as operational-down (see Network interface state management). A new connection attempt will not be initiated, regardless of whether persistence is enabled.

**Timeouts and Persistence** Connection Manager requires that all connectivity implementations support the following standard key features:

- **Connection timeouts**
- **Connection persistence**

These features describe how ifaces should behave during connect and disconnect events. You can individually set them for each iface.

**Note:** It is left to connectivity implementations to successfully and accurately implement these two features as described below. See Implementing timeouts and persistence for more details from the connectivity implementation perspective.

**Connection Timeouts** When `conn mgr if connect()` is called on an iface, a connection attempt begins.

The connection attempt continues indefinitely until it succeeds, unless a timeout has been specified for the iface (using `conn mgr if set timeout()`).
In that case, the connection attempt will be abandoned if the timeout elapses before it succeeds. If this happens, the timeout event is raised.

**Connection Persistence** Each iface also has a connection persistence setting that you can enable or disable by setting the `CONN_MGR_IF_PERSISTENT` flag with `conn_mgr_binding_set_flag()`. This setting specifies how the iface should handle unintentional connection loss.

If persistence is enabled, any unintentional connection loss will initiate a new connection attempt, with a new timeout if applicable.

Otherwise, the iface will not attempt to reconnect.

**Note:** Persistence not does affect connection attempt behavior. Only the timeout setting affects this.

For instance, if a connection attempt on an iface times out, the iface will not attempt to reconnect, even if it is persistent.

Conversely, if there is not a specified timeout, the iface will try to connect forever until it succeeds, even if it is not persistent.

See *Persistence during connection attempts* for the equivalent implementation guideline.

**Control events** Connectivity control triggers network management events to inform the application of important state changes.

See *Trigger connectivity control events* for the corresponding connectivity implementation guideline.

**Fatal Error** The `NET_EVENT_CONN_IF_FATAL_ERROR` event is raised when an iface encounters an error from which it cannot recover (meaning any subsequent attempts to associate are guaranteed to fail, and all such attempts should be abandoned).

Handlers of this event will be passed a pointer to the iface for which the fatal error occurred. Individual connectivity implementations may also pass an application-specific data pointer.

**Timeout** The `NET_EVENT_CONN_IF_TIMEOUT` event is raised when an iface association attempt times out.

Handlers of this event will be passed a pointer to the iface that timed out attempting to associate.

**Listening for control events** You can listen for control events as follows:

```c
/* Declare a net_mgmt callback struct to store the callback */
struct net_mgmt_event_callback
    my_conn_evt_callback;

/* Declare a handler to receive control events */
static void
    my_conn_evt_handler(struct net_mgmt_event_callback *cb,
        uint32_t event, struct net_if *iface)
{
    if (event == NET_EVENT_CONN_IF_TIMEOUT) {
        /* Timeout occurred, handle it */
    } else if (event == NET_EVENT_CONN_IF_FATAL_ERROR) {
        /* Fatal error occurred, handle it */
    }
}
```

(continues on next page)
int main()
{
    /* Configure the callback struct to respond to (at least) the CONN_IF_TIMEOUT * and CONN_IF_FATAL_ERROR events.
     * Note that the callback may also be triggered for events other than those specified here!
     * (See the net_mgmt documentation)
    */
    net_mgmt_init_event_callback(
        &conn_mgr_conn_callback,
        conn_mgr_conn_handler,
        NET_EVENT_CONN_IF_TIMEOUT | NET_EVENT_CONN_IF_FATAL_ERROR
    );
    /* Register the callback */
    net_mgmt_add_event_callback(&conn_mgr_conn_callback);
    return 0;
}

See Listening to network events for more details on listening for net_mgmt events.

**Automated behaviors**  There are a few actions related to connectivity that are (by default at least) performed automatically for the user.

**Automatic admin-up**

In Zephyr, ifaces are automatically taken admin-up (see Network interface state management for details on iface states) during initialization.

Applications can disable this behavior by setting the NET_IF_NO_AUTO_START interface flag with net_if_flag_set().

**Automatic connect**

By default, Connection Manager will automatically connect any bound iface that becomes admin-up.

Applications can disable this by setting the CONN_MGR_IF_NO_AUTO_CONNECT connectivity flag with conn_mgr_if_set_flag().

**Automatic admin-down**

By default, Connection Manager will automatically take any bound iface admin-down if it has given up on associating.

Applications can disable this for all ifaces by disabling the CONFIG_NET_CONNECTION_MANAGER_AUTO_IF_DOWN Kconfig option, or for individual ifaces by setting the CONN_MGR_IF_NO_AUTO_DOWN connectivity flag with conn_mgr_if_set_flag().

---

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Connectivity control API Include header file include/zephyr/net/conn mgr_connectivity.h to access these.

group conn mgr_connectivity
  Connection Manager Connectivity API.

Defines

NET_EVENT_CONN_IF_TIMEOUT
  net_mgmt event raised when a connection attempt times out

NET_EVENT_CONN_IF_FATAL_ERROR
  net_mgmt event raised when a non-recoverable connectivity error occurs on an iface

CONN_MGR_IF_NO_TIMEOUT
  Value to use with conn_mgr_if_set_timeout and conn_mgr_conn_binding::timeout to indicate no timeout.

Enums

enum net_event_conn_cmd
  Values:

  enumerator NET_EVENT_CONN_CMD_IF_TIMEOUT = 1

enumerator NET_EVENT_CONN_CMD_IF_FATAL_ERROR

enum conn mgr_if_flag
  Per-iface connectivity flags. Values:

  enumerator CONN_MGR_IF_PERSISTENT
    Persistent.
    When set, indicates that the connectivity implementation bound to this iface should attempt to persist connectivity by automatically reconnecting after connection loss.

  enumerator CONN_MGR_IF_NO_AUTO_CONNECT
    No auto-connect.
    When set, conn mgr will not automatically attempt to connect this iface when it reaches admin-up.

  enumerator CONN_MGR_IF_NO_AUTO_DOWN
    No auto-down.
    When set, conn mgr will not automatically take the iface admin-down when it stops trying to connect, even if CONFIG_NET_CONNECTION_MANAGER_AUTO_IF_DOWN is enabled.
Functions

int conn_mgr_if_connect(struct net_if *iface)
Connect interface.
If the provided iface has been bound to a connectivity implementation, initiate network connect/association.
Automatically takes the iface admin-up (by calling net_if_up) if it isn’t already.
Non-Blocking.

Parameters
• iface – Pointer to network interface

Return values
• 0 – on success.
• -ESHUTDOWN – if the iface is not admin-up.
• -ENOTSUP – if the iface does not have a connectivity implementation.
• implementation-specific – status code otherwise.

int conn_mgr_if_disconnect(struct net_if *iface)
Disconnect interface.
If the provided iface has been bound to a connectivity implementation, disconnect/dissociate it from the network, and cancel any pending attempts to connect/associate.
Does nothing if the iface is currently admin-down.

Parameters
• iface – Pointer to network interface

Return values
• 0 – on success.
• -ENOTSUP – if the iface does not have a connectivity implementation.
• implementation-specific – status code otherwise.

bool conn mgr_if_is_bound (struct net_if *iface)
Check whether the provided network interface supports connectivity / has been bound to a connectivity implementation.

Parameters
• iface – Pointer to the iface to check.

Return values
• true – if connectivity is supported (a connectivity implementation has been bound).
• false – otherwise.

int conn_mgr_if_set_opt(struct net_if *iface, int optname, const void *optval, size_t optlen)
Set implementation-specific connectivity options.
If the provided iface has been bound to a connectivity implementation that supports it, implementation-specific connectivity options related to the iface.

Parameters
• **iface** – Pointer to the network interface.
• **optname** – Integer value representing the option to set. The meaning of values is up to the `conn_mgr_conn_api` implementation. Some settings may affect multiple ifaces.
• **optval** – Pointer to the value to be assigned to the option.
• **optlen** – Length (in bytes) of the value to be assigned to the option.

**Return values**

• **0** – if successful.
• **-ENOTSUP** – if `conn_mgr_if_set_opt` not implemented by the iface.
• **-ENOBUFS** – if `optlen` is too long.
• **-EINVAL** – if NULL `optval` pointer provided.
• **-ENOPROTOOPT** – if the optname is not recognized.
• **implementation-specific** – error code otherwise.

```c
int conn_mgr_if_set_opt(struct net_if *iface, int optname, void *optval, size_t *optlen)
```

Get implementation-specific connectivity options.

If the provided iface has been bound to a connectivity implementation that supports it, retrieves implementation-specific connectivity options related to the iface.

`optlen` will always be set to the total number of bytes written, regardless of whether an error is returned, even if zero bytes were written.

**Parameters**

• **iface** – Pointer to the network interface.
• **optname** – Integer value representing the option to set. The meaning of values is up to the `conn_mgr_conn_api` implementation. Some settings may be shared by multiple ifaces.
• **optval** – Pointer to where the retrieved value should be stored.
• **optlen** – Pointer to length (in bytes) of the destination buffer available for storing the retrieved value. If the available space is less than what is needed, -ENOBUFS is returned. If the available space is invalid, -EINVAL is returned.

**Return values**

• **0** – if successful.
• **-ENOTSUP** – if `conn_mgr_if_set_opt` is not implemented by the iface.
• **-ENOBUFS** – if retrieval buffer is too small.
• **-EINVAL** – if invalid retrieval buffer length is provided, or if NULL `optval` or `optlen` pointer provided.
• **-ENOPROTOOPT** – if the optname is not recognized.
• **implementation-specific** – error code otherwise.

```c
bool conn_mgr_if_get_flag(struct net_if *iface, enum conn_mgr_if_flag flag)
```

Check the value of connectivity flags.

If the provided iface is bound to a connectivity implementation, retrieves the value of the specified connectivity flag associated with that iface.

**Parameters**
• iface -- Pointer to the network interface to check.
• flag -- The flag to check.

Returns
True if the flag is set, otherwise False. Also returns False if the provided iface is not bound to a connectivity implementation, or the requested flag doesn't exist.

int conn_mgr_if_set_flag(struct net_if *iface, enum conn_mgr_if_flag flag, bool value)
Set the value of a connectivity flags.
If the provided iface is bound to a connectivity implementation, sets the value of the specified connectivity flag associated with that iface.

Parameters
• iface -- Pointer to the network interface to modify.
• flag -- The flag to set.
• value -- Whether the flag should be enabled or disabled.

Return values
• 0 -- on success.
• -EINVAL -- if the flag does not exist.
• -ENOTSUP -- if the provided iface is not bound to a connectivity implementation.

int conn_mgr_if_get_timeout(struct net_if *iface)
Get the connectivity timeout for an iface.
If the provided iface is bound to a connectivity implementation, retrieves the timeout setting in seconds for it.

Parameters
• iface -- Pointer to the iface to check.

Returns
int - The connectivity timeout value (in seconds) if it could be retrieved, otherwise CONN_MGR_IF_NO_TIMEOUT.

int conn_mgr_if_set_timeout(struct net_if *iface, int timeout)
Set the connectivity timeout for an iface.
If the provided iface is bound to a connectivity implementation, sets the timeout setting in seconds for it.

Parameters
• iface -- Pointer to the network interface to modify.
• timeout -- The timeout value to set (in seconds). Pass CONN_MGR_IF_NO_TIMEOUT to disable the timeout.

Return values
• 0 -- on success.
• -ENOTSUP -- if the provided iface is not bound to a connectivity implementation.
**Bulk API** Connectivity control provides several bulk functions allowing all ifaces to be controlled at once.

You can restrict these functions to operate only on non-ignored ifaces if desired.

Include header file `include/zephyr/net/conn_mgr_connectivity.h` to access these.

**group** conn_mgr_connectivity_bulk

Connection Manager Bulk API.

**Functions**

```c
int conn_mgr_all_if_up(bool skip_ignored)
Convenience function that takes all available ifaces into the admin-up state.
Essentially a wrapper for `net_if_up`.

**Parameters**
- **skip_ignored** – If true, only affect ifaces that aren't ignored by conn mgr. Otherwise, affect all ifaces.

**Returns**
0 if all net_if_up calls returned 0, otherwise the first nonzero value returned by a net_if_up call.
```

```c
int conn_mgr_all_if_down(bool skip_ignored)
Convenience function that takes all available ifaces into the admin-down state.
Essentially a wrapper for `net_if_down`.

**Parameters**
- **skip_ignored** – If true, only affect ifaces that aren't ignored by conn mgr. Otherwise, affect all ifaces.

**Returns**
0 if all net_if_down calls returned 0, otherwise the first nonzero value returned by a net_if_down call.
```

```c
int conn_mgr_all_if_connect(bool skip_ignored)
Convenience function that takes all available ifaces into the admin-up state, and connects those that support connectivity.
Essentially a wrapper for `net_if_up` and `conn_mgr_if_connect`.

**Parameters**
- **skip_ignored** – If true, only affect ifaces that aren't ignored by conn mgr. Otherwise, affect all ifaces.

**Returns**
0 if all net_if_up and conn_mgr_if_connect calls returned 0, otherwise the first nonzero value returned by either net_if_up or conn_mgr_if_connect.
```

```c
int conn_mgr_all_if_disconnect(bool skip_ignored)
Convenience function that disconnects all available ifaces that support connectivity without putting them into admin-down state (unless auto-down is enabled for the iface).
Essentially a wrapper for `net_if_down`.

**Parameters**
- **skip_ignored** – If true, only affect ifaces that aren't ignored by conn mgr. Otherwise, affect all ifaces.
```
Returns
0 if all net_if_up and conn_mngr_if_connect calls returned 0, otherwise the first nonzero value returned by either net_if_up or conn_mngr_if_connect.

Connectivity Implementations

Overview Connectivity implementations are technology-specific modules that allow specific Zephyr ifaces to support Connectivity Control. They are responsible for translating generic connectivity control API calls into hardware-specific operations. They are also responsible for implementing standardized persistence and timeout behaviors.

See the implementation guidelines for details on writing conformant connectivity implementations.

Architecture The implementation API allows connectivity implementations to be defined at build time using CONN_MGR_CONN_DEFINE.

This creates a static instance of the conn_mngr_conn_impl struct, which then stores a reference to the passed in conn_mngr_conn_api struct (which should be populated with implementation callbacks).

Once defined, you can reference implementations by name and bind them to any unbound iface using CONN_MGR_BIND_CONN. Make sure not to accidentally bind two connectivity implementations to a single iface.

Once the iface is bound, connectivity control API functions can be called on the iface, and they will be translated to the corresponding implementation functions in conn_mngr_conn_api.

Binding an iface does not directly modify its iface struct.

Instead, an instance of conn_mngr_conn_binding is created and appended an internal iterable section.

This binding structure will contain a reference to the bound iface, the connectivity implementation it is bound to, as well as a pointer to a per-iface context pointer.

This iterable section can then be iterated over to find out what (if any) connectivity implementation has been bound to a given iface. This search process is used by most of the functions in the connectivity control API. As such, these functions should be called sparingly, due to their relatively high search cost.

A single connectivity implementation may be bound to multiple ifaces. See Do not instance implementations for more details.

Context Pointer Since a single connectivity implementation may be shared by several Zephyr ifaces, each binding instantiates a context container (of configurable type) unique to that binding. Each binding is then instantiated with a reference to that container, which implementations can then use to access per-iface state information.

See also Do not access bindings without locking them and Do not instance implementations.

Defining an implementation A connectivity implementation may be defined as follows:

```c
/* Create the API implementation functions */
int my_connect_impl(struct conn_mngr_conn_binding *const binding) {
    /* Cause your underlying technology to associate */
}
int my_disconnect_impl(struct conn_mngr_conn_binding *const binding) {
    /* Cause your underlying technology to disassociate */
}
```
Fig. 19: A detailed view of how Connection Manager integrates with Zephyr and the application. See here for a simplified version.
void my_init_impl(struct conn_mgr_conn_binding *const binding) {
    /* Perform any required initialization for your underlying technology */
}

/* Declare the API struct */
static struct conn_mgr_conn_api my_impl_api = {
    .connect = my_connect_impl,
    .disconnect = my_disconnect_impl,
    .init = my_init_impl,
    /* ... so on */
};

/* Define the implementation (named MY_CONNECTIVITY_IMPL) */
CONN_MGR_CONN_DEFINE(MY_CONNECTIVITY_IMPL, &my_impl_api);

---

**Note:** This does not work unless you also declare the context pointer type.

---

### Declaring an implementation publicly
Once defined, you can make a connectivity implementation available to other compilation units by declaring it (in a header file) as follows:

**Listing 4: my_connectivity_header.h**

```
CONN_MGR_CONN_DECLARE_PUBLIC(MY_CONNECTIVITY_IMPL);
```

The header file that contains this declaration must be included in any compilation units that need to reference the implementation.

### Declaring a context type
For `CONN_MGR_CONN_DEFINE` to work, you must declare a corresponding context pointer type. This is because all connectivity bindings contain a *Context Pointer* of their associated context pointer type.

If you are using `CONN_MGR_CONN_DECLARE_PUBLIC`, declare this type alongside the declaration:

**Listing 5: my_connectivity_impl.h**

```
#define MY_CONNECTIVITY_IMPL_CTX_TYPE struct my_context_type *
CONN_MGR_CONN_DECLARE_PUBLIC(MY_CONNECTIVITY_IMPL);
```

Then, make sure to include the header file before calling `CONN_MGR_CONN_DEFINE`:

**Listing 6: my_connectivity_impl.c**

```
#include "my_connectivity_impl.h"
CONN_MGR_CONN_DEFINE(MY_CONNECTIVITY_IMPL, &my_impl_api);
```

Otherwise, it is sufficient to simply declare the context pointer type immediately before the call to `CONN_MGR_CONN_DEFINE`:

```
#define MY_CONNECTIVITY_IMPL_CTX_TYPE struct my_context_type *
CONN_MGR_CONN_DEFINE(MY_CONNECTIVITY_IMPL, &my_impl_api);
```

**Note:** Naming is important. Your context pointer type declaration must use the same name as your implementation declaration, but with _CTX_TYPE appended.
In the previous example, the context type is named `MY_CONNECTIVITY_IMPL_CTX_TYPE`, because `MY_CONNECTIVITY_IMPL` was used as the connectivity implementation name.

If your connectivity implementation does not need a context pointer, simply declare the type as:

```c
#define MY_CONNECTIVITY_IMPL_CTX_TYPE void *
```

### Binding an iface to an implementation

A defined connectivity implementation may be bound to an iface by calling `CONN_MGR_BIND_CONN` anywhere after the iface’s device definition:

```c
/* Define an iface */
NET_DEVICE_INIT(my_iface,
   /* ... the specifics here don't matter ... */
);

/* Now bind MY_CONNECTIVITY_IMPL to that iface --
   * the name used should match with the above
   */
CONN_MGR_BIND_CONN(my_iface, MY_CONNECTIVITY_IMPL);
```

### Connectivity implementation guidelines

Rather than implement all features centrally, Connection Manager relies on each connectivity implementation to implement many behaviors and features individually.

This approach allows Connection Manager to remain lean, and allows each connectivity implementation to choose the most appropriate approach to these behaviors for itself. However, it relies on trust that all connectivity implementations will faithfully implement the features that have been delegated to them.

To maintain consistency between all connectivity implementations, observe the following guidelines when writing your own implementation:

**Completely implement timeout and persistence**  All connectivity implementations must offer complete support for `timeout and persistence`, such that a user can disable or enable these features, regardless of the inherent behavior of the underlying technology. In other words, no matter how the underlying technology behaves, your implementation must make it appear to the end user to behave exactly as specified in the `Timeouts and Persistence` section.

See [Implementing timeouts and persistence](#) for a detailed technical discussion on implementing timeouts and persistence.

**Conform to API specifications**  Each implementation API function you implement should behave as-described in the corresponding connectivity control API function.

For example, your implementation of `conn_mgr_conn_api.connect` should conform to the behavior described for `conn_mgr_if_connect()`.

**Allow connectivity pre-configuration**  Connectivity implementations should provide means for applications to pre-Configure all necessary connection parameters (for example, network SSID, or PSK, if applicable), before the call to `conn_mgr_if_connect()`. It should not be necessary to provide this information as part of, or following the `conn_mgr_if_connect()` call, although implementations should await this information if it is not provided.
Await valid connectivity configuration  If network association fails because the application pre-configured invalid connection parameters, or did not configure connection parameters at all, this should be treated as a network failure.

In other words, the connectivity implementation should not give up on the connection attempt, even if valid connection parameters have not been configured.

Instead, the connectivity implementation should asynchronously wait for valid connection parameters to be configured, either indefinitely, or until the configured connectivity timeout elapses.

Implement iface state reporting  All connectivity implementations must keep bound iface state up to date.

To be specific:

- Set the iface to dormant, carrier-down, or both during binding init.
  - See Network interface state management for details regarding iface carrier and dormant states.

- Update dormancy and carrier state so that the iface is non-dormant and carrier-up whenever (and only when) association is complete and connectivity is ready.

- Set the iface either to dormant or to carrier-down as soon as interruption of service is detected.
  - It is acceptable to gate this behind a small timeout (separate from the connection timeout) for network technologies where service is commonly intermittent.

- If the technology also handles IP assignment, ensure those IP addresses are assigned to the iface.

Note: iface state updates do not necessarily need to be performed directly by connectivity implementations.

For instance:

- IP assignment is not necessary if DHCP is used for the iface.

- The connectivity implementation does not need to update iface dormancy if the underlying L2 implementation already does so.

Do not use iface state as implementation state  Zephyr ifaces may be accessed from other threads without respecting the binding mutex. As such, Zephyr iface state may change unpredictably during connectivity implementation callbacks.

Therefore, do not base implementation behaviors on iface state.

Keep iface state updated to reflect network availability, but do not read iface state for any purpose.

If you need to keep track of dormancy or IP assignment, use a separate state variable stored in the context pointer.

Remain non-interferent  Connectivity implementations should not prevent applications from interacting directly with associated technology-specific APIs.

In other words, it should be possible for an application to directly use your underlying technology without breaking your connectivity implementation.
If exceptions to this are absolutely necessary, they should be constrained to specific API calls and should be documented.

**Note:** While connectivity implementations must not break, it is acceptable for implementations to have potentially unexpected behavior if applications attempt to directly control the association state.

For instance, if an application directly instructs an underlying technology to disassociate, it would be acceptable for the connectivity implementation to interpret this as an unexpected connection loss and immediately attempt to re-associate.

**Remain non-blocking** All connectivity implementation callbacks should be non-blocking.

For instance, calls to `conn_mgr_conn_api.connect` should initiate a connection process and return immediately.

One exception is `conn_mgr_conn_api.init`, whose implementations are permitted to block.

However, bear in mind that blocking during this callback will delay system init, so still consider offloading time-consuming tasks to a background thread.

**Make API immediately ready** Connectivity implementations must be ready to receive API calls immediately after `conn_mgr_conn_api.init`.

For instance, a call to `conn_mgr_conn_api.connect` must eventually lead to an association attempt, even if called immediately after `conn_mgr_conn_api.init`.

If the underlying technology cannot be made ready for connect commands immediately when `conn_mgr_conn_api.init` is called, calls to `conn_mgr_conn_api.connect` must be queued in a non-blocking fashion, and then executed later when ready.

**Do not store state information outside the context pointer** Connection Manager provides a context pointer to each binding.

Connectivity implementations should store all state information in this context pointer.

The only exception is connectivity implementations that are meant to be bound to only a single iface. Such implementations may use statically declared state instead.

See also **Do not instance implementations**.

**Access ifaces only through binding structs** Do not use statically declared ifaces or externally acquire references to ifaces.

For example, do not use `net_if_get_default()` under the assumption that the bound iface will be the default iface.

Instead, always use the `iface pointer` provided by the relevant `binding struct`. See also **Do not access bindings without locking them**.

**Make implementations optional at compile-time** Connectivity implementations should provide a Kconfig option to enable or disable the implementation without affecting bound iface availability.

In other words, it should be possible to configure builds that include Connectivity Manager, as well as the iface that would have been bound to the implementation, but not the implementation itself, nor its binding.
Do not instance implementations  Do not declare a separate connectivity implementation for every iface you are going to bind to.

Instead, bind one global connectivity implementation to all of your ifaces, and use the context pointer to store state relevant to individual ifaces.

See also Do not access bindings without locking them and Access ifaces only through binding structs.

Do not access bindings without locking them  Bindings may be accessed and modified at random by multiple threads, so modifying or reading from a binding without first locking it may lead to unpredictable behavior.

This applies to all descendents of the binding, including anything in the context container.

Make sure to unlock the binding when you are done accessing it.

Note:  A possible exception to this rule is if the resource in question is inherently thread-safe.

However, be careful taking advantage of this exception. It may still be possible to create a race condition, for instance when accessing multiple thread-safe resources simultaneously.

Therefore, it is recommended to simply always lock the binding, whether or not the resource being accessed is inherently thread-safe.

Do not disable built-in features  Do not attempt to prevent the use of built-in features (such as Timeouts and Persistence or Automated behaviors).

All connectivity implementations must fully support these features. Implementations must not attempt to force certain features to be always enabled or always disabled.

Trigger connectivity control events  Connectivity control network management events are not triggered automatically by Connection Manager.

Connectivity implementations must trigger these events themselves.

Trigger NET_EVENT_CONN_CMD_IF_TIMEOUT when a connection timeout occurs. See Timeout for details.

Trigger NET_EVENT_CONN_IF_FATAL_ERROR when a fatal (non-recoverable) connection error occurs. See Fatal Error for details.

See Network Management for details on firing network management events.

Implementing timeouts and persistence  First, see Timeouts and Persistence for a high-level description of the expected behavior of timeouts and persistence.

Connectivity implementations must fully conform to that description, regardless of the behavior of the underlying connectivity technology.

Sometimes this means writing extra logic in the connectivity implementation to fake certain behaviors. The following sections discuss various common edge-cases and nuances and how to handle them.
Inherently persistent technologies  If the underlying technology automatically attempts to reconnect or retry connection after connection loss or failure, the connectivity implementation must manually cancel such attempts when they are in conflict with timeout or persistence settings.

For example:

- If the underlying technology automatically attempts to reconnect after losing connection, and persistence is disabled for the iface, the connectivity implementation should immediately cancel this reconnection attempt.
- If a connection attempt times out on an iface whose underlying technology does not have a built-in timeout, the connectivity implementation must simulate a timeout by cancelling the connection attempt manually.

Technologies that give up on connection attempts  If the underlying technology has no mechanism to retry connection attempts, or would give up on them before the user-configured timeout, or would not reconnect after connection loss, the connectivity implementation must manually re-request connection to counteract these deviances.

- If your underlying technology is not persistent, you must manually trigger reconnect attempts when persistence is enabled.
- If your underlying technology does not support a timeout, you must manually cancel connection attempts if the timeout is enabled.
- If your underlying technology forces a timeout, you must manually trigger a new connection attempts if that timeout is shorter than the Connection Manager timeout.

Technologies with association retry  Many underlying technologies do not usually associate in a single attempt.

Instead, these underlying technologies may need to make multiple back-to-back association attempts in a row, usually with a small delay.

In these situations, the connectivity implementation should treat this series of back-to-back association sub-attempts as a single unified connection attempt.

For instance, after a sub-attempt failure, persistence being disabled should not prevent further sub-attempts, since they all count as one single overall connection attempt. See also Persistence during connection attempts.

At which point a series of failed sub-attempts should be considered a failure of the connection attempt as a whole is up to each implementation to decide.

If the connection attempt crosses this threshold, but the configured timeout has not yet elapsed, or there is no timeout, sub-attempts should continue.

Persistence during connection attempts  Persistence should not affect any aspect of implementation behavior during a connection attempt. Persistence should only affect whether or not connection attempts are automatically triggered after a connection loss.

The configured timeout should fully determine whether connection retry should be performed.

Implementation API  Include header file include/zephyr/net/conn_mgr_connectivity_impl.h to access these.

Only for use by connectivity implementations.

\[ \text{group conn_mgr_connectivity_impl} \]

Connection Manager Connectivity Implementation API.
Defines

CON_MGR_CONN_DEFINE(conn_id, conn_api)
Define a conn_mgr connectivity implementation that can be bound to network devices.

Parameters
- conn_id – The name of the new connectivity implementation
- conn_api – A pointer to a conn_mgr_conn_api struct

CON_MGR_CONN_DECLARE_PUBLIC(conn_id)
Helper macro to make a conn_mgr connectivity implementation publicly available.

CON_MGR_BIND_CONN_INST(dev_id, inst, conn_id)
Associate a connectivity implementation with an existing network device instance.

Parameters
- dev_id – Network device id.
- inst – Network device instance.
- conn_id – Name of the connectivity implementation to associate.

CON_MGR_BIND_CONN(dev_id, conn_id)
Associate a connectivity implementation with an existing network device.

Parameters
- dev_id – Network device id.
- conn_id – Name of the connectivity implementation to associate.

Functions

static inline struct conn_mgr_conn_binding *conn_mgr_if_get_binding(struct net_if *iface)
Retrieves the conn_mgr binding struct for a provided iface if it exists.
Bindings for connectivity implementations with missing API structs are ignored.
For use only by connectivity implementations.

Parameters
- iface -- bound network interface to obtain the binding struct for.

Returns
struct conn_mgr_conn_binding* Pointer to the retrieved binding struct if it exists, NULL otherwise.

static inline void conn_mgr_binding_lock(struct conn_mgr_conn_binding *binding)
Lock the passed-in binding, making it safe to access.
Call this whenever accessing binding data, unless inside a conn_mgr_conn_api callback, where it is called automatically by conn_mgr.
Reentrant.
For use only by connectivity implementations.

Parameters
- binding -- Binding to lock
static inline void conn_mgr_binding_unlock(struct conn_mgr_conn_binding *binding)
Unlocks the passed-in binding.
Call this after any call to conn_mgr_binding_lock once done accessing binding data.
Reentrant.
For use only by connectivity implementations.

Parameters
• binding -- Binding to unlock

static inline void conn_mgr_binding_set_flag(struct conn_mgr_conn_binding *binding, enum conn_mgr_if_flag flag, bool value)
Set the value of the specified connectivity flag for the provided binding.
Can be used from any thread or callback without calling conn_mgr_binding_lock.
For use only by connectivity implementations

Parameters
• binding -- The binding to check
• flag -- The flag to check
• value -- New value for the specified flag

static inline bool conn_mgr_binding_get_flag(struct conn_mgr_conn_binding *binding, enum conn_mgr_if_flag flag)
Check the value of the specified connectivity flag for the provided binding.
Can be used from any thread or callback without calling conn_mgr_binding_lock.
For use only by connectivity implementations

Parameters
• binding -- The binding to check
• flag -- The flag to check

Returns
bool The value of the specified flag

struct conn_mgr_conn_api
#include <conn_mgr_connectivity_impl.h> Connectivity Manager Connectivity API structure.
Used to provide generic access to network association parameters and procedures

Public Members

int (*connect)(struct conn_mgr_conn_binding *const binding)
When called, the connectivity implementation should start attempting to establish
connectivity (association with a network) for the bound iface pointed to by if_conn-
>iface.
Must be non-blocking.
Called by conn_mgr_if_connect.
int (*disconnect)(struct conn_mgr_conn_binding *const binding)
    When called, the connectivity implementation should disconnect (dissasociate), or
    stop any in-progress attempts to associate to a network, the bound iface pointed to
    by if_conn->iface.
    Must be non-blocking.
    Called by conn_mgr_if_disconnect.

void (*init)(struct conn_mgr_conn_binding *const binding)
    Called once for each iface that has been bound to a connectivity implementation
    using this API.
    Connectivity implementations should use this callback to perform any required
    per-bound-iface initialization.
    Implementations may choose to gracefully handle invalid buffer lengths with par-
    tial writes, rather than raise errors, if deemed appropriate.

int (*set_opt)(struct conn_mgr_conn_binding *const binding, int optname, const void *
    optval, size_t *optlen)
    Implementation callback for conn_mgr_if_set_opt.
    Used to set implementation-specific connectivity settings.
    Calls to conn_mgr_if_set_opt on an iface will result in calls to this callback with the
    conn_mgr_conn_binding struct bound to that iface.
    It is up to the connectivity implementation to interpret optname. Options can be
    specific to the bound iface (pointed to by if_conn->iface), or can apply to the whole
    connectivity implementation.
    See the description of conn_mgr_if_set_opt for more details. set_opt implementa-
    tions should conform to that description.
    Implementations may choose to gracefully handle invalid buffer lengths with par-
    tial reads, rather than raise errors, if deemed appropriate.

int (*get_opt)(struct conn_mgr_conn_binding *const binding, int optname, void *
    optval, size_t *optlen)
    Implementation callback for conn_mgr_if_set_opt.
    Used to retrieve implementation-specific connectivity settings.
    Calls to conn_mgr_if_set_opt on an iface will result in calls to this callback with the
    conn_mgr_conn_binding struct bound to that iface.
    It is up to the connectivity implementation to interpret optname. Options can be
    specific to the bound iface (pointed to by if_conn->iface), or can apply to the whole
    connectivity implementation.
    See the description of conn_mgr_if_set_opt for more details. get_opt implementa-
    tions should conform to that description.

struct conn_mgr_conn_impl
    #include <conn_mgr_connectivity_impl.h> Connectivity Implementation struct.
    Declares a conn_mgr connectivity layer implementation with the provided API

Public Members
struct conn_mgr_conn_api *api
  The connectivity API used by the implementation.

struct conn_mgr_conn_binding
#include <conn mgr_connectivity_impl.h> Connectivity Manager network interface
binding structure.
  Binds a conn_mgr connectivity implementation to an iface / network device. Stores
per-iface state for the connectivity implementation.

Generic connectivity state

uint32_t flags
  Connectivity flags.
  Public boolean state and configuration values supported by all bindings. See
conn_mgr_if_flag for options.

int timeout
  Timeout (seconds)
  Indicates to the connectivity implementation how long it should attempt to estab-
lish connectivity for during a connection attempt before giving up.
  The connectivity implementation should give up on establishing connectivity after
this timeout, even if persistence is enabled.
  Set to CONN_MGR_IF_NO_TIMEOUT to indicate that no timeout should be used.

Public Members

struct net_if *iface
  The network interface the connectivity implementation is bound to.

const struct conn_mgr_conn_impl *impl
  The connectivity implementation the network device is bound to.

void *ctx
  Pointer to private, per-iface connectivity context.

6.4 LoRa and LoRaWAN

6.4.1 Overview

LoRa (abbrev. for Long Range) is a proprietary low-power wireless communication protocol
developed by the Semtech Corporation.
LoRa acts as the physical layer (PHY) based on the chirp spread spectrum (CSS) modulation tech-
nique.
LoRaWAN (for Long Range Wide Area Network) defines a networking layer on top of the LoRa
PHY.
Zephyr provides APIs for LoRa to send raw data packets directly over the wireless interface as well as APIs for LoRaWAN to connect the end device to the internet through a gateway.

The Zephyr implementation is based on Semtech's LoRaMac-node library, which is included as a Zephyr module.

The LoRaWAN specification is published by the LoRa Alliance.

### 6.4.2 Configuration Options

**LoRa PHY**

Related configuration options can be found under `drivers/lora/Kconfig`.

- `CONFIG_LORA`
- `CONFIG_LORA_SHELL`
- `CONFIG_LORA_INIT_PRIORITY`

**LoRaWAN**

Related configuration options can be found under `subsys/lorawan/Kconfig`.

- `CONFIG_LORAWAN`
- `CONFIG_LORAWAN_SYSTEM_MAX_RX_ERROR`
- `CONFIG_LORAMAC_REGION_AS923`
- `CONFIG_LORAMAC_REGION_AU915`
- `CONFIG_LORAMAC_REGION_CN470`
- `CONFIG_LORAMAC_REGION_CN779`
- `CONFIG_LORAMAC_REGION_EU433`
- `CONFIG_LORAMAC_REGION_EU868`
- `CONFIG_LORAMAC_REGION_KR920`
- `CONFIG_LORAMAC_REGION_IN865`
- `CONFIG_LORAMAC_REGION_US915`
- `CONFIG_LORAMAC_REGION_RU864`

### 6.4.3 API Reference

**LoRa PHY**

**Related code samples**

**LoRa receive**

Receive packets in both synchronous and asynchronous mode using the LoRa radio.

**LoRa send**

Transmit a preconfigured payload every second using the LoRa radio.

`group lora_api`
Enums

enum lora_signal_bandwidth
LoRa signal bandwidth.
Values:
enumator BW_125_KHZ = 0
enumator BW_250_KHZ
enumator BW_500_KHZ

enum lora_datarate
LoRa data-rate.
Values:
enumator SF_6 = 6
enumator SF_7
enumator SF_8
enumator SF_9
enumator SF_10
enumator SF_11
enumator SF_12

enum lora_coding_rate
LoRa coding rate.
Values:
enumator CR_4_5 = 1
enumator CR_4_6 = 2
enumator CR_4_7 = 3
enumator CR_4_8 = 4
### Functions

**lora_config**

```c
static inline int lora_config(const struct device *dev, struct lora_modem_config *config)
```

Configure the LoRa modem.

**Parameters**

- `dev` – LoRa device
- `config` – Data structure containing the intended configuration for the modem

**Returns**

0 on success, negative on error

**lora_send**

```c
static inline int lora_send(const struct device *dev, uint8_t *data, uint32_t data_len)
```

Send data over LoRa.

**Parameters**

- `dev` – LoRa device
- `data` – Data to be sent
- `data_len` – Length of the data to be sent

**Returns**

0 on success, negative on error

**lora_send_async**

```c
static inline int lora_send_async(const struct device *dev, uint8_t *data, uint32_t data_len, struct k_poll_signal *async)
```

Asynchronously send data over LoRa.

**Parameters**

- `dev` – LoRa device
- `data` – Data to be sent
- `data_len` – Length of the data to be sent
- `async` – A pointer to a valid and ready to be signaled struct `k_poll_signal`.
  (Note: if NULL this function will not notify the end of the transmission).

**Returns**

0 on success, negative on error

**lora_recv**

```c
static inline int lora_recv(const struct device *dev, uint8_t *data, uint8_t size, k_timeout_t timeout, int16_t *rssi, int8_t *snr)
```

Receive data over LoRa.

**Parameters**

- `dev` – LoRa device
- `data` – Data to be sent
- `size` – Length of the data to be sent
- `timeout` – Timeout for receiving data
- `rssi` – Received Signal Strength Indicator
- `snr` – Signal-to-Noise Ratio

**Returns**

0 on success, negative on error

---

6.4. LoRa and LoRaWAN
- dev – LoRa device
- data – Buffer to hold received data
- size – Size of the buffer to hold the received data. Max size allowed is 255.
- timeout – Duration to wait for a packet.
- rssi – RSSI of received data
- snr – SNR of received data

**Returns**
Length of the data received on success, negative on error

static inline int lora_recv_async(const struct device *dev, lora_recv_cb cb)
Receive data asynchronously over LoRa.
Receive packets continuously under the configuration previously setup by lora_config.
Reception is cancelled by calling this function again with cb = NULL. This can be done within the callback handler.

**Parameters**
- dev – Modem to receive data on.
- cb – Callback to run on receiving data. If NULL, any pending asynchronous receptions will be cancelled.

**Returns**
0 when reception successfully setup, negative on error

static inline int lora_test_cw(const struct device *dev, uint32_t frequency, int8_t tx_power, uint16_t duration)
Transmit an unmodulated continuous wave at a given frequency.

**Note:** Only use this functionality in a test setup where the transmission does not interfere with other devices.

**Parameters**
- dev – LoRa device
- frequency – Output frequency (Hertz)
- tx_power – TX power (dBm)
- duration – Transmission duration in seconds.

**Returns**
0 on success, negative on error

struct lora_modem_config
#include <lora.h> Structure containing the configuration of a LoRa modem.

**Public Members**

- uint32_t frequency
  Frequency in Hz to use for transceiving.
typedef enum {
    lora_signal_bandwidth, bandwidth
} lora_signal_bandwidth;

typedef enum {
    lora_datarate, datarate
} lora_datarate;

typedef enum {
    lora_coding_rate, coding_rate
} lora_coding_rate;

uint16_t preamble_len
    Length of the preamble.

int8_t tx_power
    TX-power in dBm to use for transmission.

bool tx
    Set to true for transmission, false for receiving.

bool iq_inverted
    Invert the In-Phase and Quadrature (IQ) signals.
    Normally this should be set to false. In advanced use-cases where a differentiation
    is needed between “uplink” and “downlink” traffic, the IQ can be inverted to create
    two different channels on the same frequency

bool public_network
    Sets the sync-byte to use:

    - false: for using the private network sync-byte
    - true: for using the public network sync-byte

    The public network sync-byte is only intended for advanced usage. Normally the private network sync-byte
    should be used for peer to peer communications and the LoRaWAN APIs should
    be used for interacting with a public network.

LoRaWAN

Related code samples

LoRaWAN class A device
    Join a LoRaWAN network and send a message periodically.

define lorawan_api

Defines

LW_RECV_PORT_ANY
    Flag to indicate receiving on any port.

6.4. LoRa and LoRaWAN
**Typedefs**

typedef uint8_t (*lorawan_battery_level_cb_t)(void)
Defines the battery level callback handler function signature.

- **Retval 0**: if the node is connected to an external power source
- **Retval 1..254**: battery level, where 1 is the minimum and 254 is the maximum value
- **Retval 255**: if the node was not able to measure the battery level

typedef void (*lorawan_dr_changed_cb_t)(enum lorawan_datarate dr)
Defines the datarate changed callback handler function signature.

- **Param dr**: Updated datarate.

**Enums**

eenum lorawan_class
LoRaWAN class types.

- **Values**:
  - enumerator LORAWAN_CLASS_A = 0x00
    - Class A device.
  - enumerator LORAWAN_CLASS_B = 0x01
    - Class B device.
  - enumerator LORAWAN_CLASS_C = 0x02
    - Class C device.

eenum lorawan_act_type
LoRaWAN activation types.

- **Values**:
  - enumerator LORAWAN_ACT_OTAA = 0
    - Over-the-Air Activation (OTAA)
  - enumerator LORAWAN_ACT_ABP
    - Activation by Personalization (ABP)

eenum lorawan_datarate
LoRaWAN datarate types.

- **Values**:
  - enumerator LORAWAN_DR_0 = 0
    - DR0 data rate.
enumerator LORAWAN_DR_1
   DR1 data rate.
enumerator LORAWAN_DR_2
   DR2 data rate.
enumerator LORAWAN_DR_3
   DR3 data rate.
enumerator LORAWAN_DR_4
   DR4 data rate.
enumerator LORAWAN_DR_5
   DR5 data rate.
enumerator LORAWAN_DR_6
   DR6 data rate.
enumerator LORAWAN_DR_7
   DR7 data rate.
enumerator LORAWAN_DR_8
   DR8 data rate.
enumerator LORAWAN_DR_9
   DR9 data rate.
enumerator LORAWAN_DR_10
   DR10 data rate.
enumerator LORAWAN_DR_11
   DR11 data rate.
enumerator LORAWAN_DR_12
   DR12 data rate.
enumerator LORAWAN_DR_13
   DR13 data rate.
enumerator LORAWAN_DR_14
   DR14 data rate.
enumerator LORAWAN_DR_15
   DR15 data rate.

enum lorawan_region
   LoRaWAN region types.
   Values:
enumerator LORAWAN_REGION_AS923
    Asia 923 MHz frequency band.

enumerator LORAWAN_REGION_AU915
    Australia 915 MHz frequency band.

enumerator LORAWAN_REGION_CN470
    China 470 MHz frequency band.

enumerator LORAWAN_REGION_CN779
    China 779 MHz frequency band.

enumerator LORAWAN_REGION_EU433
    Europe 433 MHz frequency band.

enumerator LORAWAN_REGION_EU868
    Europe 868 MHz frequency band.

enumerator LORAWAN_REGION_KR920
    South Korea 920 MHz frequency band.

enumerator LORAWAN_REGION_IN865
    India 865 MHz frequency band.

enumerator LORAWAN_REGION_US915
    United States 915 MHz frequency band.

enumerator LORAWAN_REGION_RU864
    Russia 864 MHz frequency band.

enum lorawan_message_type
    LoRaWAN message types.
    Values:

    enumerator LORAWAN_MSG_UNCONFIRMED = 0
        Unconfirmed message.

    enumerator LORAWAN_MSG_CONFIRMED
        Confirmed message.

Functions

void lorawan_register_battery_level_callback(lorawan_battery_level_cb_t cb)
    Register a battery level callback function.
    Provide the LoRaWAN stack with a function to be called whenever a battery level needs
    to be read.
    Should no callback be provided the lorawan backend will report 255.

    Parameters
• cb – Pointer to the battery level function

```c
void lorawan_register_downlink_callback(struct lorawan_downlink_cb *cb)
```
Register a callback to be run on downlink packets.

**Parameters**

• cb – Pointer to structure containing callback parameters

```c
void lorawan_register_dr_changed_callback(lorawan_dr_changed_cb_t cb)
```
Register a callback to be called when the datarate changes.

The callback is called once upon successfully joining a network and again each time the datarate changes due to ADR.

**Parameters**

• cb – Pointer to datarate update callback

```c
int lorawan_join(const struct lorawan_join_config *config)
```
Join the LoRaWAN network.

Join the LoRaWAN network using OTAA or AWB.

**Parameters**

• config – Configuration to be used

**Returns**

0 if successful, negative errno code if failure

```c
int lorawan_start(void)
```
Start the LoRaWAN stack.

This function need to be called before joining the network.

**Returns**

0 if successful, negative errno code if failure

```c
int lorawan_send(uint8_t port, uint8_t *data, uint8_t len, enum lorawan_message_type type)
```
Send data to the LoRaWAN network.

Send data to the connected LoRaWAN network.

**Parameters**

• port – Port to be used for sending data. Must be set if the payload is not empty.

• data – Data buffer to be sent

• len – Length of the buffer to be sent. Maximum length of this buffer is 255 bytes but the actual payload size varies with region and datarate.

• type – Specifies if the message shall be confirmed or unconfirmed. Must be one of lorawan_message_type.

**Returns**

0 if successful, negative errno code if failure

```c
int lorawan_set_class(enum lorawan_class dev_class)
```
Set the current device class.

Change the current device class. This function may be called before or after a network connection has been established.

**Parameters**

• dev_class – New device class
Returns
0 if successful, negative errno code if failure

int lorawan_set_conf_msg_tries(uint8_t tries)
Set the number of tries used for transmissions.

Parameters
• tries – Number of tries to be used

Returns
0 if successful, negative errno code if failure

void lorawan_enable_adr(bool enable)
Enable Adaptive Data Rate (ADR)
Control whether adaptive data rate (ADR) is enabled. When ADR is enabled, the data rate is treated as a default data rate that will be used if the ADR algorithm has not established a data rate. ADR should normally only be enabled for devices with stable RF conditions (i.e., devices in a mostly static location).

Parameters
• enable – Enable or Disable adaptive data rate.

int lorawan_set_datarate(enum lorawan_datarate dr)
Set the default data rate.
Change the default data rate.

Parameters
• dr – Data rate used for transmissions

Returns
0 if successful, negative errno code if failure

enum lorawan_datarate lorawan_get_min_datarate(void)
Get the minimum possible datarate.
The minimum possible datarate may change in response to a TxParamSetupReq command from the network server.

Returns
Minimum possible data rate

void lorawan_get_payload_sizes(uint8_t *max_next_payload_size, uint8_t *max_payload_size)
Get the current payload sizes.
Query the current payload sizes. The maximum payload size varies with datarate, while the current payload size can be less due to MAC layer commands which are inserted into uplink packets.

Parameters
• max_next_payload_size – Maximum payload size for the next transmission
• max_payload_size – Maximum payload size for this datarate

int lorawan_set_region(enum lorawan_region region)
Set the region and frequency to be used.
Control the LoRa region and frequency settings. This should be called before lorawan_start(). If you only have support for a single region selected via Kconfig, this function does not need to be called at all.

Parameters
• **region** – The region to be selected

**Returns**
0 if successful, negative errno otherwise

```c
struct lorawan_join_otaa
#include <lorawan.h> LoRaWAN join parameters for over-the-Air activation (OTAA)
```

Note that all of the fields use LoRaWAN 1.1 terminology.

All parameters are optional if a secure element is present in which case the values stored in the secure element will be used instead.

**Public Members**

```c
tuint8_t *join_eui
    Join EUI.

tuint8_t *nwk_key
    Network Key.

tuint8_t *app_key
    Application Key.

tuint16_t dev_nonce
    Device Nonce.

    Starting with LoRaWAN 1.0.4 the DevNonce must be monotonically increasing for each OTAA join with the same EUI. The DevNonce should be stored in non-volatile memory by the application.
```

```c
struct lorawan_join_abp
#include <lorawan.h> LoRaWAN join parameters for activation by personalization (ABP)
```

**Public Members**

```c
tuint32_t dev_addr
    Device address on the network.

tuint8_t *app_skey
    Application session key.

tuint8_t *nwk_skey
    Network session key.

tuint8_t *app_eui
    Application EUI.
```

```c
struct lorawan_join_config
#include <lorawan.h> LoRaWAN join parameters.
```
Public Members

struct lorawan_join_otaa otaa
   OTAA join parameters.

struct lorawan_join_abp abp
   ABP join parameters.

union lorawan_join_config
   Join parameters.

uint8_t *dev_eui
   Device EUI.
   Optional if a secure element is present.

enum lorawan_act_type mode
   Activation mode.

struct lorawan_downlink_cb
   #include <lorawan.h> LoRaWAN downlink callback parameters.

Public Members

uint16_t port
   Port to handle messages for:

   • Port 0: TX packet acknowledgements
   • Ports 1-255: Standard downlink port
   • LW_RECV_PORT_ANY: All downlinks

void (*cb)(uint8_t port, bool data_pending, int16_t rssi, int8_t snr, uint8_t len, const uint8_t *data)
   Callback function to run on downlink data.

Note: Callbacks are run on the system workqueue, and should therefore be as short as possible.

   Param port
      Port message was sent on
   Param data_pending
      Network server has more downlink packets pending
   Param rssi
      Received signal strength in dBm
   Param snr
      Signal to Noise ratio in dBm
   Param len
      Length of data received, will be 0 for ACKs
   Param data
      Data received, will be NULL for ACKs
**6.5 USB**

**USB device support**

**6.5.1 USB device support**

- **Overview**
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- **Binary Device Object Store (BOS) support**
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**Overview**

The USB device stack is a hardware independent interface between USB device controller driver and USB device class drivers or customer applications. It is a port of the LPCUSB device stack and has been modified and expanded over time. It provides the following functionalities:

- Uses the **USB device controller driver API** provided by the device controller drivers to interact with the USB device controller.
- Responds to standard device requests and returns standard descriptors, essentially handling ‘Chapter 9’ processing, specifically the standard device requests in table 9-3 from the universal serial bus specification revision 2.0.
- Provides a programming interface to be used by USB device classes or customer applications. The APIs is described in include/zephyr/usb/usb_device.h
The device stack and USB device controller driver API have some limitations, such as not being able to support more than one controller instance at runtime and only supporting one USB device configuration. We are actively working on new USB support, which means we will continue to maintain the device stack described here until all supported USB classes are ported, but do not expect any new features or enhancements.

**Supported USB classes**

**Audio** There is an experimental implementation of the Audio class. It follows specification version 1.00 (bcdADC 0x0100) and supports synchronous synchronisation type only. See usb-audio-headphones-microphone and usb-audio-headset samples for reference.

**Bluetooth HCI USB transport layer** Bluetooth HCI USB transport layer implementation uses *HCI RAW channel* to expose HCI interface to the host. It is not fully in line with the description in the Bluetooth specification and consists only of an interface with the endpoint configuration:

- HCI commands through control endpoint (host-to-device only)
- HCI events through interrupt IN endpoint
- ACL data through one bulk IN and one bulk OUT endpoints

A second interface for the voice channels has not been implemented as there is no support for this type in *Bluetooth*. It is not a big problem under Linux if HCI USB transport layer is the only interface that appears in the configuration, the btusb driver would not try to claim a second (isochronous) interface. The consequence is that if HCI USB is used in a composite configuration and is the first interface, then the Linux btusb driver will claim both the first and the next interface, preventing other composite functions from working. Because of this problem, HCI USB should not be used in a composite configuration. This problem is fixed in the implementation for new USB support.


**CDC ACM** The CDC ACM class is used as backend for different subsystems in Zephyr. However, its configuration may not be easy for the inexperienced user. Below is a description of the different use cases and some pitfalls.

The interface for CDC ACM user is *Universal Asynchronous Receiver-Transmitter (UART) driver API*. But there are two important differences in behavior to a real UART controller:

- Data transfer is only possible after the USB device stack has been initialized and started, until then any data is discarded
- If device is connected to the host, it still needs an application on the host side which requests the data
- The CDC ACM poll out implementation follows the API and blocks when the TX ring buffer is full only if the hw-flow-control property is enabled and called from a non-ISR context.

The devicetree compatible property for CDC ACM UART is zephyr,cdc-acm-uart. CDC ACM support is automatically selected when USB device support is enabled and a compatible node in the devicetree sources is present. If necessary, CDC ACM support can be explicitly disabled by CONFIG_USB_CDC_ACM. About four CDC ACM UART instances can be defined and used, limited by the maximum number of supported endpoints on the controller.

CDC ACM UART node is supposed to be child of a USB device controller node. Since the designation of the controller nodes varies from vendor to vendor, and our samples and application should be as generic as possible, the default USB device controller is usually assigned an zephyr_udc0 node label. Often, CDC ACM UART is described in a devicetree overlay file and looks like this:
Samples usb-cdc-acm and usb-hid-cdc have similar overlay files. And since no special properties are present, it may seem overkill to use devicetree to describe CDC ACM UART. The motivation behind using devicetree is the easy interchangeability of a real UART controller and CDC ACM UART in applications.

**Console over CDC ACM UART** With the CDC ACM UART node from above and `zephyr_console` property of the chosen node, we can describe that CDC ACM UART is to be used with the console. A similar overlay file is used by the usb-cdc-acm-console sample.

```c
/ {
    chosen {
        zephyr,console = &cdc_acm_uart0;
    };
}
```

Before the application uses the console, it is recommended to wait for the DTR signal:

```c
const struct device *const dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_console));
uint32_t dtr = 0;
if (usb_enable(NULL)) {
    return;
}
while (!dtr) {
    uart_line_ctrl_get(dev, UART_LINE_CTRL_DTR, &dtr);
    k_sleep(K_MSEC(100));
}
printk("nuqneH\\n");
```

**CDC ACM UART as backend** As for the console sample, it is possible to configure CDC ACM UART as backend for other subsystems by setting `Chosen nodes` properties.

List of few Zephyr specific chosen properties which can be used to select CDC ACM UART as backend for a subsystem or application:

- `zephyr,bt-c2h-uart` used in Bluetooth, for example see bluetooth-hci-uart-sample
- `zephyr,ot-uart` used in OpenThread, for example see coprocessor
- `zephyr,shell-uart` used by shell for serial backend, for example see samples/subsys/shell/shell_module
- `zephyr,uart-mcumgr` used by smp-svr sample

**6.5. USB**
POSIX default tty ECHO mitigation  POSIX systems, like Linux, default to enabling ECHO on tty devices. Host side application can disable ECHO by calling `open()` on the tty device and issuing `ioctl()` (preferably via `tcsetattr()`) to disable echo if it is not desired. Unfortunately, there is an inherent race between the `open()` and `ioctl()` where the ECHO is enabled and any characters received (even if host application does not call `read()`) will be echoed back. This issue is especially visible when the CDC ACM port is used without any real UART on the other side because there is no arbitrary delay due to baud rate.

To mitigate the issue, Zephyr CDC ACM implementation arms IN endpoint with ZLP after device is configured. When the host reads the ZLP, which is pretty much the best indication that host application has opened the tty device, Zephyr will force `CONFIG_CDC_ACM_TX_DELAY_MS` milliseconds delay before real payload is sent. This should allow sufficient time for first, and only first, application that opens the tty device to disable ECHO if ECHO is not desired. If ECHO is not desired at all from CDC ACM device it is best to set up udev rule to disable ECHO as soon as device is connected.

ECHO is particularly unwanted when CDC ACM instance is used for Zephyr shell, because the control characters to set color sent back to shell are interpreted as (invalid) command and user will see garbage as a result. While minicom does disable ECHO by default, on exit with reset it will restore the termios settings to whatever was set on entry. Therefore, if minicom is the first application to open the tty device, the exit with reset will enable ECHO back and thus set up a problem for the next application (which cannot be mitigated at Zephyr side). To prevent the issue it is recommended either to leave minicom without reset or to disable ECHO before minicom is started.

DFU  USB DFU class implementation is tightly coupled to `Device Firmware Upgrade` and `MCU-Boot API`. This means that the target platform must support the `Flash Image API`.

See `usb-dfu` sample for reference.

USB Human Interface Devices (HID) support  HID support abuses `Device Driver Model` simply to allow applications to use the `device_get_binding()`. Note that there is no HID device API as such, instead the interface is provided by `hid_ops`. The default instance name is HID_n, where n can be {0, 1, 2, ...} depending on the `CONFIG_USB_HID_DEVICE_COUNT`.

Each HID instance requires a HID report descriptor. The interface to the core and the report descriptor must be registered using `usb_hid_register_device()`.

As the USB HID specification is not only used by the USB subsystem, the USB HID API reference is split into two parts, `Human Interface Devices (HID)` and `USB HID Class API`. HID helper macros from `Human Interface Devices (HID)` should be used to compose a HID report descriptor. Macro names correspond to those used in the USB HID specification.

For the HID class interface, an IN interrupt endpoint is required for each instance, an OUT interrupt endpoint is optional. Thus, the minimum implementation requirement for `hid_ops` is to provide `int_in_ready` callback.

```
#define REPORT_ID 1
static bool configured;
static const struct device *hdev;

static void int_in_ready_cb(const struct device *dev) {
    static uint8_t report[2] = {REPORT_ID, 0};
    if (hid_int_ep_write(hdev, report, sizeof(report), NULL)) {
        LOG_ERR("Failed to submit report");
    } else {
        report[1]++;
    }
}
```
static void status_cb(enum usb_dc_status_code status, const uint8_t *param)
{
    if (status == USB_DC_RESET) {
        configured = false;
    }

    if (status == USB_DC_CONFIGURED && !configured) {
        int_in_ready_cb(hdev);
        configured = true;
    }
}

static const uint8_t hid_report_desc[] = {
    HID_USAGE_PAGE(HID_USAGE_GEN_DESKTOP),
    HID_USAGE(HID_USAGE_GEN_DESKTOP_UNDEFINED),
    HID_COLLECTION(HID_COLLECTION_APPLICATION),
    HID_LOGICAL_MIN8(0x00),
    HID_LOGICAL_MAX16(0xFF, 0x00),
    HID_REPORT_ID(REPORT_ID),
    HID_REPORT_SIZE(8),
    HID_REPORT_COUNT(1),
    HID_USAGE(HID_USAGE_GEN_DESKTOP_UNDEFINED),
    HID_INPUT(0x02),
    HID_END_COLLECTION,
};

static const struct hid_ops my_ops = {
    .int_in_ready = int_in_ready_cb,
};

int main(void)
{
    int ret;

    hdev = device_get_binding("HID_0");
    if (hdev == NULL) {
        return -ENODEV;
    }

    usb_hid_register_device(hdev, hid_report_desc, sizeof(hid_report_desc), &my_ops);

    ret = usb_hid_init(hdev);
    if (ret) {
        return ret;
    }

    return usb_enable(status_cb);
}

If the application wishes to receive output reports via the OUT interrupt endpoint, it must enable CONFIG_ENABLE_HID_INT_OUT_EP and provide int_out_ready callback. The disadvantage of this is that Kconfig options such as CONFIG_ENABLE_HID_INT_OUT_EP or CONFIG_HID_INTERRUPT_EP_MPS apply to all instances. This design issue will be fixed in the HID class implementation for the new USB support.

See usb-hid or usb-hid-mouse sample for reference.
Mass Storage Class MSC follows Bulk-Only Transport specification and uses Disk Access to access and expose a RAM disk, emulated block device on a flash partition, or SD card to the host. Only one disk instance can be exported at a time.

The disc to be used by the implementation is set by the CONFIG_MASS_STORAGE_DISK_NAME and should be the same as the name used by the disc access driver that the application wants to expose to the host. SD card disk drivers use options CONFIG_MMC_VOLUME_NAME or CONFIG_SDMMC_VOLUME_NAME, and flash and RAM disk drivers use node property disk-name to set the disk name.

For the emulated block device on a flash partition, the flash partition and flash disk to be used must be described in the devicetree. If a storage partition is already described at the board level, application devicetree overlay must also delete storage_partition node first. CONFIG_MASS_STORAGE_DISK_NAME should be the same as disk-name property.

```
/delete-node/ &storage_partition;

&mx25r64 {
    partitions {
        compatible = "fixed-partitions";
        #address-cells = <1>;
        #size-cells = <1>;
        storage_partition: partition0 {
            label = "storage";
            reg = <0x00000000 0x00020000>;
        }
    }

    &msc_disk0 {
        compatible = "zephyr,flash-disk";
        partition = <&storage_partition>;
        disk-name = "NAND";
        cache-size = <4096>;
    }
};
```

The disk-property “NAND” may be confusing, but it is simply how some file systems identifies the disc. Therefore, if the application also accesses the file system on the exposed disc, default names should be used, see usb-mass sample for reference.

Networking There are three implementations that work in a similar way, providing a virtual Ethernet connection between the remote (USB host) and Zephyr network support.

- CDC ECM class, enabled with CONFIG_USB_DEVICE_NETWORK_ECM
- CDC EEM class, enabled with CONFIG_USB_DEVICE_NETWORK_EEM
- RNDIS support, enabled with CONFIG_USB_DEVICE_NETWORK_RNDIS

See zperf or socket-dumb-http-server for reference. Typically, users will need to add a configuration file overlay to the build, such as samples/net/zperf/overlay-netusb.conf.

Applications using RNDIS support should enable CONFIG_USB_DEVICE_OS_DESC for a better user experience on a host running Microsoft Windows OS.

Binary Device Object Store (BOS) support

BOS handling can be enabled with Kconfig option CONFIG_USB_DEVICE_BOS. This option also has the effect of changing device descriptor bcdUSB to 0210. The application should register descrip-
tors such as Capability Descriptor using `usb_bos_register_cap()`. Registered descriptors are added to the root BOS descriptor and handled by the stack.

See webusb sample for reference.

### Implementing a non-standard USB class

The configuration of USB device is done in the stack layer.

The following structures and callbacks need to be defined:

- Part of USB Descriptor table
- USB Endpoint configuration table
- USB Device configuration structure
- Endpoint callbacks
- Optionally class, vendor and custom handlers

For example, for the USB loopback application:

```c
struct usb_loopback_config {
    struct usb_if_descriptor if0;
    struct usb_ep_descriptor if0_out_ep;
    struct usb_ep_descriptor if0_in_ep;
} __packed;

USBD_CLASS_DESCR_DEFINE(primary, 0) struct usb_loopback_config loopback_cfg = {
    /* Interface descriptor 0 */
    .if0 = {
        .bLength = sizeof(struct usb_if_descriptor),
        .bDescriptorType = USB_DESC_INTERFACE,
        .bInterfaceNumber = 0,
        .bAlternateSetting = 0,
        .bNumEndpoints = 2,
        .bInterfaceClass = USB_BCC_VENDOR,
        .bInterfaceSubClass = 0,
        .bInterfaceProtocol = 0,
        .iInterface = 0,
    },

    /* Data Endpoint OUT */
    .if0_out_ep = {
        .bLength = sizeof(struct usb_ep_descriptor),
        .bDescriptorType = USB_DESC_ENDPOINT,
        .bEndpointAddress = LOOPBACK_OUT_EP_ADDR,
        .bmAttributes = USB_DC_EP_BULK,
        .wMaxPacketSize = sys_cpu_to_le16(CONFIG_LOOPBACK_BULK_EP_MPS),
        .bInterval = 0x00,
    },

    /* Data Endpoint IN */
    .if0_in_ep = {
        .bLength = sizeof(struct usb_ep_descriptor),
        .bDescriptorType = USB_DESC_ENDPOINT,
        .bEndpointAddress = LOOPBACK_IN_EP_ADDR,
        .bmAttributes = USB_DC_EP_BULK,
        .wMaxPacketSize = sys_cpu_to_le16(CONFIG_LOOPBACK_BULK_EP_MPS),
        .bInterval = 0x00,
    },
};
```

### Endpoint configuration:

6.5. USB
static struct usb_ep_cfg_data ep_cfg[] = {
    { .ep_cb = loopback_out_cb,
      .ep_addr = LOOPBACK_OUT_EP_ADDR,
    },
    { .ep_cb = loopback_in_cb,
      .ep_addr = LOOPBACK_IN_EP_ADDR,
    },
};

USB Device configuration structure:

USBD_DEFINE_CFG_DATA(loopback_config) = {
    .usb_device_description = NULL,
    .interface_config = loopback_interface_config,
    .interface_descriptor = &loopback_cfg.if0,
    .cb_usb_status = loopback_status_cb,
    .interface = {
        .class_handler = NULL,
        .custom_handler = NULL,
        .vendor_handler = loopback_vendor_handler,
    },
    .num_endpoints = ARRAY_SIZE(ep_cfg),
    .endpoint = ep_cfg,
};

The vendor device requests are forwarded by the USB stack core driver to the class driver through the registered vendor handler:

For the loopback class driver, loopback_vendor_handler() processes the vendor requests:

static int loopback_vendor_handler(struct usb_setup_packet *setup,
      int32_t *len, uint8_t **data) {
    LOG_DBG("Class request: bRequest 0x%x bmRequestType 0x%x len %d",
            setup->bRequest, setup->bmRequestType, *len);
    if (setup->RequestType.recipient != USB_REQTYPE_RECIPIENT_DEVICE) {
        return -ENOTSUP;
    }
    if (usb_reqtype_is_to_device(setup) &&
        setup->bRequest == 0x5b) {
        LOG_DBG("Host-to-Device, data %p", *data);
        /*
         * Copy request data in loopback_buf buffer and reuse
         * it later in control device-to-host transfer.
         */
        memcpy(loopback_buf, *data,
               MIN(sizeof(loopback_buf), setup->wLength));
        return 0;
    }
    if ((usb_reqtype_is_to_host(setup)) &&
        (setup->bRequest == 0x5c)) {
        LOG_DBG("Device-to-Host, wLength %d, data %p",
                 setup->wLength, *data);
        *data = loopback_buf;
        *len = MIN(sizeof(loopback_buf), setup->wLength);
        return 0;
    }
}

(continues on next page)
The class driver waits for the `USB_DC_CONFIGURED` device status code before transmitting any data.

### Interface number and endpoint address assignment

In USB terminology, a function is a device that provides a capability to the host, such as a HID class device that implements a keyboard. A function contains a collection of interfaces; at least one interface is required. An interface may contain device endpoints; for example, at least one input endpoint is required to implement a HID class device, and no endpoints are required to implement a USB DFU class. A USB device that combines functions is a multifunction USB device, for example, a combination of a HID class device and a CDC ACM device.

With Zephyr RTOS USB support, various combinations are possible with built-in USB classes/functions or custom user implementations. The limitation is the number of available device endpoints. Each device endpoint is uniquely addressable. The endpoint address is a combination of endpoint direction and endpoint number, a four-bit value. Endpoint number zero is used for the default control method to initialize and configure a USB device. By specification, a maximum of 15 IN and 15 OUT device endpoints are also available for use in functions. The actual number depends on the device controller used. Not all controllers support the maximum number of endpoints and all endpoint types. For example, a device controller might support one IN and one OUT isochronous endpoint, but only for endpoint number 8, resulting in endpoint addresses 0x88 and 0x08. Also, one controller may be able to have IN/OUT endpoints on the same endpoint number, interrupt IN endpoint 0x81 and bulk OUT endpoint 0x01, while the other may only be able to handle one endpoint per endpoint number. Information about the number of interfaces, interface associations, endpoint types, and addresses is provided to the host by the interface, interface specific, and endpoint descriptors.

Host driver for specific function, uses interface and endpoint descriptor to obtain endpoint addresses, types, and other properties. This allows function host drivers to be generic, for example, a multi-function device consisting of one or more CDC ACM and one or more CDC ECM class implementations is possible and no specific drivers are required.

Interface and endpoint descriptors of built-in USB class/function implementations in Zephyr RTOS typically have default interface numbers and endpoint addresses assigned in ascending order. During initialization, default interface numbers may be reassigned based on the number of interfaces in a given configuration. Endpoint addresses are reassigned based on controller capabilities, since certain endpoint combinations are not possible with every controller, and the number of interfaces in a given configuration. This also means that the device side class/function in the Zephyr RTOS must check the actual interface and endpoint descriptor values at runtime. This mechanism also allows as to provide generic samples and generic multifunction samples that are limited only by the resources provided by the controller, such as the number of endpoints and the size of the endpoint FIFOs.

There may be host drivers for a specific function, for example in the Linux Kernel, where the function driver does not read interface and endpoint descriptors to check interface numbers or endpoint addresses, but instead uses hardcoded values. Therefore, the host driver cannot be used in a generic way, meaning it cannot be used with different device controllers and different device configurations in combination with other functions. This may also be because the driver is designed for a specific hardware and is not intended to be used with a clone of this specific hardware. On the contrary, if the driver is generic in nature and should work with different hardware variants, then it must not use hardcoded interface numbers and endpoint addresses. It is not possible to disable endpoint reassignment in Zephyr RTOS, which may prevent you from implementing a hardware-clone firmware. Instead, if possible, the host driver implementation should be fixed to use values from the interface and endpoint descriptor.
Testing over USPIP in native_sim

A virtual USB controller implemented through USBIP might be used to test the USB device stack. Follow the general build procedure to build the USB sample for the native_sim configuration.

Run built sample with:

```
west build -t run
```

In a terminal window, run the following command to list USB devices:

```
$ usbip list -r localhost
Exportable USB devices
======================
- 127.0.0.1
  1-1: unknown vendor : unknown product (2fe3:0100)
    : /sys/devices/pci0000:00/0000:00:01.2/usb1/1-1
    : (Defined at Interface level) (00/00/00)
    : 0 - Vendor Specific Class / unknown subclass / unknown protocol (ff/00/00)
```

In a terminal window, run the following command to attach the USB device:

```
$ sudo usbip attach -r localhost -b 1-1
```

The USB device should be connected to your Linux host, and verified with the following commands:

```
$ sudo usbip port
Imported USB devices
====================
Port 00: <Port in Use> at Full Speed(12Mbps)
  unknown vendor : unknown product (2fe3:0100)
    -> usbip://localhost:3240/1-1
    -> remote bus/dev 001/002
$ lsusb -d 2fe3:0100
Bus 007 Device 004: ID 2fe3:0100
```

USB Vendor and Product identifiers

The USB Vendor ID for the Zephyr project is 0x2FE3. This USB Vendor ID must not be used when a vendor integrates Zephyr USB device support into its own product.

Each USB sample has its own unique Product ID. The USB maintainer, if one is assigned, or otherwise the Zephyr Technical Steering Committee, may allocate other USB Product IDs based on well-motivated and documented requests.

The following Product IDs are currently used:
The USB device descriptor field `bcdDevice` (Device Release Number) represents the Zephyr kernel major and minor versions as a binary coded decimal value.

### 6.5.2 USB device support APIs

#### USB device controller driver API

The USB device controller driver API is described in `include/zephyr/drivers/usb/usb_dc.h` and sometimes referred to as the `usb_dc` API.

This API has some limitations by design, it does not follow *Device Driver Model* and is being replaced by a new UDC driver API.

#### API reference

*group* _usb_device_controller_api_

USB Device Controller API.

#### Typedefs

```c
typedef void (*usb_dc_ep_callback)(uint8_t ep, enum usb_dc_ep_cb_status_code cb_status)
```

Callback function signature for the USB Endpoint status.

```c
typedef void (*usb_dc_status_callback)(enum usb_dc_status_code cb_status, const uint8_t *param)
```

Callback function signature for the device.

#### Enums

```c
enum usb_dc_status_code
```

USB Driver Status Codes.

Status codes reported by the registered device status callback.
Values:

enumerator USB_DC_ERROR
    USB error reported by the controller.

enumerator USB_DC_RESET
    USB reset.

enumerator USB_DC_CONNECTED
    USB connection established, hardware enumeration is completed.

enumerator USB_DC_CONFIGURED
    USB configuration done.

enumerator USB_DC_DISCONNECTED
    USB connection lost.

enumerator USB_DC_SUSPEND
    USB connection suspended by the HOST.

enumerator USB_DC_RESUME
    USB connection resumed by the HOST.

enumerator USB_DC_INTERFACE
    USB interface selected.

enumerator USB_DC_SET_HALT
    Set Feature ENDPOINT_HALT received.

enumerator USB_DC_CLEAR_HALT
    Clear Feature ENDPOINT_HALT received.

enumerator USB_DC_SOF
    Start of Frame received.

enumerator USB_DC_UNKNOWN
    Initial USB connection status.

enum usb_dc_ep_cb_status_code
    USB Endpoint Callback Status Codes.
    Status Codes reported by the registered endpoint callback.
    Values:

enumerator USB_DC_EP_SETUP
    SETUP received.

enumerator USB_DC_EP_DATA_OUT
    Out transaction on this EP, data is available for read.
enumerator USB_DC_EP_DATA_IN
   In transaction done on this EP.

enum usb_dc_ep_transfer_type
USB Endpoint Transfer Type.
Values:

enumerator USB_DC_EP_CONTROL = 0
   Control type endpoint.

enumerator USB_DC_EP_ISOCHRONOUS
   Isochronous type endpoint.

enumerator USB_DC_EP_BULK
   Bulk type endpoint.

enumerator USB_DC_EP_INTERRUPT
   Interrupt type endpoint

enum usb_dc_ep_synchronozation_type
USB Endpoint Synchronization Type.

---

**Note:** Valid only for Isochronous Endpoints

---

Values:

enumerator USB_DC_EP_NO_SYNCHRONIZATION = (0U « 2U)
   No Synchronization.

enumerator USB_DC_EPASYNCHRONOUS = (1U « 2U)
   Asynchronous.

enumerator USB_DC_EP_ADAPTIVE = (2U « 2U)
   Adaptive.

enumerator USB_DC_EP_SYNCHRONOUS = (3U « 2U)
   Synchronous.

---

**Functions**

int usb_dc_attach(void)
   Attach USB for device connection.
Function to attach USB for device connection. Upon success, the USB PLL is enabled, and the USB device is now capable of transmitting and receiving on the USB bus and of generating interrupts.

---

**Returns**
   0 on success, negative errno code on fail.
int usb_dc_detach(void)
   Detach the USB device.

   Function to detach the USB device. Upon success, the USB hardware PLL is powered
down and USB communication is disabled.

   Returns
   0 on success, negative errno code on fail.

int usb_dc_reset(void)
   Reset the USB device.

   This function returns the USB device and firmware back to it's initial state. N.B. the
USB PLL is handled by the usb_detach function

   Returns
   0 on success, negative errno code on fail.

int usb_dc_set_address(const uint8_t addr)
   Set USB device address.

   Parameters
   • addr – [in] Device address

   Returns
   0 on success, negative errno code on fail.

void usb_dc_set_status_callback(const usb_dc_status_callback cb)
   Set USB device controller status callback.

   Function to set USB device controller status callback. The registered callback is used
to report changes in the status of the device controller. The status code are described
by the usb_dc_status_code enumeration.

   Parameters
   • cb – [in] Callback function

int usb_dc_ep_check_cap(const struct usb_dc_ep_cfg_data *const cfg)
   check endpoint capabilities

   Function to check capabilities of an endpoint. usb_dc_ep_cfg_data structure provides
the endpoint configuration parameters: endpoint address, endpoint maximum packet
size and endpoint type. The driver should check endpoint capabilities and return 0 if
the endpoint configuration is possible.

   Parameters
   • cfg – [in] Endpoint config

   Returns
   0 on success, negative errno code on fail.

int usb_dc_ep_configure(const struct usb_dc_ep_cfg_data *const cfg)
   Configure endpoint.

   Function to configure an endpoint. usb_dc_ep_cfg_data structure provides the end-
point configuration parameters: endpoint address, endpoint maximum packet size
and endpoint type.

   Parameters
   • cfg – [in] Endpoint config

   Returns
   0 on success, negative errno code on fail.
int usb_dc_ep_set_stall(const uint8_t ep)
Set stall condition for the selected endpoint.

Parameters

• ep  – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_clear_stall(const uint8_t ep)
Clear stall condition for the selected endpoint.

Parameters

• ep  – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_is_stalled(const uint8_t ep, uint8_t *const stalled)
Check if the selected endpoint is stalled.

Parameters

• ep  – [in] Endpoint address corresponding to the one listed in the device configuration table

• stalled  – [out] Endpoint stall status

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_halt(const uint8_t ep)
Halt the selected endpoint.

Parameters

• ep  – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_enable(const uint8_t ep)
Enable the selected endpoint.
Function to enable the selected endpoint. Upon success interrupts are enabled for the corresponding endpoint and the endpoint is ready for transmitting/receiving data.

Parameters

• ep  – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_disable(const uint8_t ep)
Disable the selected endpoint.
Function to disable the selected endpoint. Upon success interrupts are disabled for the corresponding endpoint and the endpoint is no longer able for transmitting/receiving data.

Parameters
- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

**Returns**
0 on success, negative errno code on fail.

```c
int usb_dc_ep_flush(const uint8_t ep)
```
Flush the selected endpoint.

This function flushes the FIFOs for the selected endpoint.

**Parameters**
- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

**Returns**
0 on success, negative errno code on fail.

```c
int usb_dc_ep_write(const uint8_t ep, const uint8_t *const data, const uint32_t data_len, uint32_t *const ret_bytes)
```
Write data to the specified endpoint.

This function is called to write data to the specified endpoint. The supplied `usb_ep_callback` function will be called when data is transmitted out.

**Parameters**
- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
- **data** – [in] Pointer to data to write
- **data_len** – [in] Length of the data requested to write. This may be zero for a zero length status packet.
- **ret_bytes** – [out] Bytes scheduled for transmission. This value may be NULL if the application expects all bytes to be written

**Returns**
0 on success, negative errno code on fail.

```c
int usb_dc_ep_read(const uint8_t ep, uint8_t *const data, const uint32_t max_data_len, uint32_t *const read_bytes)
```
Read data from the specified endpoint.

This function is called by the endpoint handler function, after an OUT interrupt has been received for that EP. The application must only call this function through the supplied `usb_ep_callback` function. This function clears the ENDPOINT NAK, if all data in the endpoint FIFO has been read, so as to accept more data from host.

**Parameters**
- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
- **data** – [in] Pointer to data buffer to write to
- **max_data_len** – [in] Max length of data to read
- **read_bytes** – [out] Number of bytes read. If data is NULL and `max_data_len` is 0 the number of bytes available for read should be returned.

**Returns**
0 on success, negative errno code on fail.
int usb_dc_ep_set_callback(const uint8_t ep, const usb_dc_ep_callback cb)

Set callback function for the specified endpoint.

Function to set callback function for notification of data received and available to application or transmit done on the selected endpoint, NULL if callback not required by application code. The callback status code is described by usb_dc_ep_cb_status_code.

Parameters
- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
- **cb** – [in] Callback function

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_read_wait(uint8_t ep, uint8_t *data, uint32_t max_data_len, uint32_t *read_bytes)

Read data from the specified endpoint.

This is similar to usb_dc_ep_read, the difference being that, it doesn't clear the endpoint NAKs so that the consumer is not bogged down by further upcalls till he is done with the processing of the data. The caller should reactivate ep by invoking usb_dc_ep_read_continue() do so.

Parameters
- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
- **data** – [in] Pointer to data buffer to write to
- **max_data_len** – [in] Max length of data to read
- **read_bytes** – [out] Number of bytes read. If data is NULL and max_data_len is 0 the number of bytes available for read should be returned.

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_read_continue(uint8_t ep)

Continue reading data from the endpoint.

Clear the endpoint NAK and enable the endpoint to accept more data from the host. Usually called after usb_dc_ep_read_wait() when the consumer is fine to accept more data. Thus these calls together act as a flow control mechanism.

Parameters
- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_mps(uint8_t ep)

Get endpoint max packet size.

Parameters
- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
Endpoint max packet size (mps)
int usb_dc_wakeup_request(void)
    Start the host wake up procedure.
    Function to wake up the host if it's currently in sleep mode.

    Returns
    0 on success, negative errno code on fail.

struct usb_dc_ep_cfg_data
#include <usb_dc.h> USB Endpoint Configuration.
Structure containing the USB endpoint configuration.

Public Members

uint8_t ep_addr
    The number associated with the EP in the device configuration structure IN EP = 0x80 | <endpoint number> OUT EP = 0x00 | <endpoint number>

uint16_t ep_mps
    Endpoint max packet size.

defined usb_dc_ep_transfer_type ep_type
    Endpoint Transfer Type.
    May be Bulk, Interrupt, Control or Isochronous

USB device stack API

API reference    There are two ways to transmit data, using the ‘low’ level read/write API or the ‘high’ level transfer API.

Low level API    To transmit data to the host, the class driver should call usb_write(). Upon completion the registered endpoint callback will be called. Before sending another packet the class driver should wait for the completion of the previous write. When data is received, the registered endpoint callback is called. usb_read() should be used for retrieving the received data. For CDC ACM sample driver this happens via the OUT bulk endpoint handler (cdc_acm_bulk_out) mentioned in the endpoint array (cdc_acm_ep_data).

High level API    The usb_transfer method can be used to transfer data to/from the host. The transfer API will automatically split the data transmission into one or more USB transaction(s), depending endpoint max packet size. The class driver does not have to implement endpoint callback and should set this callback to the generic usb_transfer_ep_callback.

Related code samples

802.15.4 USB    Implement a device that exposes an IEEE 802.15.4 radio over USB.

Console over USB CDC ACM    Output ”Hello World!” to the console over USB CDC ACM.

USB Audio asynchronous explicit feedback sample    USB Audio 2 explicit feedback sample playing audio on I2S.
USB Audio headset
Implement a USB Audio headset device with audio IN/OUT loopback.

USB Audio microphone & headphones
Implement a USB Audio microphone + headphones device with audio IN/OUT loopback.

USB CDC-ACM
Use USB CDC-ACM driver to implement a serial port echo.

USB DFU (Device Firmware Upgrade)
Implement device firmware upgrade using the USB DFU class driver.

USB HID and CDC ACM
Expose multiple USB HID and CDC ACM instances.

USB HID mouse
Implement a basic HID mouse device.

USB Mass Storage
Expose board’s RAM or FLASH as a USB disk using USB Mass Storage driver.

USB testing application
Test USB device drivers using a loopback function.

---

group _usb_device_core_api
USB Device Core Layer API.

Defines

USB_TRANS_READ

USB_TRANS_WRITE

USB_TRANS_NO_ZLP

Typedefs

typedef void (*usb_ep_callback)(uint8_t ep, enum usb_dc_ep_cb_status_code cb_status)
Callback function signature for the USB Endpoint status.

typedef int (*usb_request_handler)(struct usb_setup_packet *setup, int32_t *transfer_len, uint8_t **payload_data)
Callback function signature for class specific requests.
Function which handles Class specific requests corresponding to an interface number specified in the device descriptor table. For host to device direction the ‘len’ and ‘payload_data’ contain the length of the received data and the pointer to the received data respectively. For device to host class requests, ‘len’ and ‘payload_data’ should be set by the callback function with the length and the address of the data to be transmitted buffer respectively.

typedef void (*usb_interface_config)(struct usb_desc_header *head, uint8_t bInterfaceNumber)
Function for interface runtime configuration.
typedef void (*usb_transfer_callback)(uint8_t ep, int tsize, void *priv)

Callback function signature for transfer completion.

Functions

int usb_set_config(const uint8_t *usb_descriptor)

Configure USB controller.

Function to configure USB controller. Configuration parameters must be valid or an error is returned

Parameters

• usb_descriptor – [in] USB descriptor table

Returns

0 on success, negative errno code on fail

int usb_deconfig(void)

Deconfigure USB controller.

This function returns the USB device to it’s initial state

Returns

0 on success, negative errno code on fail

int usb_enable(uint8_t ep, const uint8_t *data, uint32_t data_len, uint32_t *bytes_ret)

Write data to the specified endpoint.

Function to write data to the specified endpoint. The supplied usb_ep_callback will be called when transmission is done.

Parameters

• ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Configure USB controller.

Function to configure USB controller. Configuration parameters must be valid or an error is returned

Parameters

• usb_descriptor – [in] USB descriptor table

Returns

0 on success, negative errno code on fail
• **data** – [in] Pointer to data to write
• **data_len** – [in] Length of data requested to write. This may be zero for a zero length status packet.
• **bytes_ret** – [out] Bytes written to the EP FIFO. This value may be NULL if the application expects all bytes to be written

**Returns**
0 on success, negative errno code on fail

```c
int usb_read(uint8_t ep, uint8_t *data, uint32_t max_data_len, uint32_t *ret_bytes);
```

Read data from the specified endpoint.

This function is called by the Endpoint handler function, after an OUT interrupt has been received for that EP. The application must only call this function through the supplied usb_ep_callback function.

**Parameters**
• **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
• **data** – [in] Pointer to data buffer to write to
• **max_data_len** – [in] Max length of data to read
• **ret_bytes** – [out] Number of bytes read. If data is NULL and max_data_len is 0 the number of bytes available for read is returned.

**Returns**
0 on success, negative errno code on fail

```c
int usb_ep_set_stall(uint8_t ep);
```

Set STALL condition on the specified endpoint.

This function is called by USB device class handler code to set stall condition on endpoint.

**Parameters**
• **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

**Returns**
0 on success, negative errno code on fail

```c
int usb_ep_clear_stall(uint8_t ep);
```

Clears STALL condition on the specified endpoint.

This function is called by USB device class handler code to clear stall condition on endpoint.

**Parameters**
• **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

**Returns**
0 on success, negative errno code on fail

```c
int usb_ep_read_wait(uint8_t ep, uint8_t *data, uint32_t max_data_len, uint32_t *read_bytes);
```

Read data from the specified endpoint.

This is similar to `usb_ep_read`, the difference being that, it doesn't clear the endpoint NAKs so that the consumer is not bogged down by further upcalls till he is done with the processing of the data. The caller should reactivate ep by invoking `usb_ep_read_continue()` do so.
Parameters

- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
- **data** – [in] Pointer to data buffer to write to
- **max_data_len** – [in] Max length of data to read
- **read_bytes** – [out] Number of bytes read. If data is NULL and max_data_len is 0, the number of bytes available for read should be returned.

Returns

0 on success, negative errno code on fail.

```c
int usb_ep_read_continue(uint8_t ep)
```

Continue reading data from the endpoint.

Clear the endpoint NAK and enable the endpoint to accept more data from the host. Usually called after `usb_ep_read_wait()` when the consumer is fine to accept more data. Thus these calls together acts as flow control mechanism.

Parameters

- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns

0 on success, negative errno code on fail.

```c
void usb_transfer_ep_callback(uint8_t ep, enum usb_dc_ep_cb_status_code)
```

Transfer management endpoint callback.

If a USB class driver wants to use high-level transfer functions, driver needs to register this callback as usb endpoint callback.

```c
int usb_transfer(uint8_t ep, uint8_t *data, size_t dlen, unsigned int flags, usb_transfer_callback cb, void *priv)
```

Start a transfer.

Start a USB transfer to/from the data buffer. This function is asynchronous and can be executed in IRQ context. The provided callback will be called on transfer completion (or error) in thread context.

Parameters

- **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
- **data** – [in] Pointer to data buffer to write-to/read-from
- **dlen** – [in] Size of data buffer
- **flags** – [in] Transfer flags (USB_TRANS_READ, USB_TRANS_WRITE...)
- **cb** – [in] Function called on transfer completion/failure
- **priv** – [in] Data passed back to the transfer completion callback

Returns

0 on success, negative errno code on fail.

```c
int usb_transfer_sync(uint8_t ep, uint8_t *data, size_t dlen, unsigned int flags)
```

Start a transfer and block-wait for completion.

Synchronous version of `usb_transfer`, wait for transfer completion before returning. A return value of zero can also mean that transfer was cancelled or that the endpoint is not ready. This is due to the design of transfers and `usb_dc` API.
Parameters

- **ep** – **[in]** Endpoint address corresponding to the one listed in the device configuration table
- **data** – **[in]** Pointer to data buffer to write-to/read-from
- **dlen** – **[in]** Size of data buffer
- **flags** – **[in]** Transfer flags

Returns

number of bytes transferred on success, negative errno code on fail.

```c
void usb_cancel_transfer(uint8_t ep)
```
Cancel any ongoing transfer on the specified endpoint.

Parameters

- **ep** – **[in]** Endpoint address corresponding to the one listed in the device configuration table

```c
void usb_cancel_transfers(void)
```
Cancel all ongoing transfers.

```c
bool usb_transfer_is_busy(uint8_t ep)
```
Check that transfer is ongoing for the endpoint.

Parameters

- **ep** – **[in]** Endpoint address corresponding to the one listed in the device configuration table

Returns

true if transfer is ongoing, false otherwise.

```c
int usb_wakeup_request(void)
```
Start the USB remote wakeup procedure.

Function to request a remote wakeup. This feature must be enabled in configuration, otherwise it will always return -ENOTSUP error.

Returns

0 on success, negative errno code on fail, i.e. when the bus is already active.

```c
bool usb_get_remote_wakeup_status(void)
```
Get status of the USB remote wakeup feature.

Returns

true if remote wakeup has been enabled by the host, false otherwise.

```c
struct usb_ep_cfg_data
```

#include <usb_device.h> USB Endpoint Configuration.

This structure contains configuration for the endpoint.

Public Members

```c
usb_ep_callback ep_cb
```
Callback function for notification of data received and available to application or transmit done, NULL if callback not required by application code.
uint8_t ep_addr

The number associated with the EP in the device configuration structure IN EP = 0x80 | <endpoint number> OUT EP = 0x00 | <endpoint number>

struct usb_interface_cfg_data

#include <usb_device.h> USB Interface Configuration.
This structure contains USB interface configuration.

**Public Members**

`usb_request_handler class_handler`
Handler for USB Class specific Control (EP 0) communications.

`usb_request_handler vendor_handler`
Handler for USB Vendor specific commands.

`usb_request_handler custom_handler`
The custom request handler gets a first chance at handling the request before it is handed over to the ‘chapter 9’ request handler.

return 0 on success, -EINVAL if the request has not been handled by the custom handler and instead needs to be handled by the core USB stack. Any other error code to denote failure within the custom handler.

struct usb_cfg_data

#include <usb_device.h> USB device configuration.
The Application instantiates this with given parameters added using the “usb_set_config” function. Once this function is called changes to this structure will result in undefined behavior. This structure may only be updated after calls to usb_deconfig

**Public Members**

cnst uint8_t *usb_device_description
USB device description, see [http://www.beyondlogic.org/usbnutshell/usb5.shtml#DeviceDescriptors](http://www.beyondlogic.org/usbnutshell/usb5.shtml#DeviceDescriptors).

void *interface_descriptor
Pointer to interface descriptor.

`usb_interface_config interface_config`
Function for interface runtime configuration.

void (*cb_usb_status)(struct usb_cfg_data *cfg, enum usb_dc_status_code cb_status, const uint8_t *param)
Callback to be notified on USB connection status change.
struct `usb_interface_cfg_data` *interface*

USB interface (Class) handler and storage space.

`uint8_t` num_endpoints

Number of individual endpoints in the device configuration.

struct `usb_ep_cfg_data` *endpoint

Pointer to an array of endpoint structs of length equal to the number of EP associated with the device description, not including control endpoints.

### USB HID Class API

USB device specific part for HID support defined in include/zephyr/usb/class/usb_hid.h.

### API Reference

**Related code samples**

#### USB HID (Human Interface Device)

Use USB HID driver to enumerate as a raw HID device.

---

**group** `usb_hid_device_api`

#### Typedefs

typedef int (*`hid_cb_t`)(const struct `device` *dev, struct usb_setup_packet *setup, int32_t *len, uint8_t **data)

typedef void (*`hid_int_ready_callback`)(const struct `device` *dev)

typedef void (*`hid_protocol_cb_t`)(const struct `device` *dev, uint8_t protocol)

typedef void (*`hid_idle_cb_t`)(const struct `device` *dev, uint16_t report_id)

#### Functions

void `usb_hid_register_device`(const struct `device` *dev, const uint8_t *desc, size_t size, const struct `hid_ops` *op)

Register HID device.

**Parameters**

- dev – [in] Pointer to USB HID device
- desc – [in] Pointer to HID report descriptor
- size – [in] Size of HID report descriptor
- op – [in] Pointer to USB HID device interrupt struct
int hid_int_ep_write(const struct device *dev, const uint8_t *data, uint32_t data_len, uint32_t *bytes_ret)

Write to USB HID interrupt endpoint buffer.

Parameters
- `dev` – [in] Pointer to USB HID device
- `data` – [in] Pointer to data buffer
- `data_len` – [in] Length of data to copy

Returns
0 on success, negative errno code on fail.

int hid_int_ep_read(const struct device *dev, uint8_t *data, uint32_t max_data_len, uint32_t *ret_bytes)

Read from USB HID interrupt endpoint buffer.

Parameters
- `dev` – [in] Pointer to USB HID device
- `data` – [in] Pointer to data buffer
- `max_data_len` – [in] Max length of data to copy
- `ret_bytes` – [out] Number of bytes to copy. If data is NULL and max_data_len is 0 the number of bytes available in the buffer will be returned.

Returns
0 on success, negative errno code on fail.

int usb_hid_set_proto_code(const struct device *dev, uint8_t proto_code)

Set USB HID class Protocol Code.

Should be called before `usb_hid_init()`.

Parameters
- `dev` – [in] Pointer to USB HID device
- `proto_code` – [in] Protocol Code to be used for bInterfaceProtocol

Returns
0 on success, negative errno code on fail.

int usb_hid_init(const struct device *dev)

Initialize USB HID class support.

Parameters
- `dev` – [in] Pointer to USB HID device

Returns
0 on success, negative errno code on fail.

struct hid_ops

#include <usb_hid.h> USB HID device interface.

Binary Device Object Store (BOS) support API

API reference
group usb_bos
    USB Binary Device Object Store support.

Defines

USB_DEVICE_BOS_DESC_DEFINE_CAP
    Helper macro to place the BOS compatibility descriptor in the right memory section.

Enums

define usb_bos_capability_types
    Device capability type codes.
    Values:

    enumerator USB_BOS_CAPABILITY_EXTENSION = 0x02
    enumerator USB_BOS_CAPABILITY_PLATFORM = 0x05

Functions

void usb_bos_register_cap(struct usb_bos_platform_descriptor *hdr)
    Register BOS capability descriptor.
    This function should be used by the application to register BOS capability descriptors
    before the USB device stack is enabled.

    Parameters
        • hdr – [in] Pointer to BOS capability descriptor

 struct usb_bos_capability_lpm
    #include <bos.h> BOS USB 2.0 extension capability descriptor.

 struct usb_bos_platform_descriptor
    #include <bos.h> BOS platform capability descriptor.

 struct usb_bos_capability_webusb
    #include <bos.h> WebUSB specific part of platform capability descriptor.

 struct usb_bos_capability_msos
    #include <bos.h> Microsoft OS 2.0 descriptor specific part of platform capability descriptor.

New experimental USB support
6.5.3 New experimental USB device support

Overview

The new USB device support is experimental. It consists of USB device controller (UDC) driver API and USB device stack (next) API. The new device stack brings support for multiple device controllers, support for multiple configurations, and dynamic registration of class instances to a configuration at runtime. The stack also provides a specific class API that should be used to implement the functions (classes). It will replace USB device support.

If you would like to play around with the new device support, or the new USB support in general, please try usb-shell sample. The sample is mainly to help test the capabilities of the stack and correct implementation of the USB controller drivers.

Supported USB classes

**Bluetooth HCI USB transport layer**  See bluetooth-hci-usb-sample sample for reference. To build the sample for the new device support, set the configuration `-DCONF_FILE=usbd_next_prj.conf` either directly or via west.

**CDC ACM**  CDC ACM implementation has support for multiple instances. Description from CDC ACM also applies to the new implementation. See usb-cdc-acm sample for reference. To build the sample for the new device support, set the configuration `-DCONF_FILE=usbd_next_prj.conf` either directly or via west.

**Mass Storage Class**  See usb-mass sample for reference. To build the sample for the new device support, set the configuration `-DCONF_FILE=usbd_next_prj.conf` either directly or via west.

**Networking**  At the moment only CDC ECM class is implemented and has support for multiple instances. It provides a virtual Ethernet connection between the remote (USB host) and Zephyr network support.

See zperf for reference. To build the sample for the new device support, set the configuration overlay file `-DDEXTRA_CONF_FILE=overlay-usbd_next_ecm.conf` and devicetree overlay file `-DDTC_OVERLAY_FILE="usbd_next_ecm.overlay` either directly or via west.

6.5.4 New USB device support APIs

**USB device controller (UDC) driver API**

The USB device controller driver API is described in include/zephyr/drivers/usb/udc.h and referred to as the UDC driver API.

UDC driver API is experimental and is subject to change without notice. It is a replacement for USB device controller driver API. If you wish to port an existing driver to UDC driver API, or add a new driver, please use drivers/usb/udc/udc_skeleton.c as a starting point.

**API reference**

*group udc_api*

New USB device controller (UDC) driver API.
Functions

static inline bool udc_is_initialized(const struct device *dev)

Checks whether the controller is initialized.

Parameters
  • dev – [in] Pointer to device struct of the driver instance

Returns
  true if controller is initialized, false otherwise

static inline bool udc_is_enabled(const struct device *dev)

Checks whether the controller is enabled.

Parameters
  • dev – [in] Pointer to device struct of the driver instance

Returns
  true if controller is enabled, false otherwise

static inline bool udc_is_suspended(const struct device *dev)

Checks whether the controller is suspended.

Parameters
  • dev – [in] Pointer to device struct of the driver instance

Returns
  true if controller is suspended, false otherwise

int udc_init(const struct device *dev, udc_event_cb_t event_cb)

Initialize USB device controller.

Initialize USB device controller and control IN/OUT endpoint. After initialization con-
troller driver should be able to detect power state of the bus and signal power state
changes.

Parameters
  • dev – [in] Pointer to device struct of the driver instance
  • event_cb – [in] Event callback from the higher layer (USB device stack)

Return values
  • -EINVAL – on parameter error (no callback is passed)
  • -EALREADY – already initialized

Returns
  0 on success, all other values should be treated as error.

int udc_enable(const struct device *dev)

Enable USB device controller.

Enable powered USB device controller and allow host to recognize and enumerate the
device.

Parameters
  • dev – [in] Pointer to device struct of the driver instance

Return values
  • -EPERM – controller is not initialized
  • -EALREADY – already enabled
Returns
0 on success, all other values should be treated as error.

int udc_disable(const struct device *dev)
Disable USB device controller.
Disable enabled USB device controller. The driver should continue to detect power state changes.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Return values
-EALREADY – already disabled

Returns
0 on success, all other values should be treated as error.

int udc_shutdown(const struct device *dev)
Poweroff USB device controller.
Shut down the controller completely to reduce energy consumption or to change the role of the controller.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Return values
-EALREADY – controller is not initialized

Returns
0 on success, all other values should be treated as error.

static inline struct udc_device_caps udc_caps(const struct device *dev)
Get USB device controller capabilities.
Obtain the capabilities of the controller such as full speed (FS), high speed (HS), and more.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Returns
USB device controller capabilities.

enum udc_bus_speed udc_device_speed(const struct device *dev)
Get actual USB device speed.
The function should be called after the reset event to determine the actual bus speed.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Returns
USB device controller capabilities.

static inline int udc_set_address(const struct device *dev, const uint8_t addr)
Set USB device address.
Set address of enabled USB device.

Parameters
• dev – [in] Pointer to device struct of the driver instance
• addr – [in] USB device address
Return values
- EPERM – controller is not enabled (or not initialized)

Returns
0 on success, all other values should be treated as error.

static inline int udc_test_mode(const struct device *dev, const uint8_t mode, const bool dryrun)

Enable Test Mode.
For compliance testing, high-speed controllers must support test modes. A particular
test is enabled by a SetFeature(TEST_MODE) request. To disable a test mode, device
needs to be power cycled.

Parameters
- dev – [in] Pointer to device struct of the driver instance
- mode – [in] Test mode
- dryrun – [in] Verify that a particular mode can be enabled, but do not
  enable test mode

Return values
- ENOTSUP – Test mode is not supported

Returns
0 on success, all other values should be treated as error.

static inline int udc_host_wakeup(const struct device *dev)

Initiate host wakeup procedure.
Initiate host wakeup. Only possible when the bus is suspended.

Parameters
- dev – [in] Pointer to device struct of the driver instance

Return values
- EPERM – controller is not enabled (or not initialized)

Returns
0 on success, all other values should be treated as error.

int udc_ep_try_config(const struct device *dev, const uint8_t ep, const uint8_t attributes,
                      uint16_t *const mps, const uint8_t interval)

Try an endpoint configuration.
Try an endpoint configuration based on endpoint descriptor. This function may modify
wMaxPacketSize descriptor fields of the endpoint. All properties of the descriptor, such
as direction, and transfer type, should be set correctly. If wMaxPacketSize value is zero,
 it will be updated to maximum buffer size of the endpoint.

Parameters
- dev – [in] Pointer to device struct of the driver instance
- ep – [in] Endpoint address (same as bEndpointAddress)
- attributes – [in] Endpoint attributes (same as bmAttributes)
- mps – [in] Maximum packet size (same as wMaxPacketSize)
- interval – [in] Polling interval (same as bInterval)

Return values
- EINVAL – on wrong parameter
- ENOTSUP – endpoint configuration not supported
Configure and enable endpoint.

Parameters

- `dev` – [in] Pointer to device struct of the driver instance
- `ep` – [in] Endpoint address (same as bEndpointAddress)
- `attributes` – [in] Endpoint attributes (same as bmAttributes)
- `mps` – [in] Maximum packet size (same as wMaxPacketSize)
- `interval` – [in] Polling interval (same as bInterval)

Return values

- `-EINVAL` – on wrong parameter (control IN/OUT endpoint)
- `-EPERM` – controller is not initialized
- `-ENODEV` – endpoint configuration not found
- `-EALREADY` – endpoint is already enabled

Returns

0 on success, all other values should be treated as error.

Configure and make an endpoint ready for use. Valid for all endpoints except control IN/OUT.

disable

Disable endpoint.

Parameters

- `dev` – [in] Pointer to device struct of the driver instance
- `ep` – [in] Endpoint address

Return values

- `-EINVAL` – on wrong parameter (control IN/OUT endpoint)
- `-ENODEV` – endpoint configuration not found
- `-EALREADY` – endpoint is already disabled
- `-EPERM` – controller is not initialized

Returns

0 on success, all other values should be treated as error.

Halt endpoint.

Parameters

- `dev` – [in] Pointer to device struct of the driver instance
- `ep` – [in] Endpoint address

Return values

- `-EINVAL` – on wrong parameter (control IN/OUT endpoint)
- `-ENODEV` – endpoint configuration not found
- `-EALREADY` – endpoint is already disabled
- `-EPERM` – controller is not initialized

Returns

0 on success, all other values should be treated as error.
• -ENOMEM – endpoint configuration not found
• -ENOTSUP – not supported (e.g. isochronous endpoint)
• -EPERM – controller is not enabled

Returns
0 on success, all other values should be treated as error.

int udc_ep_clear_halt(const struct device *dev, const uint8_t ep)
Clear endpoint halt.
Valid for all endpoints.

Parameters
• dev – [in] Pointer to device struct of the driver instance
• ep – [in] Endpoint address

Return values
• -ENOMEM – endpoint configuration not found
• -ENOTSUP – not supported (e.g. isochronous endpoint)
• -EPERM – controller is not enabled

Returns
0 on success, all other values should be treated as error.

int udc_ep_enqueue(const struct device *dev, struct net_buf *const buf)
Queue USB device controller request.
Add request to the queue. If the queue is empty, the request buffer can be claimed by
the controller immediately.

Parameters
• dev – [in] Pointer to device struct of the driver instance
• buf – [in] Pointer to UDC request buffer

Return values
• -ENOMEM – endpoint configuration not found
• -EACCES – endpoint is not enabled (TBD)
• -EBUSY – request can not be queued
• -EPERM – controller is not initialized

Returns
0 on success, all other values should be treated as error.

int udc_ep_dequeue(const struct device *dev, const uint8_t ep)
Remove all USB device controller requests from endpoint queue.
UDC_EVT_EP_REQUEST event will be generated when the driver releases claimed
buffer, no new requests will be claimed, all requests in the queue will passed as
chained list of the event variable buf. The endpoint queue is empty after that.

Parameters
• dev – [in] Pointer to device struct of the driver instance
• ep – [in] Endpoint address

Return values
• -ENOMEM – endpoint configuration not found
Zephyr Project Documentation, Release 3.6.0-rc3

- EACCES – endpoint is not disabled
- EPERM – controller is not initialized

Returns
0 on success, all other values should be treated as error.

```c
struct net_buf *udc_ep_buf_alloc(const struct device *dev, const uint8_t ep, const size_t size)
```
Allocate UDC request buffer.
Allocate a new buffer from common request buffer pool.

Parameters
- `dev` – [in] Pointer to device struct of the driver instance
- `ep` – [in] Endpoint address
- `size` – [in] Size of the request buffer

Returns
pointer to allocated request or NULL on error.

```c
int udc_ep_buf_free(const struct device *dev, struct net_buf *const buf)
```
Free UDC request buffer.
Put the buffer back into the request buffer pool.

Parameters
- `dev` – [in] Pointer to device struct of the driver instance
- `buf` – [in] Pointer to UDC request buffer

Returns
0 on success, all other values should be treated as error.

```c
static inline void udc_ep_buf_set_zlp(struct net_buf *const buf)
```
Set ZLP flag in requests metadata.
The controller should send a ZLP at the end of the transfer.

Parameters
- `buf` – [in] Pointer to UDC request buffer

```c
static inline struct udc_buf_info *udc_get_buf_info(const struct net_buf *const buf)
```
Get requests metadata.

Parameters
- `buf` – [in] Pointer to UDC request buffer

Returns
pointer to metadata structure.

USB device stack (next) API

New USB device stack API is experimental and is subject to change without notice.

API reference

Related code samples

Console over USB CDC ACM
Output "Hello World!" to the console over USB CDC ACM.
USB CDC-ACM
Use USB CDC-ACM driver to implement a serial port echo.

USB CDC-ACM composite
Implement a composite USB device exposing two serial ports using USB CDC-ACM driver.

USB DFU (Device Firmware Upgrade)
Implement device firmware upgrade using the USB DFU class driver.

USB HID (Human Interface Device)
Use USB HID driver to enumerate as a raw HID device.

USB Mass Storage
Expose board's RAM or FLASH as a USB disk using USB Mass Storage driver.

USB shell
Use shell commands to interact with USB device stack.

WebUSB
Receive and echo data from a web page using WebUSB API.

group usbd_api
New USB device stack core API.

Defines

USB_BSTRING_LENGTH(s)
USB_STRING_DESCRIPTOR_LENGTH(s)
USBD_NUMOF_INTERFACES_MAX
USBD_CCTX_REGISTERED
USB Class instance registered flag.
USBD_DEVICE_DEFINE(device_name, uhc_dev, vid, pid)
USBD_CONFIGURATION_DEFINE(name, attrib, power)
USBD_DESC_LANG_DEFINE(name)
Create a string descriptor node and language string descriptor.
This macro defines a descriptor node and a string descriptor that, when added to the device context, is automatically used as the language string descriptor zero. Both descriptor node and descriptor are defined with static-storage-class specifier. Default and currently only supported language ID is 0x0409 English (United States). If string descriptors are used, it is necessary to add this descriptor as the first one to the USB device context.

Parameters

• name – Language string descriptor node identifier.

USBD_DESC_STRING_DEFINE(d_name, d_string, d_utype)

USBD_DESC_MANUFACTURER_DEFINE(d_name, d_string)
Create a string descriptor node and manufacturer string descriptor.
This macro defines a descriptor node and a string descriptor that, when added to the device context, is automatically used as the manufacturer string descriptor. Both descriptor node and descriptor are defined with static-storage-class specifier.
Parameters

- d_name – String descriptor node identifier.
- d_string – ASCII7 encoded manufacturer string literal

`USBD_DESC_PRODUCT_DEFINE(d_name, d_string)`

Create a string descriptor node and product string descriptor.

This macro defines a descriptor node and a string descriptor that, when added to the
device context, is automatically used as the product string descriptor. Both descriptor
node and descriptor are defined with static-storage-class specifier.

Parameters

- d_name – String descriptor node identifier.
- d_string – ASCII7 encoded product string literal

`USBD_DESC_SERIAL_NUMBER_DEFINE(d_name, d_string)`

Create a string descriptor node and serial number string descriptor.

This macro defines a descriptor node and a string descriptor that, when added to the
device context, is automatically used as the serial number string descriptor. The string
literal parameter is used as a placeholder, the unique number is obtained from hwinfo.
Both descriptor node and descriptor are defined with static-storage-class specifier.

Parameters

- d_name – String descriptor node identifier.
- d_string – ASCII7 encoded serial number string literal placeholder

`USBD_DEFINE_CLASS(class_name, class_api, class_data)`

`VENDOR_REQ_DEFINE(_reqs, _len)`

Helper to declare request table of `usbd_cctx_vendor_req`.

Parameters

- _reqs – Pointer to the vendor request field
- _len – Number of supported vendor requests

`USBD_VENDOR_REQ(_reqs...)`

Helper to declare supported vendor requests.

Parameters

- _reqs – Variable number of vendor requests

Enums

enum usbd_desc_usage_type

Values:

- enumerator USBD_DUT_STRING_LANG
- enumerator USBD_DUT_STRING_MANUFACTURER
- enumerator USBD_DUT_STRING_PRODUCT
enumerator USBD_OUT_STRING_SERIAL_NUMBER

enumerator USBD_OUT_STRING_INTERFACE

enum usbd_ch9_state
    USB device support middle layer runtime state.
    Part of USB device states without suspended and powered states, as it is better to track
    them separately.
    Values:
        enumerator USBD_STATE_DEFAULT = 0
        enumerator USBD_STATE_ADDRESS
        enumerator USBD_STATE_CONFIGURED

Functions

int usbd_add_descriptor(struct usbd_contex *uds_ctx, struct usbd_desc_node *dn)
Add common USB descriptor.
Add common descriptor like string or bos.
    Parameters
        • uds_ctx – [in] Pointer to USB device support context
        • dn – [in] Pointer to USB descriptor node
    Returns
        0 on success, other values on fail.
int usbd_add_configuration(struct usbd_contex *uds_ctx, struct usbd_config_node *cd)
Add a USB device configuration.
    Parameters
        • uds_ctx – [in] Pointer to USB device support context
        • cd – [in] Pointer to USB configuration node
    Returns
        0 on success, other values on fail.
int usbd_register_class(struct usbd_contex *uds_ctx, const char *name, uint8_t cfg)
Register an USB class instance.
An USB class implementation can have one or more instances. To identify the instances
we use device drivers API. Device names have a prefix derived from the name of the
class, for example CDC_ACM for CDC ACM class instance, and can also be easily iden-
tified in the shell. Class instance can only be registered when the USB device stack is
disabled. Registered instances are initialized at initialization of the USB device stack,
and the interface descriptors of each instance are adapted to the whole context.
    Parameters
        • uds_ctx – [in] Pointer to USB device support context
        • name – [in] Class instance name
• cfg – [in] Configuration value (similar to bConfigurationValue)

**Returns**
0 on success, other values on fail.

```c
int usbd_unregister_class(struct usbd_context *uds_ctx, const char *name, uint8_t cfg)
```

Unregister an USB class instance.

USB class instance will be removed and will not appear on the next start of the stack. Instance can only be unregistered when the USB device stack is disabled.

**Parameters**
- uds_ctx – [in] Pointer to USB device support context
- name – [in] Class instance name
- cfg – [in] Configuration value (similar to bConfigurationValue)

**Returns**
0 on success, other values on fail.

```c
int usbd_init(struct usbd_context *uds_ctx)
```

Initialize USB device.

Initialize USB device descriptors and configuration, initialize USB device controller. Class instances should be registered before they are involved. However, the stack should also initialize without registered instances, even if the host would complain about missing interfaces.

**Parameters**
- uds_ctx – [in] Pointer to USB device support context

**Returns**
0 on success, other values on fail.

```c
int usbd_enable(struct usbd_context *uds_ctx)
```

Enable the USB device support and registered class instances.

This function enables the USB device support.

**Parameters**
- uds_ctx – [in] Pointer to USB device support context

**Returns**
0 on success, other values on fail.

```c
int usbd_disable(struct usbd_context *uds_ctx)
```

Disable the USB device support.

This function disables the USB device support.

**Parameters**
- uds_ctx – [in] Pointer to USB device support context

**Returns**
0 on success, other values on fail.

```c
int usbd_shutdown(struct usbd_context *const uds_ctx)
```

Shutdown the USB device support.

This function completely disables the USB device support.

**Parameters**
- uds_ctx – [in] Pointer to USB device support context
Returns
0 on success, other values on fail.

int usbd_ep_set_halt(struct usbd_contex *uds_ctx, uint8_t ep)
Halt endpoint.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• ep – [in] Endpoint address

Returns
0 on success, or error from udc_ep_set_halt()

int usbd_ep_clear_halt(struct usbd_contex *uds_ctx, uint8_t ep)
Clear endpoint halt.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• ep – [in] Endpoint address

Returns
0 on success, or error from udc_ep_clear_halt()

bool usbd_ep_is_halted(struct usbd_contex *uds_ctx, uint8_t ep)
Checks whether the endpoint is halted.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• ep – [in] Endpoint address

Returns
true if endpoint is halted, false otherwise

struct net_buf *usbd_ep_ctrl_buf_alloc(struct usbd_contex *const uds_ctx, const uint8_t ep, const size_t size)
Allocate buffer for USB device control request.
Allocate a new buffer from controller's driver buffer pool.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• ep – [in] Endpoint address
• size – [in] Size of the request buffer

Returns
pointer to allocated request or NULL on error.

struct net_buf *usbd_ep_buf_alloc(const struct usbd_class_node *const c_nd, const uint8_t ep, const size_t size)
Allocate buffer for USB device request.
Allocate a new buffer from controller's driver buffer pool.

Parameters
• c_nd – [in] Pointer to USB device class node
• ep – [in] Endpoint address
• size – [in] Size of the request buffer
Returns
pointer to allocated request or NULL on error.

int usbd_ep_ctrl_enqueue(struct usbd_contex *const uds_ctx, struct net_buf *const buf)
Queue USB device control request.
Add control request to the queue.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• buf – [in] Pointer to UDC request buffer

Returns
0 on success, all other values should be treated as error.

int usbd_ep_enqueue(const struct usbd_class_node *const c_nd, struct net_buf *const buf)
Queue USB device request.
Add request to the queue.

Parameters
• c_nd – [in] Pointer to USB device class node
• buf – [in] Pointer to UDC request buffer

Returns
0 on success, or error from udc_ep_enqueue()

int usbd_ep_dequeue(struct usbd_contex *uds_ctx, const uint8_t ep)
Remove all USB device controller requests from endpoint queue.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• ep – [in] Endpoint address

Returns
0 on success, or error from udc_ep_dequeue()

int usbd_ep_buf_free(struct usbd_contex *uds_ctx, struct net_buf *buf)
Free USB device request buffer.
Put the buffer back into the request buffer pool.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• buf – [in] Pointer to UDC request buffer

Returns
0 on success, all other values should be treated as error.

bool usbd_is_suspended(struct usbd_contex *uds_CTX)
Checks whether the USB device controller is suspended.

Parameters
• uds_ctx – [in] Pointer to USB device support context

Returns
ture if endpoint is halted, false otherwise
int usbd_wakeup_request(struct usbd_contex *uds_ctx)
    Initiate the USB remote wakeup (TBD)

    Returns
    0 on success, other values on fail.

int usbd_device_set_bcd(struct usbd_contex *const uds_ctx, const uint16_t bcd)
    Set USB device descriptor value bcdUSB.

    Parameters
    • uds_ctx – [in] Pointer to USB device support context
    • bcd – [in] bcdUSB value

    Returns
    0 on success, other values on fail.

int usbd_device_set_vid(struct usbd_contex *const uds_ctx, const uint16_t vid)
    Set USB device descriptor value idVendor.

    Parameters
    • uds_ctx – [in] Pointer to USB device support context
    • vid – [in] idVendor value

    Returns
    0 on success, other values on fail.

int usbd_device_set_pid(struct usbd_contex *const uds_ctx, const uint16_t pid)
    Set USB device descriptor value idProduct.

    Parameters
    • uds_ctx – [in] Pointer to USB device support context
    • pid – [in] idProduct value

    Returns
    0 on success, other values on fail.

int usbd_device_set_code_triple(struct usbd_contex *const uds_ctx, const uint8_t base_class, const uint8_t subclass, const uint8_t protocol)
    Set USB device descriptor code triple Base Class, SubClass, and Protocol.

    Parameters
    • uds_ctx – [in] Pointer to USB device support context
    • base_class – [in] bDeviceClass value
    • subclass – [in] bDeviceSubClass value
    • protocol – [in] bDeviceProtocol value

    Returns
    0 on success, other values on fail.

int usbd_config_attrib_rwup(struct usbd_contex *const uds_ctx, const uint8_t cfg, const bool enable)
    Setup USB device configuration attribute Remote Wakeup.

    Parameters
    • uds_ctx – [in] Pointer to USB device support context
    • cfg – [in] Configuration number
    • enable – [in] Sets attribute if true, clears it otherwise
Returns
0 on success, other values on fail.

int usbd_config_attrib_self(struct usbd_context *const uds_ctx, const uint8_t cfg, const bool enable)
Setup USB device configuration attribute Self-powered.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• cfg – [in] Configuration number
• enable – [in] Sets attribute if true, clears it otherwise

Returns
0 on success, other values on fail.

int usbd_config_maxpower(struct usbd_context *const uds_ctx, const uint8_t cfg, const uint8_t power)
Setup USB device configuration power consumption.

Parameters
• uds_ctx – [in] Pointer to USB device support context
• cfg – [in] Configuration number
• power – [in] Maximum power consumption value (bMaxPower)

Returns
0 on success, other values on fail.

struct usbd_desc_node
#include <usbd.h> Descriptor node.
Descriptor node is used to manage descriptors that are not directly part of a structure, such as string or bos descriptors.

Public Members

sys_dnode_t node
  slist node struct

unsigned int idx
  Descriptor index, required for string descriptors.

unsigned int utype
  Descriptor usage type (not bDescriptorType)

unsigned int utf16le
  If not set, string descriptor must be converted to UTF16LE.

unsigned int custom_sn
  If not set, device stack obtains SN using the hwininfo API.

void *desc
  Pointer to a descriptor.
struct usbd_config_node
#include <usbd.h> Device configuration node.

Configuration node is used to manage device configurations, at least one configuration is required. It does not have an index, instead bConfigurationValue of the descriptor is used for identification.

Public Members

sys_snode_t node
    slist node struct

void *desc
    Pointer to configuration descriptor.

sys_slist_t class_list
    List of registered classes (functions)

struct usbd_ch9_data
#include <usbd.h> USB device support middle layer runtime data.

Public Members

struct usb_setup_packet setup
    Setup packet, up-to-date for the respective control request.

int ctrl_type
    Control type, internally used for stage verification.

enum usbd_ch9_state state
    Protocol state of the USB device stack.

uint32_t ep_halt
    Halted endpoints bitmap.

uint8_t configuration
    USB device stack selected configuration.

bool post_status
    Post status stage work required, e.g. set new device address

uint8_t alternate[16U]
    Array to track interfaces alternate settings.

struct usbd_status
#include <usbd.h> USB device support status.
Public Members

unsigned int initialized
  USB device support is initialized.

unsigned int enabled
  USB device support is enabled.

unsigned int suspended
  USB device is suspended.

unsigned int rwup
  USB remote wake-up feature is enabled.

struct usbd_contex
  #include <usbd.h> USB device support runtime context.
  Main structure that organizes all descriptors, configuration, and interfaces. An UDC device must be assigned to this structure.

Public Members

cnst char *name
  Name of the USB device.

struct k_mutex mutex
  Access mutex.

cnst struct device *dev
  Pointer to UDC device.

struct usbd_ch9_data ch9_data
  Middle layer runtime data.

sys_dlist_t descriptors
  slist to manage descriptors like string, bos

sys_slist_t configs
  slist to manage device configurations

struct usbd_status status
  Status of the USB device support.

void *desc
  Pointer to device descriptor.

struct usbd_cctx_vendor_req
  #include <usbd.h> Vendor Requests Table.
Public Members

const uint8_t *reqs
   Array of vendor requests supported by the class.

uint8_t len
   Length of the array.

struct usbd_class_api
   #include <usbd.h> USB device support class instance API.

Public Members

void (*feature_halt)(struct usbd_class_node *const node, uint8_t ep, bool halted)
   Feature halt state update handler.

void (*update)(struct usbd_class_node *const node, uint8_t iface, uint8_t alternate)
   Configuration update handler.

int (*control_to_dev)(struct usbd_class_node *const node, const struct usb_setup_packet *const setup, const struct net_buf *const buf)
   USB control request handler to device.

int (*control_to_host)(struct usbd_class_node *const node, const struct usb_setup_packet *const setup, struct net_buf *const buf)
   USB control request handler to host.

int (*request)(struct usbd_class_node *const node, struct net_buf *buf, int err)
   Endpoint request completion event handler.

void (*suspended)(struct usbd_class_node *const node)
   USB power management handler suspended.

void (*resumed)(struct usbd_class_node *const node)
   USB power management handler resumed.

void (*sof)(struct usbd_class_node *const node)
   Start of Frame.

void (*enable)(struct usbd_class_node *const node)
   Class associated configuration is selected.

void (*disable)(struct usbd_class_node *const node)
   Class associated configuration is disabled.

int (*init)(struct usbd_class_node *const node)
   Initialization of the class implementation.
void (*shutdown)(struct usbd_class_node *const node)
    Shutdown of the class implementation.

struct usbd_class_data
    #include <usbd.h> USB device support class data.

Public Members

struct usbd_contex *uds_ctx
    Pointer to USB device stack context structure.

void *desc
    Pointer to a class implementation descriptor that should end with a nil descriptor
    (bLength = 0 and bDescriptorType = 0).

const struct usbd_cctx_vendor_req *v_reqs
    Supported vendor request table, can be NULL.

uint32_t ep_assigned
    Bitmap of all endpoints assigned to the instance.
    The IN endpoints are mapped in the upper halfword.

uint32_t ep_active
    Bitmap of the enabled endpoints of the instance.
    The IN endpoints are mapped in the upper halfword.

uint32_t iface_bm
    Bitmap of the bInterfaceNumbers of the class instance.

atomic_t state
    Variable to store the state of the class instance.

void *priv
    Pointer to private data.

struct usbd_class_node
    #include <usbd.h>

Public Members

sys_snode_t node
    Node information for the slist.

const char *name
    Name of the USB device class instance.
const struct usbd_class_api *api
   Pointer to device support class API.

struct usbd_class_data *data
   Pointer to USB device support class data.

6.5.5 USB host support APIs

USB host controller (UHC) driver API

The USB host controller driver API is described in include/zephyr/drivers/usb/uhc.h and referred to as the UHC driver API.

UHC driver API is experimental and is subject to change without notice.

Driver API reference

group uhc_api
   USB host controller (UHC) driver API.

Defines

UHC_STATUS_INITIALIZED
   Controller is initialized by uhc_init()

UHC_STATUS_ENABLED
   Controller is enabled and all API functions are available.

Typedefs

typedef int (*uhc_event_cb_t)(const struct device *dev, const struct uhc_event *const event)
   Callback to submit UHC event to higher layer.
   At the higher level, the event is to be inserted into a message queue.

   Param dev
      [in] Pointer to device struct of the driver instance

   Param event
      [in] Point to event structure

   Return
      0 on success, all other values should be treated as error.

Enums
enum uhc_control_stage
    USB control transfer stage.
    
    Values:
    
    enumerator UHC_CONTROL_STAGE_SETUP = 0
    enumerator UHC_CONTROL_STAGE_DATA
    enumerator UHC_CONTROL_STAGE_STATUS

enum uhc_event_type
    USB host controller event types.
    
    Values:
    
    enumerator UHC_EVT_DEV_CONNECTED_LS
        Low speed device connected.
    enumerator UHC_EVT_DEV_CONNECTED_FS
        Full speed device connected.
    enumerator UHC_EVT_DEV_CONNECTED_HS
        High speed device connected.
    enumerator UHC_EVT_DEV_REMOVED
        Device (peripheral) removed.
    enumerator UHC_EVT_RESETED
        Bus reset operation finished.
    enumerator UHC_EVT_SUSPENDED
        Bus suspend operation finished.
    enumerator UHC_EVT_RESUMED
        Bus resume operation finished.
    enumerator UHC_EVT_RWUP
        Remote wakeup signal.
    enumerator UHC_EVT_EP_REQUEST
        Endpoint request result event.
    enumerator UHC_EVT_ERROR
        Non-correctable error event, requires attention from higher levels or application.
static inline bool uhc_is_initialized(const struct device *dev)
Checks whether the controller is initialized.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Returns
ture if controller is initialized, false otherwise

static inline bool uhc_is_enabled(const struct device *dev)
Checks whether the controller is enabled.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Returns
ture if controller is enabled, false otherwise

static inline int uhc_bus_reset(const struct device *dev)
Reset USB bus.
Perform USB bus reset, controller may emit UHC_EVT_RESETED at the end of reset signaling.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Return values
-EBUSY – if the controller is already performing a bus operation

Returns
0 on success, all other values should be treated as error.

static inline int uhc_sof_enable(const struct device *dev)
Enable Start of Frame generator.

Enable SOF generator.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Return values
-EALREADY – if already enabled

Returns
0 on success, all other values should be treated as error.

static inline int uhc_bus_suspend(const struct device *dev)
Suspend USB bus.
Disable SOF generator and emit UHC_EVT_SUSPENDED event when USB bus is suspended.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Return values
-EALREADY – if already suspended

Returns
0 on success, all other values should be treated as error.
static inline int uhc_bus_resume(const struct device *dev)
    Resume USB bus.
    Signal resume for at least 20ms, emit UHC_EVT_RESUMED at the end of USB bus resume signaling. The SoF generator should subsequently start within 3ms.

Parameters
• dev – [in] Pointer to device struct of the driver instance

Return values
-EBUSY – if the controller is already performing a bus operation

Returns
0 on success, all other values should be treated as error.

struct uhc_transfer *uhc_xfer_alloc(const struct device *dev, const uint8_t addr, const uint8_t ep, const uint8_t attrib, const uint16_t mps, const uint16_t timeout, void *const udev, void *const cb)

Allocate UHC transfer.
Allocate a new transfer from common transfer pool. Transfer has no buffer after allocation, but can be allocated and added from different pools.

Parameters
• dev – [in] Pointer to device struct of the driver instance
• addr – [in] Device (peripheral) address
• ep – [in] Endpoint address
• attrib – [in] Endpoint attributes
• mps – [in] Maximum packet size of the endpoint
• timeout – [in] Timeout in number of frames
• udev – [in] Opaque pointer to USB device
• cb – [in] Transfer completion callback

Returns
pointer to allocated transfer or NULL on error.

struct uhc_transfer *uhc_xfer_alloc_with_buf(const struct device *dev, const uint8_t addr, const uint8_t ep, const uint8_t attrib, const uint16_t mps, const uint16_t timeout, void *const udev, void *const cb, size_t size)

Allocate UHC transfer with buffer.
Allocate a new transfer from common transfer pool with buffer.

Parameters
• dev – [in] Pointer to device struct of the driver instance
• addr – [in] Device (peripheral) address
• ep – [in] Endpoint address
• attrib – [in] Endpoint attributes
• mps – [in] Maximum packet size of the endpoint
• timeout – [in] Timeout in number of frames
• udev – [in] Opaque pointer to USB device
• **cb** – [in] Transfer completion callback
• **size** – [in] Size of the buffer

**Returns**
pointer to allocated transfer or NULL on error.

```c
int uhc_xfer_free(const struct device *dev, struct uhc_transfer *const xfer)
```
Free UHC transfer and any buffers.
Free any buffers and put the transfer back into the transfer pool.

**Parameters**
• **dev** – [in] Pointer to device struct of the driver instance
• **xfer** – [in] Pointer to UHC transfer

**Returns**
0 on success, all other values should be treated as error.

```c
int uhc_xfer_buf_add(const struct device *dev, struct uhc_transfer *const xfer, struct net_buf *buf)
```
Add UHC transfer buffer.
Add a previously allocated buffer to the transfer.

**Parameters**
• **dev** – [in] Pointer to device struct of the driver instance
• **xfer** – [in] Pointer to UHC transfer
• **buf** – [in] Pointer to UHC request buffer

**Returns**
pointer to allocated request or NULL on error.

```c
struct net_buf *uhc_xfer_buf_alloc(const struct device *dev, const size_t size)
```
Allocate UHC transfer buffer.
Allocate a new buffer from common request buffer pool and assign it to the transfer if the xfer parameter is not NULL.

**Parameters**
• **dev** – [in] Pointer to device struct of the driver instance
• **size** – [in] Size of the request buffer

**Returns**
pointer to allocated request or NULL on error.

```c
void uhc_xfer_buf_free(const struct device *dev, struct net_buf *const buf)
```
Free UHC request buffer.
Put the buffer back into the request buffer pool.

**Parameters**
• **dev** – [in] Pointer to device struct of the driver instance
• **buf** – [in] Pointer to UHC request buffer

```c
int uhc_ep_enqueue(const struct device *dev, struct uhc_transfer *const xfer)
```
Queue USB host controller transfer.
Add transfer to the queue. If the queue is empty, the transfer can be claimed by the controller immediately.

**Parameters**
\begin{itemize}
  \item \texttt{dev} – \texttt{[in]} Pointer to device struct of the driver instance
  \item \texttt{xfer} – \texttt{[in]} Pointer to UHC transfer
\end{itemize}

\textbf{Return values}
- \texttt{EPERM} – controller is not initialized

\textbf{Returns}
0 on success, all other values should be treated as error.

\begin{verbatim}
int uhc_ep_dequeue(const struct device *dev, struct uhc_transfer *const xfer)
Remove a USB host controller transfers from queue.
Not implemented yet.
\end{verbatim}

\textbf{Parameters}
\begin{itemize}
  \item \texttt{dev} – \texttt{[in]} Pointer to device struct of the driver instance
  \item \texttt{xfer} – \texttt{[in]} Pointer to UHC transfer
\end{itemize}

\textbf{Return values}
- \texttt{EPERM} – controller is not initialized

\textbf{Returns}
0 on success, all other values should be treated as error.

\begin{verbatim}
int uhc_init(const struct device *dev, uhc_event_cb_t event_cb)
Initialize USB host controller.
\end{verbatim}

\textbf{Parameters}
\begin{itemize}
  \item \texttt{dev} – \texttt{[in]} Pointer to device struct of the driver instance
  \item \texttt{event_cb} – \texttt{[in]} Event callback from the higher layer (USB host stack)
\end{itemize}

\textbf{Return values}
\begin{itemize}
  \item \texttt{EINVAL} – on parameter error (no callback is passed)
  \item \texttt{EALREADY} – already initialized
\end{itemize}

\textbf{Returns}
0 on success, all other values should be treated as error.

\begin{verbatim}
int uhc_enable(const struct device *dev)
Enable USB host controller.
Enable powered USB host controller and allow host stack to recognize and enumerate devices.
\end{verbatim}

\textbf{Parameters}
\begin{itemize}
  \item \texttt{dev} – \texttt{[in]} Pointer to device struct of the driver instance
\end{itemize}

\textbf{Return values}
\begin{itemize}
  \item \texttt{EPERM} – controller is not initialized
  \item \texttt{EALREADY} – already enabled
\end{itemize}

\textbf{Returns}
0 on success, all other values should be treated as error.

\begin{verbatim}
int uhc_disable(const struct device *dev)
Disable USB host controller.
Disable enabled USB host controller.
\end{verbatim}
• **dev** – [in] Pointer to device struct of the driver instance

**Return values**
- **EALREADY** – already disabled

**Returns**
0 on success, all other values should be treated as error.

```c
int uhc_shutdown(const struct device *dev)
```
Poweroff USB host controller.

Shut down the controller completely to reduce energy consumption or to change the role of the controller.

**Parameters**

• **dev** – [in] Pointer to device struct of the driver instance

**Return values**
- **EALREADY** – controller is already uninitialized

**Returns**
0 on success, all other values should be treated as error.

```c
static inline struct uhc_device_caps uhc_caps(const struct device *dev)
```
Get USB host controller capabilities.

Obtain the capabilities of the controller such as high speed (HS), and more.

**Parameters**

• **dev** – [in] Pointer to device struct of the driver instance

**Returns**
USB host controller capabilities.

```c
struct uhc_transfer
```

#include <uhc.h> UHC endpoint buffer info.

This structure is mandatory for all UHC request. It contains the meta data about the request and FIFOs to store *net_buf* structures for each request.

The members of this structure should not be used directly by a higher layer (host stack).

**Public Members**

```c
sys_dnode_t node
dlist node
```

```c
uint8_t setup_pkt[8]
```
Control transfer setup packet.

```c
struct net_buf *buf
```
Transfer data buffer.

```c
uint8_t addr
```
Device (peripheral) address.

```c
uint8_t ep
```
Endpoint to which request is associated.
uint8_t attrib
   Endpoint attributes (TBD)

uint16_t mps
   Maximum packet size.

uint16_t timeout
   Timeout in number of frames.

unsigned int queued
   Flag marks request buffer is queued.

unsigned int stage
   Control stage status, up to the driver to use it or not.

void *udev
   Pointer to USB device (opaque for the UHC)

void *cb
   Pointer to transfer completion callback (opaque for the UHC)

int err
   Transfer result, 0 on success, other values on error.

struct uhc_event
   #include <uhc.h> USB host controller event.
   Common structure for all events that originate from the UHC driver and are passed to
   higher layer using message queue and a callback (uhc_event_cb_t) provided by higher
   layer during controller initialization (uhc_init).

Public Members

sys_snodet node
   slist node for the message queue

enum uhc_event_type type
   Event type.

int status
   Event status value, if any.

struct uhc_transfer *xfer
   Pointer to request used only for UHC_EVT_EP_REQUEST.

const struct device *dev
   Pointer to controller’s device struct.
struct uhc_device_caps
#include <uhc.h> USB host controller capabilities.
This structure is mainly intended for the USB host stack.

Public Members

uint32_t hs
USB high speed capable controller.

struct uhc_data
#include <uhc.h> Common UHC driver data structure.
Mandatory structure for each UHC controller driver. To be implemented as device's private data (device->data).

Public Members

struct uhc_device_caps caps
Controller capabilities.

struct k_mutex mutex
Driver access mutex.

sys_dlist_t ctrl_xfers
dlist for control transfers

sys_dlist_t bulk_xfers
dlist for bulk transfers

uhc_event_cb_t event_cb
Callback to submit an UHC event to upper layer.

atomic_t status
USB host controller status.

void *priv
Driver private data.

USB Power Delivery support

6.5.6 USB-C device stack

The USB-C device stack is a hardware independent interface between a Type-C Port Controller (TCPC) and customer applications. It is a port of the Google ChromeOS Type-C Port Manager (TCPM) stack. It provides the following functionalities:

- Uses the APIs provided by the Type-C Port Controller drivers to interact with the Type-C Port Controller.
• Provides a programming interface that’s used by a customer applications. The APIs is described in include/zephyr/usb_c/usbc.h

Currently the device stack supports implementation of Sink only and Source only devices. Dual Role Power (DRP) devices are not yet supported.

List of samples for different purposes.

Implementing a Sink Type-C and Power Delivery USB-C device

The configuration of a USB-C Device is done in the stack layer and devicetree.

The following devicetree, structures and callbacks need to be defined:

• Devicetree usb-c-connector node referencing a TCPC
• Devicetree vbus node referencing a VBUS measurement device
• User defined structure that encapsulates application specific data
• Policy callbacks

For example, for the Sample USB-C Sink application:

Each Physical Type-C port is represented in the devicetree by a usb-c-connector compatible node:

```c
port1: usbc-port@1 {
    compatible = "usb-c-connector";
    reg = <1>;
    tcpc = &ucpd1;
    vbus = &vbus1;
    power-role = "sink";
    sink-pdos = <PDO_FIXED(5000, 100, 0)>;
};
```

VBUS is measured by a device that's referenced in the devicetree by a usb-c-vbus-adc compatible node:

```c
vbus1: vbus {
    compatible = "zephyr,usb-c-vbus-adc";
    io-channels = <&adc2 8>;
    output-ohms = <49900>;
    full-ohms = <(330000 + 49900)>;
};
```

A user defined structure is defined and later registered with the subsystem and can be accessed from callback through an API:

```c
/**
 * @brief A structure that encapsulates Port data.
 */
static struct port0_data_t {
    /** Sink Capabilities */
    uint32_t snk_caps[DT_PROP_LEN(USBC_PORT0_NODE, sink_pdos)];
    /** Number of Sink Capabilities */
    int snk_cap_cnt;
    /** Source Capabilities */
    uint32_t src_caps[PDO_MAX_DATA_OBJECTS];
    /** Number of Source Capabilities */
    int src_cap_cnt;
    /** Power Supply Ready flag */
    atomic_t ps_ready;
} port0_data = {
    .snk_caps = {DT_FOREACH_PROP_ELEM(USBC_PORT0_NODE, sink_pdos, SINK_PDO)},
    (continues on next page)
These callbacks are used by the subsystem to set or get application specific data:

```c
static int port0_policy_cb_get_snk_cap(const struct device *dev,
    uint32_t **pdos,
    int *num_pdos)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    *pdos = dpm_data->snk_caps;
    *num_pdos = dpm_data->snk_cap_cnt;
    return 0;
}

static void port0_policy_cb_set_src_cap(const struct device *dev,
    const uint32_t *pdos,
    const int num_pdos)
{
    struct port0_data_t *dpm_data;
    int num;
    int i;
    dpm_data = usbc_get_dpm_data(dev);
    num = num_pdos;
    if (num > PDO_MAX_DATA_OBJECTS) {
        num = PDO_MAX_DATA_OBJECTS;
    }
    for (i = 0; i < num; i++) {
        dpm_data->src_caps[i] = *(pdos + i);
    }
    dpm_data->src_cap_cnt = num;
}

static uint32_t port0_policy_cb_get_rdo(const struct device *dev)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    return build_rdo(dpm_data);
}
```

This callback is used by the subsystem to query if a certain action can be taken:

```c
bool port0_policy_check(const struct device *dev,
    const enum usbc_policy_check_t policy_check)
{
    switch (policy_check) {
    case CHECK_POWER_ROLE_SWAP:
        /* Reject power role swaps */
        return false;
    case CHECK_DATA_ROLE_SWAP_TO_DFP:
        /* Reject data role swap to DFP */
        return false;
    }
    return true;
}
```

(continues on next page)
return false;

case CHECK_DATA_ROLE_SWAP_TO_UFP:
    /* Accept data role swap to UFP */
    return true;

case CHECK_SNK_AT_DEFAULT_LEVEL:
    /* This device is always at the default power level */
    return true;

default:
    /* Reject all other policy checks */
    return false;

} // end port0_policy_notify

This callback is used by the subsystem to notify the application of an event:

static void port0_notify(const struct device *dev, const enum usbc_policy_notify_t policy_notify)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);

    switch (policy_notify) {
    case PROTOCOL_ERROR:
        break;
    case MSG_DISCARDED:
        break;
    case MSG_ACCEPT_RECEIVED:
        break;
    case MSG_REJECTED_RECEIVED:
        break;
    case MSG_NOT_SUPPORTED_RECEIVED:
        break;
    case TRANSITION_PS:
        atomic_set_bit(&dpm_data->ps_ready, 0);
        break;
    case PD_CONNECTED:
        break;
    case NOT_PD_CONNECTED:
        break;
    case POWER_CHANGE_0A0:
        LOG_INF("PWR 0A");
        break;
    case POWER_CHANGE_DEF:
        LOG_INF("PWR DEF");
        break;
    case POWER_CHANGE_1A5:
        LOG_INF("PWR 1A5");
        break;
    case POWER_CHANGE_3A0:
        LOG_INF("PWR 3A0");
        break;
    case DATA_ROLE_IS_UFP:
        break;
    case DATA_ROLE_IS_DFP:
        break;
    case PORT_PARTNER_NOT_RESPONSIVE:
        LOG_INF("Port Partner not PD Capable");
        break;
    case SNK_TRANSITION_TO_DEFAULT:
        break;
    case HARD_RESET_RECEIVED:
        break;
    case CHECK_DATA_ROLE_SWAP_TO_UFP:
        /* Accept data role swap to UFP */
        return true;
    case CHECK_SNK_AT_DEFAULT_LEVEL:
        /* This device is always at the default power level */
        return true;
    default:
        /* Reject all other policy checks */
        return false;
    }

} // end port0_notify

(continues on next page)
break;
case SENDER_RESPONSE_TIMEOUT:
    break;
case SOURCE_CAPABILITIES_RECEIVED:
    break;
}

Registering the callbacks:

/* Register USB-C Callbacks */

/* Register Policy Check callback */
usbc_set_policy_cb_check(usbc_port0, port0_policy_check);
/* Register Policy Notify callback */
usbc_set_policy_cb_notify(usbc_port0, port0_notify);
/* Register Policy Get Sink Capabilities callback */
usbc_set_policy_cb_get_snk_cap(usbc_port0, port0_policy_cb_get_snk_cap);
/* Register Policy Set Source Capabilities callback */
usbc_set_policy_cb_set_src_cap(usbc_port0, port0_policy_cb_set_src_cap);
/* Register Policy Get Request Data Object callback */
usbc_set_policy_cb_get_rdo(usbc_port0, port0_policy_cb_get_rdo);

Register the user defined structure:

/* Set Application port data object. This object is passed to the policy callbacks */
port0_data.ps_ready = ATOMIC_INIT(0);
usbc_set_dpm_data(usbc_port0, &port0_data);

Start the USB-C subsystem:

/* Start the USB-C Subsystem */
usbc_start(usbc_port0);

Implementing a Source Type-C and Power Delivery USB-C device

The configuration of a USB-C Device is done in the stack layer and devicetree.
Define the following devicetree, structures and callbacks:
• Devicetree usb-c-connector node referencing a TCPC
• Devicetree vbus node referencing a VBUS measurement device
• User defined structure that encapsulates application specific data
• Policy callbacks

For example, for the Sample USB-C Source application:

Each Physical Type-C port is represented in the devicetree by a usb-c-connector compatible node:

port1: usbc-port@1 {
    compatible = "usb-c-connector";
    reg = <1>;
    tcpc = <&ucpd1>;
    vbus = <&vbus>;
    power-role = "source";
    typec-power-opmode = "3.0A";
    source-pdos = <PDO_FIXED(5000, 100, 0) PDO_FIXED(9000, 100, 0) PDO_
Zephyr Project Documentation, Release 3.6.0-rc3

(--FIXED(15000, 100, 0));

VBUS is measured by a device that's referenced in the devicetree by a `usb-c-vbus-adc` compatible node:

```c
vbus1: vbus {
    compatible = "zephyr,usb-c-vbus-adc";
    io-channels = <&adc1 9>;
    output-ohms = <49900>;
    full-ohms = <(330000 + 49900)>;
    /* Pin B13 is used to control VBUS Discharge for Port1 */
    discharge-gpios = <&gpiob 13 GPIO_ACTIVE_HIGH>;
};
```

A user defined structure is defined and later registered with the subsystem and can be accessed from callback through an API:

```c
/**
 * @brief A structure that encapsulates Port data.
 */
static struct port0_data_t {
    /** Source Capabilities */
    uint32_t src_caps[DT_PROP_LEN(USBC_PORT0_NODE, source_pdos)];
    /** Number of Source Capabilities */
    int src_cap_cnt;
    /** CC Rp value */
    int rp;
    /** Sink Request RDO */
    union pd_rdo sink_request;
    /** Requested Object Pos */
    int obj_pos;
    /** VCONN CC line*/
    enum tc_cc_polarity vconn_pol;
    /** True if power supply is ready */
    bool ps_ready;
    /** True if power supply should transition to a new level */
    bool ps_tran_start;
    /** Log Sink Requested RDO to console */
    atomic_t show_sink_request;
} port0_data = {
    .rp = DT_ENUM_IDX(USBC_PORT0_NODE, typec_power_opmode),
    .src_caps = {DT_FOREACH_PROP_ELEM(USBC_PORT0_NODE, source_pdos, SOURCE_PDO),
                .src_cap_cnt = DT_PROP_LEN(USBC_PORT0_NODE, source_pdos),
};
```

These callbacks are used by the subsystem to set or get application specific data:

```c
/**
 * @brief PE calls this function when it needs to set the Rp on CC
 */
int port0_policy_cb_get_src_rp(const struct device *dev,
    enum tc_rp_value *rp)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    *rp = dpm_data->rp;
    return 0;
}
```
```c
/**
 * @brief PE calls this function to Enable (5V) or Disable (0V) the Power Supply
 */
int port0_policy_cb_src_en(const struct device *dev, bool en)
{
    source_ctrl_set(en ? SOURCE_5V : SOURCE_0V);
    return 0;
}

/** *
 * @brief PE calls this function to Enable or Disable VCONN *
 */
int port0_policy_cb_vconn_en(const struct device *dev,
                             enum tc_cc_polarity pol,
                             bool en)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    dpm_data->vconn_pol = pol;

    if (en == false) {
        /* Disable VCONN on CC1 and CC2 */
        vconn_ctrl_set(VCONN_OFF);
    } else if (pol == TC_POLARITY_CC1) {
        /* set VCONN on CC1 */
        vconn_ctrl_set(VCONN1_ON);
    } else {
        /* set VCONN on CC2 */
        vconn_ctrl_set(VCONN2_ON);
    }

    return 0;
}

/** *
 * @brief PE calls this function to get the Source Caps that will be sent to the Sink *
 */
int port0_policy_cb_get_src_caps(const struct device *dev,
                                  const uint32_t **pdos,
                                  uint32_t *num_pdos)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    *pdos = dpm_data->src_caps;
    *num_pdos = dpm_data->src_cap_cnt;

    return 0;
}

/** *
 * @brief PE calls this function to verify that a Sink's request if valid *
 */
static enum usbc_snk_req_reply_t port0_policy_cb_check_sink_request(const struct device *dev,
                                                                     const uint32_t request_msg)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    union pd_fixed_supply_pdo_source pdo;
    uint32_t obj_pos;

    // Continue on next page
```

(continues from previous page)
```c
uint32_t op_current;

dpm_data->sink_request.raw_value = request_msg;
obj_pos = dpm_data->sink_request.fixed.object_pos;
op_current =
    PD_CONVERT_FIXED_PDO_CURRENT_TO_MA(dpm_data->sink_request.fixed.operating_current);

if (obj_pos == 0 || obj_pos > dpm_data->src_cap_cnt) {
    return SNK_REQUEST_REJECT;
}

pdo.raw_value = dpm_data->src_caps[obj_pos - 1];
if (dpm_data->sink_request.fixed.operating_current > pdo.max_current) {
    return SNK_REQUEST_REJECT;
}

dpm_data->obj_pos = obj_pos;
atomic_set_bit(&port0_data.show_sink_request, 0);

/**< Clear PS ready. This will be set to true after PS is ready after
* it transitions to the new level.
*/
port0_data.ps_ready = false;
    return SNK_REQUEST_VALID;
}

/**
* @brief PE calls this function to check if the Power Supply is at the requested
* level
*/
static bool port0_policy_cb_is_ps_ready(const struct device *dev) {
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);

    /* Return true to inform that the Power Supply is ready */
    return dpm_data->ps_ready;
}

/**
* @brief PE calls this function to check if the Present Contract is still
* valid
*/
static bool port0_policy_cb_present_contract_is_valid(const struct device *dev,
    const uint32_t present_contract) {
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    union pd_fixed_supply_pdo_source pdo;
    union pd_rdo request;
    uint32_t obj_pos;
    uint32_t op_current;

    request.raw_value = present_contract;
    obj_pos = request.fixed.object_pos;
op_current = PD_CONVERT_FIXED_PDO_CURRENT_TO_MA(request.fixed.operating_current);
```

if (obj_pos == 0 || obj_pos > dpm_data->src_cap_cnt) {
  return false;
}

pdo.raw_value = dpm_data->src_caps[obj_pos - 1];
if (request.fixed.operating_current > pdo.max_current) {
  return false;
}
return true;

This callback is used by the subsystem to query if a certain action can be taken:

```c
bool port0_policy_check(const struct device *dev,
                        const enum usbc_policy_check_t policy_check)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    switch (policy_check) {
    case CHECK_POWER_ROLE_SWAP:
        /* Reject power role swaps */
        return false;
    case CHECK_DATA_ROLE_SWAP_TO_DFP:
        /* Accept data role swap to DFP */
        return true;
    case CHECK_DATA_ROLE_SWAP_TO_UFP:
        /* Reject data role swap to UFP */
        return false;
    case CHECK_SRC_PS_AT_DEFAULT_LEVEL:
        /* This check is sent from the PE_SRC_Transition_to_default
         * state and requires the following:
         * 1: Vconn should be turned ON
         * 2: Return TRUE when Power Supply is at default level
         */
        /* Power on VCONN */
        vconn_ctrl_set(dpm_data->vconn_pol);
        /* PS should be at default level after receiving a Hard Reset */
        return true;
    default:
        /* Reject all other policy checks */
        return false;
    }
}
```

This callback is used by the subsystem to notify the application of an event:

```c
static void port0_notify(const struct device *dev,
                         const enum usbc_policy_notify_t policy_notify)
{
    struct port0_data_t *dpm_data = usbc_get_dpm_data(dev);
    switch (policy_notify) {
    case PROTOCOL_ERROR:
        break;
    (continues on next page)
case MSG_DISCARDED:
    break;

case MSG_ACCEPT_RECEIVED:
    break;

case MSG_REJECTED_RECEIVED:
    break;

case MSG_NOT_SUPPORTED_RECEIVED:
    break;

case TRANSITION_PS:
    dpm_data->ps_tran_start = true;
    break;

case PD_CONNECTED:
    break;

case NOT_PD_CONNECTED:
    break;

case DATA_ROLE_IS_UFP:
    break;

case DATA_ROLE_IS_DFP:
    break;

case PORT_PARTNER_NOT_RESPONSIVE:
    LOG_INF("Port Partner not PD Capable");
    break;

case HARD_RESET_RECEIVED:
    /*
     * This notification is sent from the PE_SRC_Transition_to_default
     * state and requires the following:
     * 1: Vconn should be turned OFF
     * 2: Reset of the local hardware
     */

    /* Power off VCONN */
    vconn_ctrl_set(VCONN_OFF);
    /* Transition PS to Default level */
    source_ctrl_set(SOURCE_5V);
    break;

default:
    }
}  

Registering the callbacks:

    /* Register USB-C Callbacks */

    /* Register Policy Check callback */
    usbc_set_policy_cb_check(usbc_port0, port0_policy_check);
    /* Register Policy Notify callback */
    usbc_set_policy_cb_notify(usbc_port0, port0_notify);
    /* Register Policy callback to set the Rp on CC lines */
    usbc_set_policy_cb_get_src_rp(usbc_port0, port0_policy_cb_get_src_rp);
    /* Register Policy callback to enable or disable power supply */
    usbc_set_policy_cb_src_en(usbc_port0, port0_policy_cb_src_en);
    /* Register Policy callback to enable or disable vconn */
    usbc_set_vconn_control_cb(usbc_port0, port0_policy_cb_vconn_en);
    /* Register Policy callback to send the source caps to the sink */
    usbc_set_policy_cb_get_src_caps(usbc_port0, port0_policy_cb_get_src_caps);
    /* Register Policy callback to check if the sink request is valid */
    usbc_set_policy_cb_check_sink_request(usbc_port0, port0_policy_cb_check_sink_request);
    /* Register Policy callback to check if the power supply is ready */
    usbc_set_policy_cb_is_ps_ready(usbc_port0, port0_policy_cb_is_ps_ready);
    /* Register Policy callback to check if Present Contract is still valid */
(continues on next page)
usbc_set_policy_cb_present_contract_is_valid(usbc_port0, port0_policy_cb_present_contract_is_valid);

Register the user defined structure:

```
/* Set Application port data object. This object is passed to the policy callbacks */
usbc_set_dpm_data(usbc_port0, &port0_data);
```

Start the USB-C subsystem:

```
/* Start the USB-C Subsystem */
usbc_start(usbc_port0);
```

### API reference

#### Related code samples

**Basic USB-C Sink**
Implement a USB-C Power Delivery application in the form of a USB-C Sink.

**Basic USB-C Source**
Implement a USB-C Power Delivery application in the form of a USB-C Source.

---

**group _usbc_device_api**
USB-C Device APIs.

#### Defines

**FIXED_5V_100MA_RDO**
This Request Data Object (RDO) value can be returned from the policy_cb_get_rdo if 5V@100mA with the following options are sufficient for the Sink to operate.

The RDO is configured as follows: Maximum operating current 100mA Operating current 100mA Unchunked Extended Messages Not Supported No USB Suspend Not USB Communications Capable No capability mismatch Don’t giveback Object position 1 (5V PDO)

#### Enums

**enum usbc_policy_request_t**
Device Policy Manager requests.

**Values:**

- **enumerator REQUEST_NOP**
  No request.
enumerator REQUEST_TC_DISABLED
    Request Type-C layer to transition to Disabled State.

enumerator REQUEST_TC_ERROR_RECOVERY
    Request Type-C layer to transition to Error Recovery State.

enumerator REQUEST_TC_END
    End of Type-C requests.

enumerator REQUEST_PE_DR_SWAP
    Request Policy Engine layer to perform a Data Role Swap.

enumerator REQUEST_PE_HARD_RESET_SEND
    Request Policy Engine layer to send a hard reset.

enumerator REQUEST_PE_SOFT_RESET_SEND
    Request Policy Engine layer to send a soft reset.

enumerator REQUEST_PE_GET_SRC_CAPS
    Request Policy Engine layer to get Source Capabilities from port partner.

enumerator REQUEST_GET_SNK_CAPS
    Request Policy Engine to get Sink Capabilities from port partner.

enumerator REQUEST_PE_GOTO_MIN
    Request Policy Engine to request the port partner to source minimum power.

defined enum usbc_policy_notify_t
    Device Policy Manager notifications.
    
    Values:

enumerator MSG_ACCEPT_RECEIVED
    Power Delivery Accept message was received.

enumerator MSG_REJECTED_RECEIVED
    Power Delivery Reject message was received.

enumerator MSG_DISCARDED
    Power Delivery discarded the message being transmitted.

enumerator MSG_NOT_SUPPORTED_RECEIVED
    Power Delivery Not Supported message was received.

enumerator DATA_ROLE_IS_UFP
    Data Role has been set to Upstream Facing Port (UFP)

enumerator DATA_ROLE_IS_DFP
    Data Role has been set to Downstream Facing Port (DFP)
enumerator PD_CONNECTED
   A PD Explicit Contract is in place.

enumerator NOT_PD_CONNECTED
   No PD Explicit Contract is in place.

enumerator TRANSITION_PS
   Transition the Power Supply.

enumerator PORT_PARTNER_NOT_RESPONSIVE
   Port partner is not responsive.

enumerator PROTOCOL_ERROR
   Protocol Error occurred.

enumerator SNK_TRANSITION_TO_DEFAULT
   Transition the Sink to default.

enumerator HARD_RESET_RECEIVED
   Hard Reset Received.

enumerator POWER_CHANGE_0A0
   Sink SubPower state at 0V.

enumerator POWER_CHANGE_DEF
   Sink SubPower state a 5V / 500mA.

enumerator POWER_CHANGE_1A5
   Sink SubPower state a 5V / 1.5A.

enumerator POWER_CHANGE_3A0
   Sink SubPower state a 5V / 3A.

enumerator SENDER_RESPONSE_TIMEOUT
   Sender Response Timeout.

enumerator SOURCE_CAPABILITIES_RECEIVED
   Source Capabilities Received.

enum usbc_policy_check_t
   Device Policy Manager checks.
   Values:

   enumerator CHECK_POWER_ROLE_SWAP
      Check if Power Role Swap is allowed.

   enumerator CHECK_DATA_ROLE_SWAP_TO_DFP
      Check if Data Role Swap to DFP is allowed.
enumerator CHECK_DATA_ROLE_SWAP_TO_UFP
Check if Data Role Swap to UFP is allowed.

enumerator CHECK_SNK_AT_DEFAULT_LEVEL
Check if Sink is at default level.

enumerator CHECK_VCONN_CONTROL
Check if should control VCONN.

enumerator CHECK_SRC_PS_AT_DEFAULT_LEVEL
Check if Source Power Supply is at default level.

enum usbc_policy_wait_t
Device Policy Manager Wait message notifications.
Values:

enumerator WAIT_SINK_REQUEST
The port partner is unable to meet the sink request at this time.

enumerator WAIT_POWER_ROLE_SWAP
The port partner is unable to do a Power Role Swap at this time.

enumerator WAIT_DATA_ROLE_SWAP
The port partner is unable to do a Data Role Swap at this time.

enumerator WAIT_VCONN_SWAP
The port partner is unable to do a VCONN Swap at this time.

enum usbc_snk_req_reply_t
Device Policy Manager’s response to a Sink Request.
Values:

enumerator SNK_REQUEST_VALID
The sink port partner’s request can be met.

enumerator SNK_REQUEST_REJECT
The sink port partner’s request can not be met.

enumerator SNK_REQUEST_WAIT
The sink port partner’s request can be met at a later time.

Functions

int usbc_start(const struct device *dev)
Start the USB-C Subsystem.

Parameters
  • dev – Runtime device structure
Return values
0 – on success

int usbc_suspend(const struct device *dev)
Suspend the USB-C Subsystem.

Parameters
• dev – Runtime device structure

Return values
0 – on success

int usbc_request(const struct device *dev, const enum usbc_policy_request_t req)
Make a request of the USB-C Subsystem.

Parameters
• dev – Runtime device structure
• req – request

Return values
0 – on success

void usbc_bypass_next_sleep(const struct device *dev)

void usbc_set_dpm_data(const struct device *dev, void *dpm_data)
Set pointer to Device Policy Manager (DPM) data.

Parameters
• dev – Runtime device structure
• dpm_data – pointer to dpm data

void *usbc_get_dpm_data(const struct device *dev)
Get pointer to Device Policy Manager (DPM) data.

Parameters
• dev – Runtime device structure

Return values
• pointer – to dpm data that was set with usbc_set_dpm_data
• NULL – if dpm data was not set

void usbc_set_vconn_control_cb(const struct device *dev, const tcpc_vconn_control_cb_t cb)
Set the callback used to set VCONN control.

Parameters
• dev – Runtime device structure
• cb – VCONN control callback

void usbc_set_vconn_discharge_cb(const struct device *dev, const tcpc_vconn_discharge_cb_t cb)
Set the callback used to discharge VCONN.

Parameters
• dev – Runtime device structure
• cb – VCONN discharge callback
void usbc_set_policy_cb_check(const struct device *dev, const policy_cb_check_t cb)
Set the callback used to check a policy.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_notify(const struct device *dev, const policy_cb_notify_t cb)
Set the callback used to notify Device Policy Manager of a policy change.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_wait_notify(const struct device *dev, const policy_cb_wait_notify_t cb)
Set the callback used to notify Device Policy Manager of WAIT message reception.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_get_snk_cap(const struct device *dev, const policy_cb_get_snk_cap_t cb)
Set the callback used to get the Sink Capabilities.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_set_src_cap(const struct device *dev, const policy_cb_set_src_cap_t cb)
Set the callback used to store the received Port Partner’s Source Capabilities.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_get_rdo(const struct device *dev, const policy_cb_get_rdo_t cb)
Set the callback used to get the Request Data Object (RDO)

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_is_snk_at_default(const struct device *dev, const policy_cb_is_snk_at_default_t cb)
Set the callback used to check if the sink power supply is at the default level.

Parameters
• dev – Runtime device structure
• cb – callback
void usbc_set_policy_cb_get_src_rp(const struct device *dev, const
policy_cb_get_src_rp_t cb)
Set the callback used to get the Rp value that should be placed on the CC lines.

Parameters
• dev – USB-C Connector Instance
• cb – callback

void usbc_set_policy_cb_src_en(const struct device *dev, const
policy_cb_src_en_t cb)
Set the callback used to enable VBUS.

Parameters
• dev – USB-C Connector Instance
• cb – callback

void usbc_set_policy_cb_get_src_caps(const struct device *dev, const
policy_cb_get_src_caps_t cb)
Set the callback used to get the Source Capabilities from the Device Policy Manager.

Parameters
• dev – USB-C Connector Instance
• cb – callback

void usbc_set_policy_cb_check_sink_request(const struct device *dev, const
policy_cb_check_sink_request_t cb)
Set the callback used to check if Sink request is valid.

Parameters
• dev – USB-C Connector Instance
• cb – callback

void usbc_set_policy_cb_is_ps_ready(const struct device *dev, const
policy_is_ps_ready_t cb)
Set the callback used to check if Source Power Supply is ready.

Parameters
• dev – USB-C Connector Instance
• cb – callback

void usbc_set_policy_cb_present_contract_is_valid(const struct device *dev, const
policy_present_contract_is_valid_t cb)
Set the callback to check if present Contract is still valid.

Parameters
• dev – USB-C Connector Instance
• cb – callback

void usbc_set_policy_cb_change_src_caps(const struct device *dev, const
policy_change_src_caps_t cb)
Set the callback used to request that a different set of Source Caps be sent to the Sink.

Parameters
• dev – USB-C Connector Instance
void usbc_set_policy_cb_set_port_partner_snk_cap(const struct device *dev, const policy_cb_set_port_partner_snk_cap_t cb)

Set the callback used to store the Capabilities received from a Sink Port Partner.

**Parameters**
- **dev** – USB-C Connector Instance
- **cb** – callback

**SINK callback reference**

group sink_callbacks

**Typedefs**

typedef int (*policy_cb_get_snk_cap_t)(const struct device *dev, uint32_t **pdos, int *num_pdos)

Callback type used to get the Sink Capabilities.

- **Param dev**
  USB-C Connector Instance
- **Param pdos**
  pointer where pdos are stored
- **Param num_pdos**
  pointer where number of pdos is stored
- **Return**
  0 on success

typedef void (*policy_cb_set_src_cap_t)(const struct device *dev, const uint32_t *pdos, const int num_pdos)

Callback type used to report the received Port Partner’s Source Capabilities.

- **Param dev**
  USB-C Connector Instance
- **Param pdos**
  pointer to the partner’s source pdos
- **Param num_pdos**
  number of source pdos

typedef bool (*policy_cb_check_t)(const struct device *dev, const enum usbc_policy_check_t policy_check)

Callback type used to check a policy.

- **Param dev**
  USB-C Connector Instance
- **Param policy_check**
  policy to check
- **Return**
  true if policy is currently allowed by the device policy manager
typedef bool (*policy_cb_wait_notify_t)(const struct device *dev, const enum usbc_policy_wait_t wait_notify)

Callback type used to notify Device Policy Manager of WAIT message reception.

**Param dev**
USB-C Connector Instance

**Param wait_notify**
wait notification

**Return**
return true if the PE should wait and resend the message

typedef void (*policy_cb_notify_t)(const struct device *dev, const enum usbc_policy_notify_t policy_notify)

Callback type used to notify Device Policy Manager of a policy change.

**Param dev**
USB-C Connector Instance

**Param policy_notify**
policy notification

typedef uint32_t (*policy_cb_get_rdo_t)(const struct device *dev)

Callback type used to get the Request Data Object (RDO)

**Param dev**
USB-C Connector Instance

**Return**
RDO

typedef bool (*policy_cb_is_snk_at_default_t)(const struct device *dev)

Callback type used to check if the sink power supply is at the default level.

**Param dev**
USB-C Connector Instance

**Return**
true if power supply is at default level

**SOURCE callback reference**

**group source_callbacks**

**Typedefs**

typedef int (*policy_cb_get_src_caps_t)(const struct device *dev, const uint32_t **pdos, uint32_t *num_pdos)

Callback type used to get the Source Capabilities from the Device Policy Manager.

**Param dev**
USB-C Connector Instance

**Param pdos**
pointer to source capability pdos
**Param num_pdos**
pointer to number of source capability pdos

**Return**
0 on success

typedef enum _usbc_snk_req_reply_t (*policy_cb_check_sink_request_t)(const struct device *dev, const uint32_t request_msg)
Callback type used to check if Sink request is valid.

**Param dev**
USB-C Connector Instance

**Param request_msg**
request message to check

**Return**
sink request reply

typedef bool (*policy_cb_is_ps_ready_t)(const struct device *dev)
Callback type used to check if Source Power Supply is ready.

**Param dev**
USB-C Connector Instance

**Return**
true if power supply is ready, else false

typedef bool (*policy_cb_present_contract_is_valid_t)(const struct device *dev, const uint32_t present_contract)
Callback type used to check if present Contract is still valid.

**Param dev**
USB-C Connector Instance

**Param present_contract**
present contract

**Return**
true if present contract is still valid

typedef bool (*policy_cb_change_src_caps_t)(const struct device *dev)
Callback type used to request that a different set of Source Caps be sent to the Sink.

**Param dev**
USB-C Connector Instance

**Return**
true if a different set of Cource Caps is available

typedef void (*policy_cb_set_port_partner_snk_cap_t)(const struct device *dev, const uint32_t *pdos, const int num_pdos)
Callback type used to report the Capabilities received from a Sink Port Partner.

**Param dev**
USB-C Connector Instance

**Param pdos**
pointer to sink cap pdos

**Param num_pdos**
number of sink cap pdos
typedef int (*policy_cb_get_src_rp_t)(const struct device *dev, enum tc_rp_value *rp)

Callback type used to get the Rp value that should be placed on the CC lines.

- **Param dev**
  USB-C Connector Instance

- **Param rp**
  rp value

- **Return**
  0 on success

typedef int (*policy_cb_src_en_t)(const struct device *dev, bool en)

Callback type used to enable VBUS.

- **Param dev**
  USB-C Connector Instance

- **Param en**
  true if VBUS should be enabled, else false to disable it

- **Return**
  0 on success

**Common sections related to USB support**

### 6.5.7 Human Interface Devices (HID)

Common USB HID part that can be used outside of USB support, defined in header file `include/zephyr/usb/class/hid.h`.

**HID types reference**

- `group usb_hid_definitions`
  - hid.h API
    - **USB HID types and values**

- `USB HID_VERSION`
  - HID Specification release v1.11.

- `USB_DESC_HID`
  - USB HID Class HID descriptor type.

- `USB_DESC_HID_REPORT`
  - USB HID Class Report descriptor type.

- `USB_DESC_HID_PHYSICAL`
  - USB HID Class physical descriptor type.

- `USB_HID_GET_REPORT`
  - USB HID Class GetReport bRequest value.
USB_HID_GET_IDLE
  USB HID Class GetIdle bRequest value.

USB_HID_GET_PROTOCOL
  USB HID Class GetProtocol bRequest value.

USB_HID_SET_REPORT
  USB HID Class SetReport bRequest value.

USB_HID_SET_IDLE
  USB HID Class SetIdle bRequest value.

USB_HID_SET_PROTOCOL
  USB HID Class SetProtocol bRequest value.

HID_BOOT_IFACE_CODE_NONE
  USB HID Boot Interface Protocol (bInterfaceProtocol) Code None.

HID_BOOT_IFACE_CODE_KEYBOARD

HID_BOOT_IFACE_CODE_MOUSE

HID_PROTOCOL_BOOT
  USB HID Class Boot protocol code.

HID_PROTOCOL_REPORT
  USB HID Class Report protocol code.

HID_ITEM_TYPE_MAIN
  HID Main item type.

HID_ITEM_TYPE_GLOBAL
  HID Global item type.

HID_ITEM_TYPE_LOCAL
  HID Local item type.

HID_ITEM_TAG_INPUT
  HID Input item tag.

HID_ITEM_TAG_OUTPUT
  HID Output item tag.

HID_ITEM_TAG_COLLECTION
  HID Collection item tag.
HID_ITEM_TAG_FEATURE
    HID Feature item tag.

HID_ITEM_TAG_COLLECTION_END
    HID End Collection item tag.

HID_ITEM_TAG_USAGE_PAGE
    HID Usage Page item tag.

HID_ITEM_TAG_LOGICAL_MIN
    HID Logical Minimum item tag.

HID_ITEM_TAG_LOGICAL_MAX
    HID Logical Maximum item tag.

HID_ITEM_TAG_PHYSICAL_MIN
    HID Physical Minimum item tag.

HID_ITEM_TAG_PHYSICAL_MAX
    HID Physical Maximum item tag.

HID_ITEM_TAG_UNIT_EXPONENT
    HID Unit Exponent item tag.

HID_ITEM_TAG_UNIT
    HID Unit item tag.

HID_ITEM_TAG_REPORT_SIZE
    HID Report Size item tag.

HID_ITEM_TAG_REPORT_ID
    HID Report ID item tag.

HID_ITEM_TAG_REPORT_COUNT
    HID Report count item tag.

HID_ITEM_TAG_USAGE
    HID Usage item tag.

HID_ITEM_TAG_USAGE_MIN
    HID Usage Minimum item tag.

HID_ITEM_TAG_USAGE_MAX
    HID Usage Maximum item tag.

HID_COLLECTION_PHYSICAL
    Physical collection type.
HID_COLLECTION_APPLICATION
    Application collection type.

HID_COLLECTION_LOGICAL
    Logical collection type.

HID_COLLECTION_REPORT
    Report collection type.

HID_COLLECTION_NAMED_ARRAY
    Named Array collection type.

HID_COLLECTION_USAGE_SWITCH
    Usage Switch collection type.

HID_COLLECTION_MODIFIER
    Modifier collection type.

HID_USAGE_GEN_DESKTOP
    HID Generic Desktop Controls Usage page.

HID_USAGE_GEN_KEYBOARD
    HID Keyboard Usage page.

HID_USAGE_GEN_LEDS
    HID LEDs Usage page.

HID_USAGE_GEN_BUTTON
    HID Button Usage page.

HID_USAGE_GEN_DESKTOP_UNDEFINED
    HID Generic Desktop Undefined Usage ID.

HID_USAGE_GEN_DESKTOP_POINTER
    HID Generic Desktop Pointer Usage ID.

HID_USAGE_GEN_DESKTOP_MOUSE
    HID Generic Desktop Mouse Usage ID.

HID_USAGE_GEN_DESKTOP_JOYSTICK
    HID Generic Desktop Joystick Usage ID.

HID_USAGE_GEN_DESKTOP_GAMEPAD
    HID Generic Desktop Gamepad Usage ID.

HID_USAGE_GEN_DESKTOP_KEYBOARD
    HID Generic Desktop Keyboard Usage ID.
HID_USAGE_GEN_DESKTOP_KEYPAD
HID Generic Desktop Keypad Usage ID.

HID_USAGE_GEN_DESKTOP_X
HID Generic Desktop X Usage ID.

HID_USAGE_GEN_DESKTOP_Y
HID Generic Desktop Y Usage ID.

HID_USAGE_GEN_DESKTOP_WHEEL
HID Generic Desktop Wheel Usage ID.

HID items reference

group usb_hid_items

Defines

HID_ITEM(bTag, bType, bSize)
Define HID short item.

Parameters
• bTag – Item tag
• bType – Item type
• bSize – Item data size

Returns
HID Input item

HID_INPUT(a)
Define HID Input item with the data length of one byte.

For usage examples, see
HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Input item data

Returns
HID Input item

HID_OUTPUT(a)
Define HID Output item with the data length of one byte.

For usage examples, see
HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Output item data

Returns
HID Output item

6.5. USB
HID_FEATURE(a)
Define HID Feature item with the data length of one byte.

Parameters
• a – Feature item data

Returns
HID Feature item

HID_COLLECTION(a)
Define HID Collection item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Collection item data

Returns
HID Collection item

HID_END_COLLECTION
Define HID End Collection (non-data) item.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Returns
HID End Collection item

HID_USAGE_PAGE(page)
Define HID Usage Page item.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• page – Usage Page

Returns
HID Usage Page item

HID_LOGICAL_MIN8(a)
Define HID Logical Minimum item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Minimum value in logical units

Returns
HID Logical Minimum item

HID_LOGICAL_MAX8(a)
Define HID Logical Maximum item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Maximum value in logical units
Returns
HID Logical Maximum item

HID_LOGICAL_MIN16(a, b)
Define HID Logical Minimum item with the data length of two bytes.

Parameters
• a – Minimum value lower byte
• b – Minimum value higher byte

Returns
HID Logical Minimum item

HID_LOGICAL_MAX16(a, b)
Define HID Logical Maximum item with the data length of two bytes.

Parameters
• a – Minimum value lower byte
• b – Minimum value higher byte

Returns
HID Logical Maximum item

HID_LOGICAL_MIN32(a, b, c, d)
Define HID Logical Minimum item with the data length of four bytes.

Parameters
• a – Minimum value lower byte
• b – Minimum value low middle byte
• c – Minimum value high middle byte
• d – Minimum value higher byte

Returns
HID Logical Minimum item

HID_LOGICAL_MAX32(a, b, c, d)
Define HID Logical Maximum item with the data length of four bytes.

Parameters
• a – Minimum value lower byte
• b – Minimum value low middle byte
• c – Minimum value high middle byte
• d – Minimum value higher byte

Returns
HID Logical Maximum item

HID_REPORT_SIZE(size)
Define HID Report Size item with the data length of one byte.

For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• size – Report field size in bits

Returns
HID Report Size item
HID_REPORT_ID(id)
Define HID Report ID item with the data length of one byte.

Parameters
• id – Report ID

Returns
HID Report ID item

HID_REPORT_COUNT(count)
Define HID Report Count item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• count – Number of data fields included in the report

Returns
HID Report Count item

HID_USAGE(idx)
Define HID Usage Index item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• idx – Number of data fields included in the report

Returns
HID Usage Index item

HID_USAGE_MIN8(a)
Define HID Usage Minimum item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Starting Usage

Returns
HID Usage Minimum item

HID_USAGE_MAX8(a)
Define HID Usage Maximum item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Ending Usage

Returns
HID Usage Maximum item

HID_USAGE_MIN16(a, b)
Define HID Usage Minimum item with the data length of two bytes.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Starting Usage lower byte
• b – Starting Usage higher byte

**Returns**
HID Usage Minimum item

```c
HID_USAGE_MAX16(a, b)
```

Define HID Usage Maximum item with the data length of two bytes.

For usage examples, see `HID_MOUSE_REPORT_DESC()`, `HID_KEYBOARD_REPORT_DESC()`

**Parameters**
• a – Ending Usage lower byte
• b – Ending Usage higher byte

**Returns**
HID Usage Maximum item

### HID Mouse and Keyboard report descriptors

The pre-defined Mouse and Keyboard report descriptors can be used by a HID device implementation or simply as examples.

**group usb_hid_mk_report_desc**

**Defines**

```c
HID_MOUSE_REPORT_DESC(bcント)
```

Simple HID mouse report descriptor for n button mouse.

**Parameters**

• `bcント` – Button count. Allowed values from 1 to 8.

```c
HID_KEYBOARD_REPORT_DESC()
```

Simple HID keyboard report descriptor.

** Enums **

```c
eenum hid_kbd_code
```

HID keyboard button codes.

**Values:**

```c
enumerator HID_KEY_A = 4
enumerator HID_KEY_B = 5
enumerator HID_KEY_C = 6
enumerator HID_KEY_D = 7
```
enumerator HID_KEY_E = 8
enumerator HID_KEY_F = 9
enumerator HID_KEY_G = 10
enumerator HID_KEY_H = 11
enumerator HID_KEY_I = 12
enumerator HID_KEY_J = 13
enumerator HID_KEY_K = 14
enumerator HID_KEY_L = 15
enumerator HID_KEY_M = 16
enumerator HID_KEY_N = 17
enumerator HID_KEY_O = 18
enumerator HID_KEY_P = 19
enumerator HID_KEY_Q = 20
enumerator HID_KEY_R = 21
enumerator HID_KEY_S = 22
enumerator HID_KEY_T = 23
enumerator HID_KEY_U = 24
enumerator HID_KEY_V = 25
enumerator HID_KEY_W = 26
enumerator HID_KEY_X = 27
enumerator HID_KEY_Y = 28
enumerator HID_KEY_Z = 29
enumerator HID_KEY_1 = 30
enumerator HID_KEY_2 = 31
enumerator HID_KEY_3 = 32
enumerator HID_KEY_4 = 33
enumerator HID_KEY_5 = 34
enumerator HID_KEY_6 = 35
enumerator HID_KEY_7 = 36
enumerator HID_KEY_8 = 37
enumerator HID_KEY_9 = 38
enumerator HID_KEY_0 = 39
enumerator HID_KEY_ENTER = 40
enumerator HID_KEY_ESC = 41
enumerator HID_KEY_BACKSPACE = 42
enumerator HID_KEY_TAB = 43
enumerator HID_KEY_SPACE = 44
enumerator HID_KEY_MINUS = 45
enumerator HID_KEY_EQUAL = 46
enumerator HID_KEY_LEFTBRACE = 47
enumerator HID_KEY_RIGHTBRACE = 48
enumerator HID_KEY_BACKSLASH = 49
enumerator HID_KEY_HASH = 50
enumerator HID_KEY_SEMICOLON = 51
enumerator HID_KEY_APOSTROPHE = 52
enumerator HID_KEY_GRAVE = 53
enumerator HID_KEY_COMMA = 54
enumerator HID_KEY_DOT = 55
enumerator HID_KEY_SLASH = 56
enumerator HID_KEY_CAPSLOCK = 57
enumerator HID_KEY_F1 = 58
enumerator HID_KEY_F2 = 59
enumerator HID_KEY_F3 = 60
enumerator HID_KEY_F4 = 61
enumerator HID_KEY_F5 = 62
enumerator HID_KEY_F6 = 63
enumerator HID_KEY_F7 = 64
enumerator HID_KEY_F8 = 65
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enumerator HID_KEY_F10 = 67
enumerator HID_KEY_F11 = 68
enumerator HID_KEY_F12 = 69
enumerator HID_KEY_SYSRQ = 70
enumerator HID_KEY_SCROLLLOCK = 71
enumerator HID_KEY_PAUSE = 72
enumerator HID_KEY_INSERT = 73
enumerator HID_KEY_HOME = 74
enumerator HID_KEY_PAGEUP = 75
enumerator HID_KEY_DELETE = 76
enumerator HID_KEY_END = 77
enumerator HID_KEY_PAGEDOWN = 78
enumerator HID_KEY_RIGHT = 79
enumerator HID_KEY_LEFT = 80
enumerator HID_KEY_DOWN = 81
enumerator HID_KEY_UP = 82
enumerator HID_KEY_NUMLOCK = 83
enumerator HID_KEY_KPSLASH = 84
enumerator HID_KEY_KPASTERISK = 85
enumerator HID_KEY_KPMINUS = 86
enumerator HID_KEY_KPPLUS = 87
enumerator HID_KEY_KPENTER = 88
enumerator HID_KEY_KP_1 = 89
enumerator HID_KEY_KP_2 = 90
enumerator HID_KEY_KP_3 = 91
enumerator HID_KEY_KP_4 = 92
enumerator HID_KEY_KP_5 = 93
enumerator HID_KEY_KP_6 = 94
enumerator HID_KEY_KP_7 = 95
enumerator HID_KEY_KP_8 = 96
enumerator HID_KEY_KP_9 = 97
enumerator HID_KEY_KP_0 = 98
enum hid_kbd_modifier
    HID keyboard modifiers.
    Values:

    enumerator HID_KBD_MODIFIER_NONE = 0x00
    enumerator HID_KBD_MODIFIER_LEFT_CTRL = 0x01
    enumerator HID_KBD_MODIFIER_LEFT_SHIFT = 0x02
    enumerator HID_KBD_MODIFIER_LEFT_ALT = 0x04
    enumerator HID_KBD_MODIFIER_LEFT_UI = 0x08
    enumerator HID_KBD_MODIFIER_RIGHT_CTRL = 0x10
    enumerator HID_KBD_MODIFIER_RIGHT_SHIFT = 0x20
    enumerator HID_KBD_MODIFIER_RIGHT_ALT = 0x40
    enumerator HID_KBD_MODIFIER_RIGHT_UI = 0x80

enum hid_kbd_led
    HID keyboard LEDs.
    Values:

    enumerator HID_KBD_LED_NUM_LOCK = 0x01
    enumerator HID_KBD_LED_CAPS_LOCK = 0x02
    enumerator HID_KBD_LED_SCROLL_LOCK = 0x04
    enumerator HID_KBD_LED_COMPOSE = 0x08
    enumerator HID_KBD_LED_KANA = 0x10
Chapter 7

Hardware Support

7.1 Architecture-related Guides

7.1.1 Zephyr support status on ARC processors

Overview

This page describes current state of Zephyr for ARC processors and some future plans. Please note that

• plans are given without exact deadlines
• software features require corresponding hardware to be present and configured the proper way
• not all the features can be enabled at the same time

Support status

Legend: Y - yes, supported; N - no, not supported; WIP - Work In Progress; TBD - to be decided
## Processor families

<table>
<thead>
<tr>
<th>Port status</th>
<th>EM</th>
<th>HS3x/4x</th>
<th>VPX</th>
<th>HS5x</th>
<th>HS6x</th>
</tr>
</thead>
<tbody>
<tr>
<td>up-streamed</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>TBD</td>
<td>TBD</td>
</tr>
</tbody>
</table>

### Features

<table>
<thead>
<tr>
<th>Feature</th>
<th>EM</th>
<th>HS3x/4x</th>
<th>VPX</th>
<th>HS5x</th>
<th>HS6x</th>
</tr>
</thead>
<tbody>
<tr>
<td>Closely coupled memories (ICCM, DCCM)</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>TBD</td>
<td>TBD</td>
</tr>
<tr>
<td>Execution with caches - Instruction/Data, L1/L2 caches</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Hardware-assisted unaligned memory access</td>
<td>Y&lt;sup&gt;2&lt;/sup&gt;</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Regular interrupts with multiple priority levels, direct interrupts</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Fast interrupts, separate register banks for fast interrupts</td>
<td>Y</td>
<td>Y</td>
<td>TBD</td>
<td>N</td>
<td>N</td>
</tr>
<tr>
<td>Hardware floating point unit (FPU)</td>
<td>N/A</td>
<td>Y</td>
<td>TBD</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Symmetric multiprocessing (SMP) support, switch-based</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Hardware-assisted stack checking</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>N</td>
</tr>
<tr>
<td>Hardware-assisted atomic operations</td>
<td>N/A</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Hardware ISA</td>
<td>Y&lt;sup&gt;3&lt;/sup&gt;</td>
<td>N&lt;sup&gt;3&lt;/sup&gt;</td>
<td>TBD&lt;sup&gt;6&lt;/sup&gt;</td>
<td>TBD</td>
<td>TBD</td>
</tr>
<tr>
<td>DSP AGU/XY extensions</td>
<td>Y</td>
<td>N&lt;sup&gt;3&lt;/sup&gt;</td>
<td>N/A</td>
<td>TBD</td>
<td>TBD</td>
</tr>
<tr>
<td>Userspace</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>TBD</td>
<td>TBD</td>
</tr>
<tr>
<td>Memory protection unit (MPU)</td>
<td>Y</td>
<td>Y</td>
<td>TBD</td>
<td>N</td>
<td>N</td>
</tr>
<tr>
<td>Memory management unit (MMU)</td>
<td>N/A</td>
<td>N</td>
<td>TBD</td>
<td>N</td>
<td>N</td>
</tr>
<tr>
<td>SecureShield</td>
<td>Y</td>
<td>N/A</td>
<td>N/A</td>
<td>N/A</td>
<td>N/A</td>
</tr>
<tr>
<td>Single-thread kernel support&lt;sup&gt;5&lt;/sup&gt;</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
</tbody>
</table>

### Toolchains

<table>
<thead>
<tr>
<th>Toolchain</th>
<th>EM</th>
<th>HS3x/4x</th>
<th>VPX</th>
<th>HS5x</th>
<th>HS6x</th>
</tr>
</thead>
<tbody>
<tr>
<td>GNU (open source GCC-based)</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>MetaWare (proprietary Clang-based)</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
</tbody>
</table>

### Simulators

<table>
<thead>
<tr>
<th>Simulator</th>
<th>EM</th>
<th>HS3x/4x</th>
<th>VPX</th>
<th>HS5x</th>
<th>HS6x</th>
</tr>
</thead>
<tbody>
<tr>
<td>QEMU (open source)&lt;sup&gt;4&lt;/sup&gt;</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>nSIM (proprietary, provided by MetaWare Development Tools)</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
</tbody>
</table>

### Notes

7.1.2 Arm Cortex-M Developer Guide

**Overview**

This page contains detailed information about the status of the Arm Cortex-M architecture porting in the Zephyr RTOS and describes key aspects when developing Zephyr applications for Arm Cortex-M-based platforms.

---

<sup>6</sup> Currently only ARC VPX scalar port is supported. The support of VPX vector pipeline, VCCM, STU is not included in this port, and require additional development and/or other runtime integration.

<sup>1</sup> Usage of CCMs is limited on SMP systems.

<sup>2</sup> Except the systems with secure features (SecureShield) due to HW limitation.

<sup>3</sup> We only support save/restore ACCL/ACCH registers in task's context. Rest of DSP/AGU registers save/restore isn't implemented but kernel itself does not use these registers. This allows single task per core to use DSP/AGU safely.

<sup>5</sup> Single-thread kernel is support only for single core targets.

<sup>4</sup> QEMU doesn't support all the ARC processor's HW features. For the detailed info please check the ARC QEMU documentation.
# Key supported features

The table below summarizes the status of key OS features in the different Arm Cortex-M implementation variants.

<table>
<thead>
<tr>
<th>Architecture variant</th>
<th>Processor families</th>
<th>M0/M</th>
<th>M0+</th>
<th>M3</th>
<th>M4</th>
<th>M7</th>
<th>M23</th>
<th>M33</th>
<th>M55</th>
</tr>
</thead>
<tbody>
<tr>
<td>OS Features</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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<td></td>
<td></td>
</tr>
<tr>
<td>Programmable fault IRQ priorities</td>
<td></td>
<td>Y</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Single-thread kernel support</td>
<td></td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Thread local storage support</td>
<td></td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Interrupt handling</td>
<td></td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>Regular interrupts</td>
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<td>Y</td>
<td>Y</td>
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<td>Y</td>
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<tr>
<td>Dynamic interrupts</td>
<td></td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
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</tr>
<tr>
<td>Direct interrupts</td>
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<td>Y</td>
<td>Y</td>
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<tr>
<td>Zero Latency interrupts</td>
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<td>Y</td>
<td>Y</td>
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<td>Y</td>
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<tr>
<td>CPU idling</td>
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<td>Y</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>Native system timer (SysTick)</td>
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<td>N¹</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>Memory protection</td>
<td></td>
<td></td>
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<td>User mode</td>
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<td>Y</td>
<td>Y</td>
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<td>HW stack protection (MPU)</td>
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<td>N</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>HW-assisted stack limit checking</td>
<td></td>
<td>N</td>
<td>N</td>
<td>N</td>
<td>N</td>
<td>N</td>
<td>Y²</td>
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<tr>
<td>HW-assisted null-pointer dereference detection</td>
<td></td>
<td>N</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>HW-assisted atomic operations</td>
<td></td>
<td>N</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>Support for non-cacheable regions</td>
<td></td>
<td>N</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
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<tr>
<td>Execute SRAM functions</td>
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<td>N</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
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<tr>
<td>Floating Point Services</td>
<td></td>
<td>N</td>
<td>N</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>DSP ISA</td>
<td></td>
<td>N</td>
<td>N</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
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<tr>
<td>Trusted-Execution</td>
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<td>N</td>
<td>N</td>
<td>N</td>
<td>N</td>
<td>Y</td>
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<tr>
<td>Native TrustZone-M support</td>
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<td>N</td>
<td>N</td>
<td>N</td>
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<tr>
<td>TF-M integration</td>
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<td>N</td>
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<tr>
<td>Code relocation</td>
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<td>Y</td>
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<tr>
<td>SW-based vector table relaying</td>
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<td>Y</td>
<td>Y</td>
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<tr>
<td>HW-assisted timing functions</td>
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<td>N</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
</tr>
</tbody>
</table>
Notes

OS features

Threads

**Thread stack alignment** Each Zephyr thread is defined with its own stack memory. By default, Cortex-M enforces a double word thread stack alignment, see CONFIG_STACK_ALIGN_DOUBLE_WORD. If MPU-based HW-assisted stack overflow detection (CONFIG_MPU_STACK_GUARD) is enabled, thread stacks need to be aligned with a larger value, reflected by CONFIG_ARM_MPU_REGION_MIN_ALIGN_AND_SIZE. In Arm v6-M and Arm v7-M architecture variants, thread stacks are additionally required to be align with a value equal to their size, in applications that need to support user mode (CONFIG_USERSPACE). The thread stack sizes in that case need to be a power of two. This is all reflected by CONFIG_MPU_REQUIRES_POWER_OF_TWO_ALIGNMENT, that is enforced in Arm v6-M and Arm v7-M builds with user mode support.

**Stack pointers** While executing in thread mode the processor is using the Process Stack Pointer (PSP). The processor uses the Main Stack Pointer (MSP) while executing in handler mode, that is, while servicing exceptions and HW interrupts. Using PSP in thread mode facilitates thread stack pointer manipulation during thread context switching, without affecting the current execution context flow in handler mode.

In Arm Cortex-M builds a single interrupt stack memory is shared among exceptions and interrupts. The size of the interrupt stack needs to be selected taking into consideration nested interrupts, each pushing an additional stack frame. Developers can modify the interrupt stack size using CONFIG_ISR_STACK_SIZE.

The interrupt stack is also used during early boot so the kernel can initialize the main thread’s stack before switching to the main thread.

**Thread context switching** In Arm Cortex-M builds, the PendSV exception is used in order to trigger a context switch to a different thread. PendSV exception is always present in Cortex-M implementations. PendSV is configured with the lowest possible interrupt priority level, in all Cortex-M variants. The main reasons for that design are

- to utilize the tail chaining feature of Cortex-M processors, and thus limit the number of context switch operations that occur.
- to not impact the interrupt latency observed by HW interrupts.

As a result, context switch in Cortex-M is non-atomic, i.e. it may be preempted by HW interrupts, however, a context-switch operation must be completed before a new thread context-switch may start.

Typically a thread context-switch will perform the following operations

- When switching-out the current thread, the processor stores
  - the callee-saved registers (R4 - R11) in the thread’s container for callee-saved registers, which is located in kernel memory
  - the thread’s current operation mode
    * user or privileged execution mode
    * presence of an active floating point context

---

1 SysTick is optional in Cortex-M1
2 Stack limit checking only in Secure builds in Cortex-M23
the EXC_RETURN value of the current handler context (PendSV)
– the floating point callee-saved registers (S16 - S31) in the thread's container for FP callee-saved registers, if the current thread has an active FP context
– the PSP of the current thread which points to the beginning of the current thread's exception stack frame. The latter contains the caller-saved context and the return address of the switched-out thread.

• When switching-in a new thread the processor
  – restores the new thread's callee-saved registers from the thread's container for callee-saved registers
  – restores the new thread's operation mode
  – restores the FP callee-saved registers if the switched-in thread had an active FP context before being switched-out
  – re-programs the dynamic MPU regions to allow a user thread access its stack and application memories, and/or programs a stack-overflow MPU guard at the bottom of the thread's privileged stack
  – restores the PSP for the incoming thread and re-programs the stack pointer limit register (if applicable, see CONFIG_BUILTIN_STACK_GUARD)
  – optionally does a stack limit checking for the switched-in thread, if sentinel-based stack limit checking is enabled (see CONFIG_STACK_SENTINEL).

PendSV exception return sequence restores the new thread's caller-saved registers and the return address, as part of unstacking the exception stack frame.

The implementation of the context-switch mechanism is present in arch/arm/core/swap_helper.S.

Stack limit checking (Arm v8-M) Armv8-M and Armv8.1-M variants support stack limit checking using the MSPLIM and PSPLIM core registers. The feature is enabled when CONFIG_BUILTIN_STACK_GUARD is set. When stack limit checking is enabled, both the thread's privileged or user stack, as well as the interrupt stack are guarded by PSPLIM and MSPLIM registers, respectively. MSPLIM is configured once during kernel boot, while PSLIM is re-programmed during every thread context-switch or during system calls, when the thread switches from using its default stack to using its privileged stack, and vice versa. PSPLIM re-programming

• has a relatively low runtime overhead (programming is done with MSR instructions)
• does not impact interrupt latency
• does not require any memory areas to be reserved for stack guards
• does not make use of MPU regions

It is, therefore, considered as a lightweight but very efficient stack overflow detection mechanism in Cortex-M applications.

Stack overflows trigger the dedicated UsageFault exception provided by Arm v8-M.

Interrupt handling features This section describes certain aspects around exception and interrupt handling in Arm Cortex-M.

Interrupt priority levels The number of available (configurable) interrupt priority levels is determined by the number of implemented interrupt priority bits in NVIC; this needs to be described for each Cortex-M platform using DeviceTree.
Reserved priority levels  A number of interrupt priority levels are reserved for the OS.

By design, system fault exceptions have the highest priority level. In Baseline Cortex-M, this is actually enforced by hardware, as HardFault is the only available processor fault exception, and its priority is higher than any configurable exception priority.

In Mainline Cortex-M, the available fault exceptions (e.g. MemManageFault, UsageFault, etc.) are assigned the highest configurable priority level. (CONFIG_CPU_CORTEX_M_HAS_PROGRAMMABLE_FAULT_PRIOS signifies explicitly that the Cortex-M implementation supports configurable fault priorities.)

This priority level is never shared with HW interrupts (an exception to this rule is described below). As a result, processor faults occurring in regular ISRs will be handled by the corresponding fault handler and will not escalate to a HardFault, similar to processor faults occurring in thread mode.

SVC exception is normally configured with the highest configurable priority level (an exception to this rule will be described below). SVCs are used by the Zephyr kernel to dispatch system calls, trigger runtime system errors (e.g. Kernel oops or panic), or implement IRQ offloading.

In Baseline Cortex-M the priority level of SVC may be shared with other exceptions or HW interrupts that are also given the highest configurable priority level (As a result of this, kernel runtime errors during interrupt handling will escalate to HardFault. Additional logic in the fault handling routines ensures that such runtime errors are detected successfully).

In Mainline Cortex-M, however, the SVC priority level is reserved, thus normally it is only shared with the fault exceptions of configurable priority. This simplifies the fault handling routines in Mainline Cortex-M architecture, since runtime kernel errors are serviced by the SVC handler (i.e no HardFault escalation, even if the kernel errors occur in ISR context).

HW interrupts in Mainline Cortex-M builds are allocated a priority level lower than the SVC.

One exception to the above rules is when Zephyr applications support Zero Latency Interrupts (ZLIs). Such interrupts are designed to have a priority level higher than any HW or system interrupt. If the ZLI feature is enabled in Mainline Cortex-M builds (see CONFIG_ZERO_LATENCY_IRQS), then

- ZLIs are assigned the highest configurable priority level
- SVCs are assigned the second highest configurable priority level
- Regular HW interrupts are assigned priority levels lower than SVC.

The priority level configuration in Cortex-M is implemented in include/arch/arm/exception.h.

Locking and unlocking IRQs  In Baseline Cortex-M locking interrupts is implemented using the PRIMASK register.

```
arch_irq_lock()
```

will set the PRIMASK register to 1, eventually, masking all IRQs with configurable priority. While this fulfills the OS requirement of locking interrupts, the consequence is that kernel runtime errors (triggering SVCs) will escalate to HardFault.

In Mainline Cortex-M locking interrupts is implemented using the BASEPRI register (Mainline Cortex-M builds select CONFIG_CPU_CORTEX_M_HAS_BASEPRI to signify that BASEPRI register is implemented.). By modifying BASEPRI (or BASEPRI_MAX) arch_irq_lock() masks all system and HW interrupts with the exception of
This allows zero latency interrupts to be triggered inside OS critical sections. Additionally, this allows system (processor and kernel) faults to be handled by Zephyr in exactly the same way, regardless of whether IRQs have been locked or not when the error occurs. It also allows for system calls to be dispatched while IRQs are locked.

**Note:** Mainline Cortex-M fault handling is designed and configured in a way that all processor and kernel faults are handled by the corresponding exception handlers and never result in HardFault escalation. In other words, a HardFault may only occur in Zephyr applications that have modified the default fault handling configurations. The main reason for this design was to reserve the HardFault exception for handling exceptional error conditions in safety critical applications.

**Dynamic direct interrupts** Cortex-M builds support the installation of direct interrupt service routines during runtime. Direct interrupts are designed for performance-critical interrupt handling and do not go through all of the common Zephyr interrupt handling code.

Direct dynamic interrupts are enabled via switching on `CONFIG_DYNAMIC_DIRECT_INTERRUPTS`.

**Zero Latency interrupts** As described above, in Mainline Cortex-M applications, the Zephyr kernel reserves the highest configurable interrupt priority level for its own use (SVC). SVCs will not be masked by interrupt locking. Zero-latency interrupt can be used to set up an interrupt at the highest interrupt priority which will not be blocked by interrupt locking. To use the ZLI feature `CONFIG_ZERO_LATENCY_IRQS` needs to be enabled.

Zero latency IRQs have minimal interrupt latency, as they will always preempt regular HW or system interrupts.

Note, however, that since ZLI ISRs will run at a priority level higher than the kernel exceptions they cannot use any kernel functionality. Additionally, since the ZLI interrupt priority level is equal to processor fault priority level, faults occurring in ZLI ISRs will escalate to HardFault and will not be handled in the same way as regular processor faults. Developers need to be aware of this limitation.

**CPU Idling** The Cortex-M architecture port implements both `k_cpu_idle()` and `k_cpu_atomic_idle()`. The implementation is present in `arch/arm/core/cpu_idle.S`.

In both implementations, the processor will attempt to put the core to low power mode. In `k_cpu_idle()` the processor ends up executing WFI (Wait For Interrupt) instruction, while in `k_cpu_atomic_idle()` the processor will execute a WFE (Wait For Event) instruction.

When using the CPU idling API in Cortex-M it is important to note the following:

- Both `k_cpu_idle()` and `k_cpu_atomic_idle()` are assumed to be invoked with interrupts locked. This is taken care of by the kernel if the APIs are called by the idle thread.
- After waking up from low power mode, both functions will restore interrupts unconditionally, that is, regardless of the interrupt lock status before the CPU idle API was called.

The Zephyr CPU Idling mechanism is detailed in `CPU Idling`. 
Memory protection features  This section describes certain aspects around memory protection features in Arm Cortex-M applications.

User mode system calls  User mode is supported in Cortex-M platforms that implement the standard (Arm) MPU or a similar core peripheral logic for memory access policy configuration and control, such as the NXP MPU for Kinetis platforms. (Currently, CONFIG_ARCH_HAS_USERSPACE is selected if CONFIG_ARM_MPU is enabled by the user in the board default Kconfig settings).

A thread performs a system call by triggering a (synchronous) SVC exception, where

- up to 5 arguments are placed on registers R1 - R5
- system call ID is placed on register R6.

The SVC Handler will branch to the system call preparation logic, which will perform the following operations

- switch the thread’s PSP to point to the beginning of the thread’s privileged stack area, optionally reprogramming the PSPLIM if stack limit checking is enabled
- modify CONTROL register to switch to privileged mode
- modify the return address in the SVC exception stack frame, so that after exception return the system call dispatcher is executed (in thread privileged mode)

Once the system call execution is completed the system call dispatcher will restore the user’s original PSP and PSPLIM and switch the CONTROL register back to unprivileged mode before returning back to the caller of the system call.

System calls execute in thread mode and can be preempted by interrupts at any time. A thread may also be context-switched-out while doing a system call; the system call will resume as soon as the thread is switched-in again.

The system call dispatcher executes at SVC priority, therefore it cannot be preempted by HW interrupts (with the exception of ZLIs), which may observe some additional interrupt latency if they occur during a system call preparation.

MPU-assisted stack overflow detection  Cortex-M platforms with MPU may enable CONFIG_MPU_STACK_GUARD to enable the MPU-based stack overflow detection mechanism. The following points need to be considered when enabling the MPU stack guards

- stack overflows are triggering processor faults as soon as they occur
- the mechanism is essential for detecting stack overflows in supervisor threads, or user threads in privileged mode; stack overflows in threads in user mode will always be detected regardless of CONFIG_MPU_STACK_GUARD being set.
- stack overflows are always detected, however, the mechanism does not guarantee that no memory corruption occurs when supervisor threads overflow their stack memory
- CONFIG_MPU_STACK_GUARD will normally reserve one MPU region for programming the stack guard (in certain Arm v8-M configurations with CONFIG_MPU_GAP_FILLING enabled 2 MPU regions are required to implement the guard feature)
- MPU guards are re-programmed at every context-switch, adding a small overhead to the thread swap routine. Compared, however, to the CONFIG_BUILTIN_STACK_GUARD feature, no re-programming occurs during system calls.
- When CONFIG_HW_STACK_PROTECTION is enabled on Arm v8-M platforms the native stack limit checking mechanism is used by default instead of the MPU-based stack overflow detection mechanism; users may override this setting by manually enabling CONFIG_MPU_STACK_GUARD in these scenarios.
Memory map and MPU considerations

**Fixed MPU regions**  By default, when `CONFIG_ARM_MPU` is enabled a set of fixed MPU regions are programmed during system boot.

- One MPU region programs the entire flash area as read-execute. User can override this setting by enabling `CONFIG_MPU_ALLOW_FLASH_WRITE`, which programs the flash with RWX permissions. If `CONFIG_USERSPACE` is enabled unprivileged access on the entire flash area is allowed.

- One MPU region programs the entire SRAM area with privileged-only RW permissions. That is, an MPU region is utilized to disallow execute permissions on SRAM. (An exception to this setting is when `CONFIG_MPU_GAP_FILLING` is disabled (Arm v8-M only); in that case no SRAM MPU programming is done so the access is determined by the default Arm memory map policies, allowing for privileged-only RWX permissions on SRAM).

- All the memory regions defined in the devicetree with the property `zephyr,memory-attr` defining the MPU permissions for the memory region. See the next section for more details.

The above MPU regions are defined in `soc/arm/common/cortex_m/arm_mpu_regions`. Alternative MPU configurations are allowed by enabling `CONFIG_CPU_HAS_CUSTOM_FIXED_SOC_MPU_REGIONS`. When enabled, this option signifies that the Cortex-M SoC will define and configure its own fixed MPU regions in the SoC definition.

**Fixed MPU regions defined in devicetree**  When the property `zephyr,memory-attr` is present in a memory node, a new MPU region will be allocated and programmed during system boot. When used with the `zephyr,memory-region` devicetree compatible, it will result in a linker section being generated associated to that MPU region.

For example, to define a new non-cacheable memory region in devicetree:

```c
sram_no_cache: memory@20300000 {
    compatible = "zephyr,memory-region", "mmio-sram";
    reg = <0x20300000 0x100000>;
    zephyr,memory-region = "SRAM_NO_CACHE";
    zephyr,memory-attr = <( DT_MEM_ARM(ATR_MPU_RAM_NOCACHE) )>;
};
```

This will automatically create a new MPU entry in with the correct name, base, size and attributes gathered directly from the devicetree.

**Static MPU regions**  Additional static MPU regions may be programmed once during system boot. These regions are required to enable certain features

- a RX region to allow execution from SRAM, when `CONFIG_ARCH_HAS_RAMFUNC_SUPPORT` is enabled and users have defined functions to execute from SRAM.

- a RX region for relocating text sections to SRAM, when `CONFIG_CODE_DATA_RELOCATION_SRAM` is enabled

- a no-cache region to allow for a none-cacheable SRAM area, when `CONFIG_NOCACHE_MEMORY` is enabled

- a possibly unprivileged RW region for GCOV code coverage accounting area, when `CONFIG_COVERAGE_GCOV` is enabled

- a no-access region to implement null pointer dereference detection, when `CONFIG_NULL_PTR_EXCEPTION_DETECTION_MPU` is enabled

The boundaries of these static MPU regions are derived from symbols exposed by the linker, in `include/linker/linker-defs.h`.
Dynamic MPU regions  Certain thread-specific MPU regions may be re-programmed dynamically, at each thread context switch:

- an unprivileged RW region for the current thread's stack area (for user threads)
- a read-only region for the MPU stack guard
- unprivileged RW regions for the partitions of the current thread's application memory domain.

Considerations  The number of available MPU regions for a Cortex-M platform is a limited resource. Most platforms have 8 MPU regions, while some Cortex-M33 or Cortex-M7 platforms may have up to 16 MPU regions. Therefore there is a relatively strict limitation on how many fixed, static and dynamic MPU regions may be programmed simultaneously. For platforms with 8 available MPU regions it might not be possible to enable all the aforementioned features that require MPU region programming. In most practical applications, however, only a certain set of features is required and 8 MPU regions are, in many cases, sufficient.

In Arm v8-M processors the MPU architecture does not allow programmed MPU regions to overlap. CONFIG_MPU_GAP_FILLING controls whether the fixed MPU region covering the entire SRAM is programmed. When it does, a full SRAM area partitioning is required, in order to program the static and the dynamic MPU regions. This increases the total number of required MPU regions. When CONFIG_MPU_GAP_FILLING is not enabled the fixed MPU region covering the entire SRAM is not programmed, thus, the static and dynamic regions are simply programmed on top of the always-existing background region (full-SRAM partitioning is not required). Note, however, that the background SRAM region allows execution from SRAM, so when CONFIG_MPU_GAP_FILLING is not set Zephyr is not protected against attacks that attempt to execute malicious code from SRAM.

Floating point Services  Both unshared and shared FP registers mode are supported in Cortex-M (see Floating Point Services for more details).

When FPU support is enabled in the build (CONFIG_FPU is enabled), the sharing FP registers mode (CONFIG_FPU_SHARING) is enabled by default. This is done as some compiler configurations may activate a floating point context by generating FP instructions for any thread, regardless of whether floating point calculations are performed, and that context must be preserved when switching such threads in and out.

The developers can still disable the FP sharing mode in their application projects, and switch to Unshared FP registers mode, if it is guaranteed that the image code does not generate FP instructions outside the single thread context that is allowed (and supposed) to do so.

Under FPU sharing mode, the callee-saved FPU registers are saved and restored in context-switch, if the corresponding threads have an active FP context. This adds some runtime overhead on the swap routine. In addition to the runtime overhead, the sharing FPU mode

- requires additional memory for each thread to save the callee-saved FP registers
- requires additional stack memory for each thread, to stack the caller-saved FP registers, upon exception entry, if an FP context is active. Note, however, that since lazy stacking is enabled, there is no runtime overhead of FP context stacking in regular interrupts (FP state preservation is only activated in the swap routine in PendSV interrupt).

Misc

Chain-loadable images  Cortex-M applications may either be standalone images or chain-loadable, for instance, by a bootloader. Application images chain-loadable by bootloaders (or other applications) normally occupy a specific area in the flash denoted as their code partition. CONFIG_USE_DT_CODE_PARTITION will ensure that a Zephyr chain-loadable image will be linked into its code partition, specified in DeviceTree.
HW initialization at boot  In order to boot properly, chain-loaded applications may require that the core Arm hardware registers and peripherals are initialized in their reset values. Enabling CONFIG_INIT_ARCH_HW_AT_BOOT Zephyr to force the initialization of the internal Cortex-M architectural state during boot to the reset values as specified by the corresponding Arm architecture manual.

Software vector relaying  In Cortex-M platforms that implement the VTOR register (see CONFIG_CPU_CORTEX_M_HAS_VTOR), chain-loadable images relocate the Cortex-M vector table by updating the VTOR register with the offset of the image vector table.

Baseline Cortex-M platforms without VTOR register might not be able to relocate their vector table which remains at a fixed location. Therefore, a chain-loadable image will require an alternative way to route HW interrupts and system exceptions to its own vector table; this is achieved with software vector relaying.

When a bootloader image enables CONFIG_SW_VECTOR_RELAY it is able to relay exceptions and interrupts based on a vector table pointer that is set by the chain-loadable application. The latter sets the CONFIG_SW_VECTOR_RELAY_CLIENT option to instruct the boot sequence to set the vector table pointer in SRAM so that the bootloader can forward the exceptions and interrupts to the chain-loadable image's software vector table.

While this feature is intended for processors without VTOR register, it may also be used in Mainline Cortex-M platforms.

Code relocation  Cortex-M support the code relocation feature. When CONFIG_CODE_DATA_RELOCATION_SRAM is selected, Zephyr will relocate .text, data and .bss sections from the specified files and place it in SRAM. It is possible to relocate only parts of the code sections into SRAM, without relocating the whole image text and data sections. More details on the code relocation feature can be found in Code And Data Relocation.

Linking Cortex-M applications

Most Cortex-M platforms make use of the default Cortex-M GCC linker script in include/arch/arm/cortex-m/scripts/linked.ld, although it is possible for platforms to use a custom linker script as well.

CMSIS

Cortex-M CMSIS headers are hosted in a standalone module repository: zephyrproject-rtos/cortex-m. CONFIG_CPU_CORTEX_M selects CONFIG_HAS_CMSIS_CORE to signify that CMSIS headers are available for all supported Cortex-M variants.

Testing

A list of unit tests for the Cortex-M porting and miscellaneous features is present in tests/arch/arm/. The tests suites are continuously extended and new test suites are added, in an effort to increase the coverage of the Cortex-M architecture support in Zephyr.
QEMU

We use QEMU to verify the implemented features of the Cortex-M architecture port in Zephyr. Adequate coverage is achieved by defining and utilizing a list of QEMU targets, each with a specific architecture variant and Arm peripheral support list.

The table below lists the QEMU platform targets defined in Zephyr along with the corresponding Cortex-M implementation variant and the peripherals these targets emulate.

<table>
<thead>
<tr>
<th>QEMU target</th>
<th>Architecture variant</th>
<th>Emulated features</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>Arm v6-M</td>
<td>NVIC, BASEPRI, SysTick, MPU, FPU, SPLIM, TrustZone-M</td>
</tr>
<tr>
<td></td>
<td>Arm v7-M</td>
<td>NVIC, BASEPRI, SysTick, MPU, FPU, SPLIM, TrustZone-M</td>
</tr>
<tr>
<td></td>
<td>Arm v8-M</td>
<td>NVIC, BASEPRI, SysTick, MPU, FPU, SPLIM, TrustZone-M</td>
</tr>
<tr>
<td></td>
<td>Arm v8.1-M</td>
<td>NVIC, BASEPRI, SysTick, MPU, FPU, SPLIM, TrustZone-M</td>
</tr>
</tbody>
</table>

Maintainers & Collaborators

The status of the Arm Cortex-M architecture port in Zephyr is: maintained. The updated list of maintainers and collaborators for Cortex-M can be found in MAINTAINERS.yml.

7.1.3 Zephyr support status on RISC-V processors

Overview

This page describes current state of Zephyr for RISC-V processors. Currently, there's support for some boards, as well as Qemu support and support for some FPGA implementations such as neorv32 and litex_vexriscv.

Zephyr support includes PMP, user mode, several ISA extensions as well as semihosting.

User mode and PMP support

When the platform has Physical Memory Protection (PMP) support, enabling it on Zephyr allows user space support and stack protection to be selected.

ISA extensions

It's possible to set in Zephyr which ISA extensions (RV32/64I(E)MAFD(G)QC) are available on a given platform, by setting the appropriate RISCV_ISA_* kconfig. Look at arch/riscv/Kconfig.isa for more information.

Note that Zephyr SDK toolchain support may not be defined for all combinations.
SMP support

SMP is supported on RISC-V, but currently only on Qemu platforms. In order to test the SMP support, one can use `qemu_riscv32_smp` or `qemu_riscv64_smp` boards.

7.1.4 Semihosting Guide

Overview

Semihosting is a mechanism that enables code running on ARM and RISC-V targets to communicate and use the Input/Output facilities on a host computer that is running a debugger or emulator.

More complete documentation on the available functionality is available at the ARM Github documentation.

The RISC-V functionality borrows from the ARM definitions, as described at the RISC-V Github documentation.

File Operations

Semihosting enables files on the host computer to be opened, read, and modified by an application. This can be useful when attempting to validate the behaviour of code across datasets that are larger than what can fit into ROM of an emulated platform. File paths can be either absolute, or relative to the directory of the running process.

```c
const char *path = "./data.bin";
long file_len, bytes_read, fd;
uint8_t buffer[16];

/* Open the data file for reading */
fd = semihost_open(path, SEMIHOST_OPEN_RB);
if (fd < 0)
  return -ENOENT;

/* Read all data from the file */
file_len = semihost_flen(fd);
while(file_len > 0)
  bytes_read = semihost_read(fd, buffer, MIN(file_len, sizeof(buffer)));
  if (bytes_read < 0)
    break;
/* Process read data */
do_data_processing(buffer, bytes_read);
/* Update remaining length */
file_len -= bytes_read;
/* Close the file */
semihost_close(fd);
```

7.1.5 Additional Functionality

Additional functionality is available by running semihosting instructions directly with `semihost_exec()` with one of the instructions defined in `semihost_instr`. For complete documentation on the required arguments and return codes, see the ARM Github documentation.
API Reference

\textit{group} semihost

\textbf{Enums}

\textbf{enum} semihost\_instr

Semihosting instructions.

\textit{Values}:

- \textbf{enumerator} SEMIHOST\_OPEN = 0x01
  
  Open a file or stream on the host system.

- \textbf{enumerator} SEMIHOST\_ISTTY = 0x09
  
  Check whether a file is associated with a stream/terminal.

- \textbf{enumerator} SEMIHOST\_WRITE = 0x05
  
  Write to a file or stream.

- \textbf{enumerator} SEMIHOST\_READ = 0x06
  
  Read from a file at the current cursor position.

- \textbf{enumerator} SEMIHOST\_CLOSE = 0x02
  
  Closes a file on the host which has been opened by SEMIHOST\_OPEN.

- \textbf{enumerator} SEMIHOST\_FLEN = 0x0C
  
  Get the length of a file.

- \textbf{enumerator} SEMIHOST\_SEEK = 0x0A
  
  Set the file cursor to a given position in a file.

- \textbf{enumerator} SEMIHOST\_TMPNAM = 0x0D
  
  Get a temporary absolute file path to create a temporary file.

- \textbf{enumerator} SEMIHOST\_REMOVE = 0x0E
  
  Remove a file on the host system.
  
  Possibly insecure!

- \textbf{enumerator} SEMIHOST\_RENAME = 0x0F
  
  Rename a file on the host system.
  
  Possibly insecure!

- \textbf{enumerator} SEMIHOST\_WRITEC = 0x03
  
  Write one character to the debug terminal.

- \textbf{enumerator} SEMIHOST\_WRITE0 = 0x04
  
  Write a NULL terminated string to the debug terminal.
enumerator SEMIHOST_READC = 0x07
   Read one character from the debug terminal.

enumerator SEMIHOST_CLOCK = 0x10

enumerator SEMIHOST_ELAPSED = 0x30

enumerator SEMIHOST_TICKFREQ = 0x31

enumerator SEMIHOST_TIME = 0x11

enumerator SEMIHOST_ERRNO = 0x13
   Retrieve the errno variable from semihosting operations.

enumerator SEMIHOST_GET_CMDLINE = 0x15
   Get commandline parameters for the application to run with.

enumerator SEMIHOST_HEAPINFO = 0x16

enumerator SEMIHOST_ISSERROR = 0x08

enumerator SEMIHOST_SYSTEM = 0x12

e num semihost_open_mode
   Modes to open a file with.
   Behaviour corresponds to equivalent fopen strings. i.e. SEMIHOST_OPEN_RB_PLUS == "rb+"
   Values:

enumerator SEMIHOST_OPEN_R = 0

enumerator SEMIHOST_OPEN_RB = 1

enumerator SEMIHOST_OPEN_R_PLUS = 2

enumerator SEMIHOST_OPEN_RB_PLUS = 3

enumerator SEMIHOST_OPEN_W = 4

enumerator SEMIHOST_OPEN_WB = 5

enumerator SEMIHOST_OPEN_W_PLUS = 6

enumerator SEMIHOST_OPEN_WB_PLUS = 7

enumerator SEMIHOST_OPEN_A = 8
enumerator SEMIHOST_OPEN_AB = 9
enumerator SEMIHOST_OPEN_A_PLUS = 10
enumerator SEMIHOST_OPEN_AB_PLUS = 11

Functions

long semihost_exec(enum semihost_instr instr, void *args)
    Manually execute a semihosting instruction.
    Parameters
    • instr – instruction code to run
    • args – instruction specific arguments
    Returns
    integer return code of instruction

char semihost_poll_in(void)
    Read a byte from the console.
    Returns
    char byte read from the console.

void semihost_poll_out(char c)
    Write a byte to the console.
    Parameters
    • c – byte to write to console

long semihost_open(const char *path, long mode)
    Open a file on the host system.
    Parameters
    • path – file path to open. Can be absolute or relative to current directory
              of the running process.
    • mode – value from semihost_open_mode.
    Return values
    • handle – positive handle on success.
    • -1 – on failure.

long semihost_close(long fd)
    Close a file.
    Parameters
    • fd – handle returned by semihost_open.
    Return values
    • 0 – on success.
    • -1 – on failure.
long semihost_flen(long fd)
Query the size of a file.

Parameters
- fd – handle returned by semihost_open.

Return values
- positive – file size on success.
- -1 – on failure.

long semihost_seek(long fd, long offset)
Seeks to an absolute position in a file.

Parameters
- fd – handle returned by semihost_open.
- offset – offset from the start of the file in bytes.

Return values
- 0 – on success.
- -errno – negative error code on failure.

long semihost_read(long fd, void *buf, long len)
Read the contents of a file into a buffer.

Parameters
- fd – handle returned by semihost_open.
- buf – buffer to read data into.
- len – number of bytes to read.

Return values
- read – number of bytes read on success.
- -errno – negative error code on failure.

long semihost_write(long fd, const void *buf, long len)
Write the contents of a buffer into a file.

Parameters
- fd – handle returned by semihost_open.
- buf – buffer to write data from.
- len – number of bytes to write.

Return values
- 0 – on success.
- -errno – negative error code on failure.

7.1.6 x86 Developer Guide

Overview
This page contains information on certain aspects when developing for x86-based platforms.
Virtual Memory

During very early boot, page tables are loaded so technically the kernel is executing in virtual address space. By default, physical and virtual memory are identity mapped and thus giving the appearance of execution taking place in physical address space. The physical address space is marked by kconfig `CONFIG_SRAM_BASE_ADDRESS` and `CONFIG_SRAM_SIZE` while the virtual address space is marked by `CONFIG_KERNEL_VM_BASE` and `CONFIG_KERNEL_VM_SIZE`. Note that `CONFIG_SRAM_OFFSET` controls where the Zephyr kernel is being placed in the memory, and its counterpart `CONFIG_KERNEL_VM_OFFSET`.

Separate Virtual Address Space from Physical Address Space  On 32-bit x86, it is possible to have separate physical and virtual address space. Code and data are linked in virtual address space, but are still loaded in physical memory. However, during boot, code and data must be available and also addressable in physical address space before `vm_enter` inside `arch/x86/core/ia32/crt0.S`. After `vm_enter`, code execution is done via virtual addresses and data can be referred via their virtual addresses. This is possible as the page table generation script (`arch/x86/gen_mmu.py`) identity maps the physical addresses at the page directory level, in addition to mapping virtual addresses to the physical memory. Later in the boot process, the entries for identity mapping at the page directory level are cleared in `z_x86_mmu_init()`, effectively removing the identity mapping of physical memory. This unmapping must be done for userspace isolation or else they would be able to access restricted memory via physical addresses. Since the identity mapping is done at the page directory level, there is no need to allocate additional space for the page table. However, additional space may still be required for additional page directory table.

There are restrictions on where virtual address space can be:

- Physical and virtual address spaces must be disjoint. This is required as the entries in page directory table will be cleared. If they are not disjoint, it would clear the entries needed for virtual addresses.
  - If `CONFIG_X86_PAE` is enabled (=y), each address space must reside in their own 1GB region, due to each entry of PDP (Page Directory Pointer) covers 1GB of memory. For example:
    - Assuming `CONFIG_SRAM_OFFSET` and `CONFIG_KERNEL_VM_OFFSET` are both `0x0`.
    - `CONFIG_SRAM_BASE_ADDRESS == 0x00000000` and `CONFIG_KERNEL_VM_BASE = 0x40000000` is valid, while `CONFIG_SRAM_BASE_ADDRESS == 0x00000000` and `CONFIG_KERNEL_VM_BASE = 0x20000000` is not.
  - If `CONFIG_X86_PAE` is disabled (=n), each address space must reside in their own 4MB region, due to each entry of PD (Page Directory) covers 4MB of memory.
  - Both `CONFIG_SRAM_BASE_ADDRESS` and `CONFIG_KERNEL_VM_BASE` must also align with the starting addresses of targeted regions.

Specifying Additional Memory Mappings at Build Time

The page table generation script (`arch/x86/gen_mmu.py`) generates the necessary multi-level page tables for code execution and data access using the kernel image produced by the first linker pass. Additional command line arguments can be passed to the script to generate additional memory mappings. This is useful for static mappings and/or device MMIO access during very early boot. To pass extra command line arguments to the script, populate a CMake list named `X86_EXTRA_GEN_MMU_ARGUMENTS` in the board configuration file. Here is an example:

```makefile
set(X86_EXTRA_GEN_MMU_ARGUMENTS
    -m map 0xA0000000,0x2000
    -m map 0x80000000,0x400000,LWUX,0xB0000000)
```
The argument --map takes the following value: `<physical address>,<size>[,<flags:LUWX>[,"<virtual address>"]],` where:

- `<physical address>` is the physical address of the mapping. (Required)
- `<size>` is the size of the region to be mapped. (Required)
- `<flags>` is the flag associated with the mapping: (Optional)
  - `L`: Large page at the page directory level.
  - `U`: Allow userspace access.
  - `W`: Read/write.
  - `X`: Allow execution.
  - `D`: Cache disabled.
  
  * Default is small page (4KB), supervisor only, read only, and execution disabled.
- `<virtual address>` is the virtual address of the mapping. (Optional)

Note that specifying additional memory mappings requires larger storage space for the pre-allocated page tables (both kernel and per-domain tables). `CONFIG_X86_EXTRA_PAGE_TABLE_PAGES` is needed to specify how many more memory pages to be reserved for the page tables. If the needed space is not exactly the same as required space, the `gen_mmu.py` script will print out a message indicating what needs to be the value for the kconfig.

## 7.2 Barriers API

```
7.2. Barriers API 2905
```

```
group barrier_apis

Functions

ALWAYS_INLINE static void barrier_dmem_fence_full(void)
  Full/sequentially-consistent data memory barrier.
  This routine acts as a synchronization fence between threads and prevents re-ordering
  of data accesses instructions across the barrier instruction.

ALWAYS_INLINE static void barrier_dsync_fence_full(void)
  Full/sequentially-consistent data synchronization barrier.
  This routine acts as a synchronization fence between threads and prevents re-
  ordering of data accesses instructions across the barrier instruction like `barrier_dmem_fence_full()
  `, but has the additional effect of blocking execution of any fur-
  ther instructions, not just loads or stores, or both, until synchronization is complete.

  **Note:** When not supported by hardware or architecture, this instruction falls back to
  a full/sequentially-consistent data memory barrier.

ALWAYS_INLINE static void barrier_isync_fence_full(void)
  Full/sequentially-consistent instruction synchronization barrier.
  This routine is used to guarantee that any subsequent instructions are fetched and to
  ensure any previously executed context-changing operations, such as writes to sys-
  tem control registers, have completed by the time the routine completes. In hardware
terms, this might mean that the instruction pipeline is flushed, for example.
```
Note: When not supported by hardware or architecture, this instruction falls back to a compiler barrier.

7.3 Cache Interface

This is a high-level guide to cache interface and Kconfig options related to cache controllers. See Cache API for API reference material.

Zephyr has different Kconfig options to control how the cache controller is implemented and controlled.

- \texttt{CONFIG\_CPU\_HAS\_DCACHE} / \texttt{CONFIG\_CPU\_HAS\_ICACHE}: these hidden options should be selected at SoC / platform level when the CPU actually supports a data or instruction cache. The cache controller can be in the core or can be an external cache controller for which a driver is provided.

These options have the goal to document an available feature and should be set whether we plan to support and use the caches in Zephyr or not.

- \texttt{CONFIG\_DCACHE} / \texttt{CONFIG\_ICACHE}: these options must be selected when support for data or instruction cache is present and working in zephyr.

All the code paths related to cache control must be conditionally enabled depending on these symbols. When the symbol is set the cache is considered enabled and used.

These symbols say nothing about the actual API interface exposed to the user. For example a platform using the data cache can enable the \texttt{CONFIG\_DCACHE} symbol and use some HAL exported function in some platform-specific code to enable and manage the d-cache.

- \texttt{CONFIG\_CACHE\_MANAGEMENT}: this option must be selected when the cache operations are exposed to the user through a standard API (see Cache API).

When this option is enabled we assume that all the cache functions are implemented in the architectural code or in an external cache controller driver.

- \texttt{CONFIG\_ARCH\_CACHE} / \texttt{CONFIG\_EXTERNAL\_CACHE}: mutually exclusive options for \texttt{CACHE\_TYPE} used to define whether the cache operations are implemented at arch level or using an external cache controller with a provided driver.

  - \texttt{CONFIG\_ARCH\_CACHE}: the cache API is implemented by the arch code
  
  - \texttt{CONFIG\_EXTERNAL\_CACHE}: the cache API is implemented by a driver that supports the external cache controller. In this case the driver must be located as usual in the \texttt{drivers/ cache/ directory}.

7.3.1 Cache API

\texttt{group} cache\_interface

\texttt{Functions}

\texttt{ALWAYS\_INLINE static void sys\_cache\_data\_enable(void)}

Enable the d-cache.

Enable the data cache
ALWAYS_INLINE static void sys_cache_data_disable(void)
   Disable the d-cache.
   Disable the data cache

ALWAYS_INLINE static void sys_cache_instr_enable(void)
   Enable the i-cache.
   Enable the instruction cache

ALWAYS_INLINE static void sys_cache_instr_disable(void)
   Disable the i-cache.
   Disable the instruction cache

ALWAYS_INLINE static int sys_cache_data_flush_all(void)
   Flush the d-cache.
   Flush the whole data cache.

   **Return values**
   * 0 – If succeeded.
   * -ENOTSUP – If not supported.
   * -errno – Negative errno for other failures.

ALWAYS_INLINE static int sys_cache_instr_flush_all(void)
   Flush the i-cache.
   Flush the whole instruction cache.

   **Return values**
   * 0 – If succeeded.
   * -ENOTSUP – If not supported.
   * -errno – Negative errno for other failures.

ALWAYS_INLINE static int sys_cache_data_invd_all(void)
   Invalidate the d-cache.
   Invalidate the whole data cache.

   **Return values**
   * 0 – If succeeded.
   * -ENOTSUP – If not supported.
   * -errno – Negative errno for other failures.

ALWAYS_INLINE static int sys_cache_instr_invd_all(void)
   Invalidate the i-cache.
   Invalidate the whole instruction cache.

   **Return values**
   * 0 – If succeeded.
   * -ENOTSUP – If not supported.
   * -errno – Negative errno for other failures.

ALWAYS_INLINE static int sys_cache_data_flush_and_invd_all(void)
   Flush and Invalidate the d-cache.
   Flush and Invalidate the whole data cache.

7.3. Cache Interface
Return values
- 0 – If succeeded.
- -ENOTSUP – If not supported.
- -errno – Negative errno for other failures.

ALWAYS_INLINE static int sys_cache_instr_flush_and_invd_all(void)
Flush and Invalidate the i-cache.

Flush and Invalidate the whole instruction cache.

Return values
- 0 – If succeeded.
- -ENOTSUP – If not supported.
- -errno – Negative errno for other failures.

int sys_cache_data_flush_range(void *addr, size_t size)
Flush an address range in the d-cache.
Flush the specified address range of the data cache.

Note: the cache operations act on cache line. When multiple data structures share
the same cache line being flushed, all the portions of the data structures sharing the
same line will be flushed. This is usually not a problem because writing back is a
non-destructive process that could be triggered by hardware at any time, so having an
aligned addr or a padded size is not strictly necessary.

Parameters
- addr – Starting address to flush.
- size – Range size.

Return values
- 0 – If succeeded.
- -ENOTSUP – If not supported.
- -errno – Negative errno for other failures.

ALWAYS_INLINE static int sys_cache_instr_flush_range(void *addr, size_t size)
Flush an address range in the i-cache.
Flush the specified address range of the instruction cache.

Note: the cache operations act on cache line. When multiple data structures share
the same cache line being flushed, all the portions of the data structures sharing the
same line will be flushed. This is usually not a problem because writing back is a
non-destructive process that could be triggered by hardware at any time, so having an
aligned addr or a padded size is not strictly necessary.

Parameters
- addr – Starting address to flush.
- size – Range size.

Return values
• 0 – If succeeded.
• -ENOTSUP – If not supported.
• -errno – Negative errno for other failures.

int sys_cache_data_invd_range(void *addr, size_t size)
Invalidates an address range in the d-cache.

Invalidate the specified address range of the data cache.

**Note:** the cache operations act on cache line. When multiple data structures share the same cache line being invalidated, all the portions of the non-read-only data structures sharing the same line will be invalidated as well. This is a destructive process that could lead to data loss and/or corruption. When `addr` is not aligned to the cache line and/or `size` is not a multiple of the cache line size the behaviour is undefined.

**Parameters**
- `addr` – Starting address to invalidate.
- `size` – Range size.

**Return values**
- 0 – If succeeded.
- -ENOTSUP – If not supported.
- -errno – Negative errno for other failures.

ALWAYS_INLINE static int sys_cache_instr_invd_range(void *addr, size_t size)
Invalidates an address range in the i-cache.

Invalidate the specified address range of the instruction cache.

**Note:** the cache operations act on cache line. When multiple data structures share the same cache line being invalidated, all the portions of the non-read-only data structures sharing the same line will be invalidated as well. This is a destructive process that could lead to data loss and/or corruption. When `addr` is not aligned to the cache line and/or `size` is not a multiple of the cache line size the behaviour is undefined.

**Parameters**
- `addr` – Starting address to invalidate.
- `size` – Range size.

**Return values**
- 0 – If succeeded.
- -ENOTSUP – If not supported.
- -errno – Negative errno for other failures.

int sys_cache_data_flush_and_invd_range(void *addr, size_t size)
Flush and Invalidate an address range in the d-cache.

Flush and Invalidate the specified address range of the data cache.
**Note:** the cache operations act on cache line. When multiple data structures share the same cache line being flushed, all the portions of the data structures sharing the same line will be flushed before being invalidated. This is usually not a problem because writing back is a non-destructive process that could be triggered by hardware at any time, so having an aligned `addr` or a padded size is not strictly necessary.

**Parameters**
- `addr` – Starting address to flush and invalidate.
- `size` – Range size.

**Return values**
- 0 – If succeeded.
- -ENOTSUP – If not supported.
- -errno – Negative errno for other failures.

```c
ALWAYS_INLINE static int sys_cache_instr_flush_and_invnd_range(void *addr, size_t size)
```
Flush and Invalidate an address range in the i-cache.
Flush and Invalidate the specified address range of the instruction cache.

**Note:** the cache operations act on cache line. When multiple data structures share the same cache line being flushed, all the portions of the data structures sharing the same line will be flushed before being invalidated. This is usually not a problem because writing back is a non-destructive process that could be triggered by hardware at any time, so having an aligned `addr` or a padded size is not strictly necessary.

**Parameters**
- `addr` – Starting address to flush and invalidate.
- `size` – Range size.

**Return values**
- 0 – If succeeded.
- -ENOTSUP – If not supported.
- -errno – Negative errno for other failures.

```c
ALWAYS_INLINE static size_t sys_cache_data_line_size_get(void)
```
Get the the d-cache line size.
The API is provided to get the data cache line.
The cache line size is calculated (in order of priority):

- At run-time when `CONFIG_DCACHE_LINE_SIZE_DETECT` is set.
- At compile time using the value set in `CONFIG_DCACHE_LINE_SIZE`.
- At compile time using the `d-cache-line-size` CPU0 property of the DT.
- 0 otherwise

**Return values**
• **size** – Size of the d-cache line.
• **0** – If the d-cache is not enabled.

`ALWAYS_INLINE static size_t sys_cache_instr_line_size_get(void)`
Get the i-cache line size.
The API is provided to get the instruction cache line.
The cache line size is calculated (in order of priority):

• At run-time when `CONFIG_ICACHE_LINE_SIZE_DETECT` is set.
• At compile time using the value set in `CONFIG_ICACHE_LINE_SIZE`.
• At compile time using the `i-cache-line-size` CPU0 property of the DT.
• **0** otherwise

**Return values**
• **size** – Size of the d-cache line.
• **0** – If the d-cache is not enabled.

`ALWAYS_INLINE static bool sys_cache_is_ptr_cached(void *ptr)`
Test if a pointer is in cached region.
Some hardware may map the same physical memory twice so that it can be seen in both (incoherent) cached mappings and a coherent “shared” area. This tests if a particular pointer is within the cached, coherent area.

**Parameters**
• **ptr** – Pointer

**Return values**
• **True** – if pointer is in cached region.
• **False** – if pointer is not in cached region.

`ALWAYS_INLINE static bool sys_cache_is_ptr_uncached(void *ptr)`
Test if a pointer is in un-cached region.
Some hardware may map the same physical memory twice so that it can be seen in both (incoherent) cached mappings and a coherent “shared” area. This tests if a particular pointer is within the un-cached, incoherent area.

**Parameters**
• **ptr** – Pointer

**Return values**
• **True** – if pointer is not in cached region.
• **False** – if pointer is in cached region.

`ALWAYS_INLINE static void *sys_cache_cached_ptr_get(void *ptr)`
Return cached pointer to a RAM address.
This function takes a pointer to any addressable object (either in cacheable memory or not) and returns a pointer that can be used to refer to the same memory through the L1 data cache. Data read through the resulting pointer will reflect locally cached values on the current CPU if they exist, and writes will go first into the cache and be written back later.
See also:
arch_uncached_ptr()

Note: This API returns the same pointer if CONFIG_CACHE_DOUBLEMAP is not enabled.

Parameters
• ptr – A pointer to a valid C object

Returns
A pointer to the same object via the L1 dcache

ALWAYS_INLINE static void *sys_cache_uncached_ptr_get(void *ptr)
Return uncached pointer to a RAM address.
This function takes a pointer to any addressable object (either in cacheable memory or not) and returns a pointer that can be used to refer to the same memory while bypassing the L1 data cache. Data in the L1 cache will not be inspected nor modified by the access.

See also:
arch_cached_ptr()

Note: This API returns the same pointer if CONFIG_CACHE_DOUBLEMAP is not enabled.

Parameters
• ptr – A pointer to a valid C object

Returns
A pointer to the same object bypassing the L1 dcache

7.4 Zephyr’s device emulators/simulators

7.4.1 Overview
Zephyr includes in its codebase a set of device emulators/simulators. With this we refer to SW components which are built together with the embedded SW and present themselves as devices of a given class to the rest of the system.
These device emulators/simulators can be built for any target which has sufficient RAM and flash, even if some may have extra functionality which is only available in some targets.

Note:
Zephyr also includes and uses many other types of simulators/emulators, including CPU and platform simulators, radio simulators, and several build targets which allow running the embedded code in the development host.
Some of Zephyr communication controllers/drivers include also either loopback modes or loopback devices.
This page does not cover any of these.

Note: Drivers which are specific to some platform, like for example the native_sim specific drivers which emulate a peripheral class by connecting to host APIs are not covered by this page.

7.4.2 Available Emulators

ADC emulator
- A fake driver which pretends to be actual ADC, and can be used for testing higher-level API for ADC devices.
  - Main Kconfig option: CONFIG_ADC_EMUL
  - DT binding: zephyr,adc-emul

DMA emulator
- Emulated DMA controller
  - Main Kconfig option: CONFIG_DMA_EMUL
  - DT binding: zephyr,dma-emul

EEPROM emulator
- Emulate an EEPROM on a flash partition
  - Main Kconfig option: CONFIG_EEPROM_EMULATOR
  - DT binding: zephyr,emu-eeprom

EEPROM simulator
- Emulate an EEPROM on RAM
  - Main Kconfig option: CONFIG_EEPROM_SIMULATOR
  - DT binding: zephyr,sim-eeprom
  - Note: For native targets it is also possible to keep the content as a file on the host filesystem.

External bus and bus connected peripheral emulators
  - Documentation
  - Allow emulating external buses like I2C or SPI and peripherals connected to them.

Flash simulator
- Emulate a flash on RAM
  - Main Kconfig option: CONFIG_FLASH_SIMULATOR
  - DT binding: zephyr,sim-flash
  - Note: For native targets it is also possible to keep the content as a file on the host filesystem. Check the native_sim flash simulator section.

GPIO emulator
- Emulated GPIO controllers which can be driven from SW
  - Main Kconfig option: CONFIG_GPIO_EMUL
  - DT binding: zephyr,gpio-emul

I2C emulator
7.5 External Bus and Bus Connected Peripherals Emulators

7.5.1 Overview

Zephyr supports a simple emulator framework to support testing of external peripheral drivers without requiring real hardware.

Emulators are used to emulate external hardware devices, to support testing of various subsystems. For example, it is possible to write an emulator for an I2C compass such that it appears on the I2C bus and can be used just like a real hardware device.

Emulators often implement special features for testing. For example a compass may support returning bogus data if the I2C bus speed is too high, or may return invalid measurements if calibration has not yet been completed. This allows for testing that high-level code can handle these situations correctly. Test coverage can therefore approach 100% if all failure conditions are emulated.

7.5.2 Concept

The diagram below shows application code / high-level tests at the top. This is the ultimate application we want to run.

Below that are peripheral drivers, such as the AT24 EEPROM driver. We can test peripheral drivers using an emulation driver connected via a emulated I2C controller/emulator which passes I2C traffic from the AT24 driver to the AT24 simulator.

Separately we can test the STM32 and NXP I2C drivers on real hardware using API tests. These require some sort of device attached to the bus, but with this, we can validate much of the driver functionality.

Putting the two together, we can test the application and peripheral code entirely on native_sim. Since we know that the I2C driver on the real hardware works, we should expect the application and peripheral drivers to work on the real hardware also.
Using the above framework we can test an entire application (e.g. Embedded Controller) on native_sim using emulators for all non-chip drivers.

With this approach we can:

- Write individual tests for each driver (green), covering all failure modes, error conditions, etc.
- Ensure 100% test coverage for drivers (green)
- Write tests for combinations of drivers, such as GPIOs provided by an I2C GPIO expander driver talking over an I2C bus, with the GPIOs controlling a charger. All of this can work in the emulated environment or on real hardware.
- Write a complex application that ties together all of these pieces and runs on native_sim. We can develop on a host, use source-level debugging, etc.
- Transfer the application to any board which provides the required features (e.g. I2C, enough GPIOs), by adding Kconfig and devicetree fragments.

### 7.5.3 Creating a Device Driver Emulator

The emulator subsystem is modeled on the Device Driver Model. You create an emulator instance using one of the `EMUL_DT_DEFINE()` or `EMUL_DT_INST_DEFINE()` APIs.

Emulators for peripheral devices reuse the same devicetree node as the real device driver. This means that your emulator defines `DT_DRV_COMPAT` using the same compat value from the real driver.

```c
/* From drivers/sensor/bm160/bm160.c */
#define DT_DRV_COMPAT bosch_bmi160

/* From drivers/sensor/bmi160/emul_bmi160.c */
#define DT_DRV_COMPAT bosch_bmi160
```
The `EMUL_DT_DEFINE()` function accepts two API types:

1. `bus_api` - This points to the API for the upstream bus that the emulator connects to. The `bus_api` parameter is required. The supported emulated bus types include I2C, SPI, and eSPI.

2. `_backend_api` - This points to the device-class specific backend API for the emulator. The `_backend_api` parameter is optional.

The diagram below demonstrates the logical organization of the `bus_api` and `_backend_api` using the BC1.2 charging detector driver as the model device-class.

![Diagram showing the logical organization of API functions for BC1.2 charging detector driver]

The real code is shown in green, while the emulator code is shown in yellow.

The `bus_api` connects the BC1.2 emulators to the `native_sim` I2C controller. The real BC1.2 drivers are unchanged and operate exactly as if there was a physical I2C controller present in the system. The `native_sim` I2C controller uses the `bus_api` to initiate register reads and writes to the emulator.

The `_backend_api` provides a mechanism for tests to manipulate the emulator out of band. Each device class defines its own API functions. The backend API functions focus on high-level behavior and do not provide hooks for specific emulators.

In the case of the BC1.2 charging detector the backend API provides functions to simulate connecting and disconnecting a charger to the emulated BC1.2 device. Each emulator is responsible for updating the correct vendor specific registers and potentially signalling an interrupt.

Example test flow:

1. Test registers BC1.2 detection callback using the Zephyr BC1.2 driver API.
2. Test connects a charger using the BC1.2 emulator backend.
3. Test verifies B1.2 detection callback invoked with correct charger type.
4. Test disconnects a charger using the BC1.2 emulator backend. With this architecture, the same test can be used with all supported drivers in the same driver class.

7.5.4 Available Emulators

Zephyr includes the following emulators:

- I2C emulator driver, allowing drivers to be connected to an emulator so that tests can be performed without access to the real hardware
- SPI emulator driver, which does the same for SPI
- eSPI emulator driver, which does the same for eSPI. The emulator is being developed to support more functionalities.

7.5.5 Samples

Here are some examples present in Zephyr:

1. Bosch BMI160 sensor driver connected via both I2C and SPI to an emulator:

```
west build -b native_sim tests/drivers/sensor/accel/
```

2. The same test can be built with a second EEPROM which is an Atmel AT24 EEPROM driver connected via I2C to an emulator:

```
west build -b native_sim tests/drivers/eeprom/api -- -DDTC_OVERLAY_FILE=at2x_emul.
 DOVERLAY_CONFIG=at2x_emul.conf
```

API Reference

**group io_emulators**

Emulators used to test drivers and higher-level code that uses them.

**Defines**

- **EMUL_DT_NAME_GET(node_id)**
  
  Use the devicetree node identifier as a unique name.

  **Parameters**

  - node_id – A devicetree node identifier

- **EMUL_DT_DEFINE(node_id, init_fn, data_ptr, cfg_ptr, bus_api, _backend_api)**

  Define a new emulator.

  This adds a new struct emul to the linker list of emulations. This is typically used in your emulator's `DT_INST_FOREACH_STATUS_OKAY()` clause.

  **Parameters**

  - node_id – Node ID of the driver to emulate (e.g. `DT_DRV_INST(n)`); the node_id MUST have a corresponding `DEVICE_DT_DEFINE()`.

  - init_fn – function to call to initialise the emulator (see emul_init type-def)
• data_ptr – emulator-specific data
• cfg_ptr – emulator-specific configuration data
• bus_api – emulator-specific bus api
• _backend_api – emulator-specific backend api

EMUL_DT_INST_DEFINE(inst, ...
Like EMUL_DT_DEFINE(), but uses an instance of a DT_DRV_COMPAT compatible instead of a node identifier.

Parameters
• inst – instance number. The node_id argument to EMUL_DT_DEFINE is set to DT_DRV_INST(inst).
• ... – other parameters as expected by EMUL_DT_DEFINE.

EMUL_DT_GET(node_id)
Get a const struct emul* from a devicetree node identifier.

Returns a pointer to an emulator object created from a devicetree node, if any device was allocated by an emulator implementation.

If no such device was allocated, this will fail at linker time. If you get an error that looks like undefined reference to __device_dts_ord_<N>, that is what happened. Check to make sure your emulator implementation is being compiled, usually by enabling the Kconfig options it requires.

Parameters
• node_id – A devicetree node identifier

Returns
A pointer to the emul object created for that node

EMUL_DT_GET_OR_NULL(node_id)
Utility macro to obtain an optional reference to an emulator.

If the node identifier refers to a node with status okay, this returns EMUL_DT_GET(node_id). Otherwise, it returns NULL.

Parameters
• node_id – A devicetree node identifier

Returns
a emul reference for the node identifier, which may be NULL.

Typedefs

typedef int (*emul_init_t)(const struct emul *emul, const struct device *parent)
Standard callback for emulator initialisation providing the initialiser record and the device that calls the emulator functions.

Param emul
Emulator to init

Param parent
Parent device that is using the emulator
Enums

```
enum emul_bus_type
    The types of supported buses.

Values:

enumerator EMUL_BUS_TYPE_I2C
enumerator EMUL_BUS_TYPE_ESPI
enumerator EMUL_BUS_TYPE_SPI
enumerator EMUL_BUS_TYPE_NONE
```

Functions

```
int emul_init_for_bus(const struct device *dev)
    Set up a list of emulators.

Parameters
    • dev – Device the emulators are attached to (e.g. an I2C controller)

Returns
    0 if OK
    negative value on error
```

```
const struct emul *emul_get_binding(const char *name)
    Retrieve the emul structure for an emulator by name.

Emulator objects are created via the EMUL_DT_DEFINE() macro and placed in memory by the linker. If the emulator structure is needed for custom API calls, it can be retrieved by the name that the emulator exposes to the system (this is the devicetree node's label by default).

Parameters
    • name – Emulator name to search for. A null pointer, or a pointer to an empty string, will cause NULL to be returned.

Returns
    pointer to emulator structure; NULL if not found or cannot be used.
```

```
struct emul_link_for_bus
    #include <emul.h> Structure uniquely identifying a device to be emulated.
```

```
struct emul_list_for_bus
    #include <emul.h> List of emulators attached to a bus.
```

Public Members
const struct emul_link_for_bus *children
   Identifiers for children of the node.

unsigned int num_children
   Number of children of the node.

struct no_bus_emul
   #include <emul.h> Emulator API stub when an emulator is not actually placed on a bus.

struct emul
   #include <emul.h> An emulator instance - represents the target emulated device/peripheral that is interacted with through an emulated bus.
   Instances of emulated bus nodes (e.g. i2c_emul) and emulators (i.e. struct emul) are exactly 1..1

Public Members

emul_init_t init
   function used to initialise the emulator state

const struct device *dev
   handle to the device for which this provides low-level emulation

const void *cfg
   Emulator-specific configuration data.

void *data
   Emulator-specific data.

enum emul_bus_type bus_type
   The bus type that the emulator is attached to.

const void *backend_api
   Address of the API structure exposed by the emulator instance.

union bus
   #include <emul.h> Pointer to the emulated bus node.

Public Members

struct i2c_emul *i2c
struct espi_emul *espi
struct spi_emul *spi
struct no_bus_emul *none
7.6 Peripherals

7.6.1 1-Wire Bus

Overview

1-Wire is a low speed half-duplex serial bus using only a single wire plus ground for both data transmission and device power supply. Similarly to I2C, 1-Wire uses a bidirectional open-collector data line, and is a single master multidrop bus. This means one master initiates all data exchanges with the slave devices. The 1-Wire bus supports longer bus lines than I2C, while it reaches speeds of up to 15.4 kbps in standard mode and up to 125 kbps in overdrive mode. Reliable communication in standard speed configuration is possible with 10 nodes over a bus length of 100 meters. Using overdrive speed, 3 nodes on a bus of 10 meters length are expected to work solid. Optimized timing parameters and fewer nodes on the bus may allow to reach larger bus extents.

The implementation details are specified in the BOOK OF IBUTTON STANDARDS.

![Fig. 1: A typical 1-Wire bus topology](image)

**W1 Master API**  Zephyr’s 1-Wire Master API is used to interact with 1-Wire slave devices like temperature sensors and serial memories.

In Zephyr this API is split into the following layers.

- The link layer handles basic communication functions such as bus reset, presence detect and bit transfer operations. It is the only hardware-dependent layer in Zephyr. This layer is supported by a driver using the Zephyr Universal Asynchronous Receiver-Transmitter (UART) interface, which should work on most Zephyr platforms. In the future, a GPIO/Timer based driver and hardware specific drivers might be added.

- The 1-Wire network layer handles all means for slave identification and bus arbitration. This includes ROM commands like Match ROM, or Search ROM.
  - All slave devices have a unique 64-bit identification number, which includes a 8-bit 1-Wire Family Code and a 8-bit CRC.
  - In order to find slaves on the bus, the standard specifies an search algorithm which successively detects all slaves on the bus. This algorithm is described in detail by Maxim’s Applicationnote 187.

- Transport layer and Presentation layer functions are not implemented in the generic 1-Wire driver and therefore must be handled in individual slave drivers.

The 1-Wire API is considered experimental.
Configuration Options

Related configuration options:
- CONFIG_W1
- CONFIG_W1_NET

API Reference

1-Wire data link layer

_group w1_data_link
1-Wire data link layer

Functions

`int w1_reset_bus(const struct device *dev)`
Reset the 1-Wire bus to prepare slaves for communication.

This routine resets all 1-Wire bus slaves such that they are ready to receive a command. Connected slaves answer with a presence pulse once they are ready to receive data.

In case the driver supports both standard speed and overdrive speed, the reset routine takes care of sending either a short or a long reset pulse depending on the current state. The speed can be changed using `w1_configure()`.

**Parameters**
- `dev` – **[in]** Pointer to the device structure for the driver instance.

**Return values**
- 0 – If no slaves answer with a present pulse.
- 1 – If at least one slave answers with a present pulse.
- `-errno` – Negative error code on error.

`int w1_read_bit(const struct device *dev)`
Read a single bit from the 1-Wire bus.

**Parameters**
- `dev` – **[in]** Pointer to the device structure for the driver instance.

**Return values**
- `rx_bit` – The read bit value on success.
- `-errno` – Negative error code on error.

`int w1_write_bit(const struct device *dev, const bool bit)`
Write a single bit to the 1-Wire bus.

**Parameters**
- `dev` – **[in]** Pointer to the device structure for the driver instance.
- `bit` – Transmitting bit value 1 or 0.

**Return values**
- 0 – If successful.
- `-errno` – Negative error code on error.
int w1_read_byte(const struct device *dev)
Read a single byte from the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Return values
• rx_byte – The read byte value on success.
• -errno – Negative error code on error.

int w1_write_byte(const struct device *dev, uint8_t byte)
Write a single byte to the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• byte – Transmitting byte.

Return values
• 0 – If successful.
• -errno – Negative error code on error.

int w1_read_block(const struct device *dev, uint8_t *buffer, size_t len)
Read a block of data from the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• buffer – [out] Pointer to receive buffer.
• len – Length of receiving buffer (in bytes).

Return values
• 0 – If successful.
• -errno – Negative error code on error.

int w1_write_block(const struct device *dev, const uint8_t *buffer, size_t len)
Write a block of data from the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• buffer – [in] Pointer to transmitting buffer.
• len – Length of transmitting buffer (in bytes).

Return values
• 0 – If successful.
• -errno – Negative error code on error.

size_t w1_get_slave_count(const struct device *dev)
Get the number of slaves on the bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Return values
• slave_count – Positive Number of connected 1-Wire slaves on success.
• -errno – Negative error code on error.
int w1_configure(const struct device *dev, enum w1_settings_type type, uint32_t value)

Configure parameters of the 1-Wire master.

Allowed configuration parameters are defined in enum w1_settings_type, but master devices may not support all types.

**Parameters**

- **dev** – [in] Pointer to the device structure for the driver instance.
- **type** – Enum specifying the setting type.
- **value** – The new value for the passed settings type.

**Return values**

- **0** – If successful.
- **-ENOTSUP** – The master doesn't support the configuration of the supplied type.
- **-EIO** – General input / output error, failed to configure master devices.

1-Wire network layer

**group w1_network**

1-Wire network layer

1-Wire ROM Commands

**W1_CMD_SKIP_ROM**

This command allows the bus master to read the slave devices without providing their ROM code.

**W1_CMD_MATCH_ROM**

This command allows the bus master to address a specific slave device by providing its ROM code.

**W1_CMD_RESUME**

This command allows the bus master to resume a previous read out from where it left off.

**W1_CMD_READ_ROM**

This command allows the bus master to read the ROM code from a single slave device.

This command should be used when there is only a single slave device on the bus.

**W1_CMD_SEARCH_ROM**

This command allows the bus master to discover the addresses (i.e., ROM codes) of all slave devices on the bus.

**W1_CMD_SEARCH_ALARM**

This command allows the bus master to identify which devices have experienced an alarm condition.
This command allows the bus master to address all devices on the bus and then switch them to overdrive speed.

This command allows the bus master to address a specific device and switch it to overdrive speed.

**CRC Defines**

**W1_CRC8_SEED**
Seed value used to calculate the 1-Wire 8-bit crc.

**W1_CRC8_POLYNOMIAL**
Polynomial used to calculate the 1-Wire 8-bit crc.

**W1_CRC16_SEED**
Seed value used to calculate the 1-Wire 16-bit crc.

**W1_CRC16_POLYNOMIAL**
Polynomial used to calculate the 1-Wire 16-bit crc.

**Defines**

**W1_SEARCH_ALL_FAMILIES**
This flag can be passed to searches in order to not filter on family ID.

**W1_ROM_INIT_ZERO**
Initialize all `w1_rom` struct members to zero.

**Typedefs**

typedef void (*w1_search_callback_t)(struct `w1_rom` rom, void *user_data)
Define the application callback handler function signature for searches.

**Param rom**
found The ROM of the found slave.

**Param user_data**
User data provided to the `w1_search_bus()` call.
int w1_read_rom(const struct device *dev, struct w1_rom *rom)
Read Peripheral 64-bit ROM.

This procedure allows the 1-Wire bus master to read the peripherals' 64-bit ROM without using the Search ROM procedure. This command can be used as long as not more than a single peripheral is connected to the bus. Otherwise data collisions occur and a faulty ROM is read.

Parameters
- **dev** – [in] Pointer to the device structure for the driver instance.
- **rom** – [out] Pointer to the ROM structure.

Return values
- 0 – If successful.
- -ENODEV – In case no slave responds to reset.
- -errno – Other negative error code in case of invalid crc and communication errors.

int w1_match_rom(const struct device *dev, const struct w1_slave_config *config)
Select a specific slave by broadcasting a selected ROM.

This routine allows the 1-Wire bus master to select a slave identified by its unique ROM, such that the next command will target only this single selected slave.

This command is only necessary in multidrop environments, otherwise the Skip ROM command can be issued. Once a slave has been selected, to reduce the communication overhead, the resume command can be used instead of this command to communicate with the selected slave.

Parameters
- **dev** – [in] Pointer to the device structure for the driver instance.
- **config** – [in] Pointer to the slave specific 1-Wire config.

Return values
- 0 – If successful.
- -ENODEV – In case no slave responds to reset.
- -errno – Other negative error code on error.

int w1_resume_command(const struct device *dev)
Select the slave last addressed with a Match ROM or Search ROM command.

This routine allows the 1-Wire bus master to re-select a slave device that was already addressed using a Match ROM or Search ROM command.

Parameters
- **dev** – Pointer to the device structure for the driver instance.

Return values
- 0 – If successful.
- -ENODEV – In case no slave responds to reset.
- -errno – Other negative error code on error.
int w1_skip_rom(const struct device *dev, const struct w1_slave_config *config)
Select all slaves regardless of ROM.
This routine sets up the bus slaves to receive a command. It is usually used when there is only one peripheral on the bus to avoid the overhead of the Match ROM command. But it can also be used to concurrently write to all slave devices.

Parameters
- dev – [in] Pointer to the device structure for the driver instance.
- config – [in] Pointer to the slave specific 1-Wire config.

Return values
- 0 – If successful.
- -ENODEV – In case no slave responds to reset.
- -errno – Other negative error code on error.

int w1_reset_select(const struct device *dev, const struct w1_slave_config *config)
In single drop configurations use Skip Select command, otherwise use Match ROM command.

Parameters
- dev – [in] Pointer to the device structure for the driver instance.
- config – [in] Pointer to the slave specific 1-Wire config.

Return values
- 0 – If successful.
- -ENODEV – In case no slave responds to reset.
- -errno – Other negative error code on error.

int w1_write_read(const struct device *dev, const struct w1_slave_config *config, const uint8_t *write_buf, size_t write_len, uint8_t *read_buf, size_t read_len)
Write then read data from the 1-Wire slave with matching ROM.
This routine uses w1_reset_select to select the given ROM. Then writes given data and reads the response back from the slave.

Parameters
- dev – [in] Pointer to the device structure for the driver instance.
- config – [in] Pointer to the slave specific 1-Wire config.
- write_buf – [in] Pointer to the data to be written.
- write_len – Number of bytes to write.
- read_buf – [out] Pointer to storage for read data.
- read_len – Number of bytes to read.

Return values
- 0 – If successful.
- -ENODEV – In case no slave responds to reset.
- -errno – Other negative error code on error.
int w1_search_bus(const struct device *dev, uint8_t command, uint8_t family, w1_search_callback_t callback, void *user_data)

Search 1-wire slaves on the bus.

This function searches slaves on the 1-wire bus, with the possibility to search either all slaves or only slaves that have an active alarm state. If a callback is passed, the callback is called for each found slave.


Note: Filtering on families is not supported.

Parameters

- dev – [in] Pointer to the device structure for the driver instance.
- command – Can either be W1_SEARCH_ALARM or W1_SEARCH_ROM.
- family – W1_SEARCH_ALL_FAMILIES searches all families, filtering on a specific family is not yet supported.
- callback – Application callback handler function to be called for each found slave.
- user_data – [in] User data to pass to the application callback handler function.

Return values

- slave_count – Number of slaves found.
- -errno – Negative error code on error.

static inline int w1_search_rom(const struct device *dev, w1_search_callback_t callback, void *user_data)

Search for 1-Wire slave on bus.

This routine can discover unknown slaves on the bus by scanning for the unique 64-bit registration number.

Parameters

- dev – [in] Pointer to the device structure for the driver instance.
- callback – Application callback handler function to be called for each found slave.
- user_data – [in] User data to pass to the application callback handler function.

Return values

- slave_count – Number of slaves found.
- -errno – Negative error code on error.

static inline int w1_search_alarm(const struct device *dev, w1_search_callback_t callback, void *user_data)

Search for 1-Wire slaves with an active alarm.

This routine searches 1-Wire slaves on the bus, which currently have an active alarm.

Parameters

- dev – [in] Pointer to the device structure for the driver instance.
- callback – Application callback handler function to be called for each found slave.
• **user_data** – [in] User data to pass to the application callback handler function.

**Return values**

• **slave_count** – Number of slaves found.
• **-errno** – Negative error code on error.

static inline uint64_t w1_rom_to_uint64(const struct w1_rom *rom)

Function to convert a `w1_rom` struct to an uint64_t.

**Parameters**

• **rom** – [in] Pointer to the ROM struct.

**Return values**

• **rom64** – The ROM converted to an unsigned integer in endianness.

static inline void w1_uint64_to_rom(const uint64_t rom64, struct w1_rom *rom)

Function to write an uint64_t to struct `w1_rom` pointer.

**Parameters**

• **rom64** – Unsigned 64 bit integer representing the ROM in host endianness.
• **rom** – [out] The ROM struct pointer.

static inline uint8_t w1_crc8(const uint8_t *src, size_t len)

Compute CRC-8 checksum as defined in the 1-Wire specification.

The 1-Wire of CRC 8 variant is using 0x31 as its polynomial with the initial value set to 0x00. This CRC is used to check the correctness of the unique 56-bit ROM.

**Parameters**

• **src** – [in] Input bytes for the computation.
• **len** – Length of the input in bytes.

**Return values**

• **crc** – The computed CRC8 value.

static inline uint16_t w1_crc16(const uint16_t seed, const uint8_t *src, const size_t len)

Compute 1-Wire variant of CRC 16.

The 16-bit 1-Wire crc variant is using the reflected polynomial function $X^{16} + X^{15} + X^{2} + 1$ with the initial value set to 0x0000. See also APPLICATION NOTE 27: “UNDERSTANDING AND USING CYCLIC REDUNDANCY CHECKS WITH MAXIM 1-WIRE AND IBUTTON PRODUCTS” https://www.maximintegrated.com/en/design/technical-documents/app-notes/2/27.html

**Parameters**

• **seed** – Init value for the CRC, it is usually set to 0x0000.
• **src** – [in] Input bytes for the computation.
• **len** – Length of the input in bytes.

**Return values**

• **crc** – The computed CRC16 value.

```c
#include <w1.h>

struct w1_rom
```

#include `<w1.h>` `w1_rom` struct.
Public Members

uint8_t family
   The 1-Wire family code identifying the slave device type.
   An incomplete list of family codes is available at: https://www.maximintegrated.com/en/app-notes/index.mvp/id/155 others are documented in the respective device data sheet.

uint8_t serial[6]
   The serial together with the family code composes the unique 56-bit id.

uint8_t crc
   8-bit checksum of the 56-bit unique id.

struct w1_slave_config
   #include <w1.h> Node specific 1-wire configuration struct.
   This struct is passed to network functions, such that they can configure the bus to address the specific slave using the selected speed.

Public Members

struct w1_rom rom
   Unique 1-Wire ROM.

uint32_t overdrive
   overdrive speed is used if set to 1.

1-Wire generic functions and helpers Functions that are not directly related to any of the networking layers.

Related code samples

1-Wire scanner
   Scan for 1-Wire devices and print their family ID and serial number.

group w1_interface
   1-Wire Interface

 Enums

enum w1_settings_type
   Defines the 1-Wire master settings types, which are runtime configurable.
   Values:

   enumerator W1_SETTING_SPEED
      Overdrive speed is enabled in case a value of 1 is passed and disabled passing 0.
enumerator W1_SETTING_STRONG_PULLUP

The strong pullup resistor is activated immediately after the next written data block by passing a value of 1, and deactivated passing 0.

enumerator W1_SETTINGS_TYPE_COUNT

Number of different settings types.

Functions

static inline int w1_lock_bus(const struct device *dev)

Lock the 1-wire bus to prevent simultaneous access.

This routine locks the bus to prevent simultaneous access from different threads. The calling thread waits until the bus becomes available. A thread is permitted to lock a mutex it has already locked.

Parameters

• dev – [in] Pointer to the device structure for the driver instance.

Return values

• 0 – If successful.
• -errno – Negative error code on error.

static inline int w1_unlock_bus(const struct device *dev)

Unlock the 1-wire bus.

This routine unlocks the bus to permit access to bus line.

Parameters

• dev – [in] Pointer to the device structure for the driver instance.

Return values

• 0 – If successful.
• -errno – Negative error code on error.

7.6.2 Analog-to-Digital Converter (ADC)

Overview

API Reference

Related code samples

Analog-to-Digital Converter (ADC)

Read analog inputs from ADC channels.

group adc_interface

ADC driver APIs.
Defines

ADC_CHANNEL_CFG_DT(node_id)
Get ADC channel configuration from a given devicetree node.

This returns a static initializer for a struct `adc_channel_cfg` filled with data from a given devicetree node.

Example devicetree fragment:

```plaintext
&adc {
    #address-cells = <1>;
    #size-cells = <0>;

    channel@0 {
        reg = <0>;
        zephyr,gain = "ADC_GAIN_1_6";
        zephyr,reference = "ADC_REF_INTERNAL";
        zephyr,acquisition-time = <ADC_ACQ_TIME(ADC_ACQ_TIME_MICROSECONDS, 20)>;
        zephyr,input-positive = <NRF_SAADC_AIN6>;
        zephyr,input-negative = <NRF_SAADC_AIN7>;
    }

    channel@1 {
        reg = <1>;
        zephyr,gain = "ADC_GAIN_1_6";
        zephyr,reference = "ADC_REF_INTERNAL";
        zephyr,acquisition-time = <ADC_ACQ_TIME_DEFAULT>;
        zephyr,input-positive = <NRF_SAADC_AIN0>;
    }
}
```

Example usage:

```c
static const struct adc_channel_cfg ch0_cfg_dt = ADC_CHANNEL_CFG_DT(DT_CHILD(DT_NODELABEL(adc), channel_0));
static const struct adc_channel_cfg ch1_cfg_dt = ADC_CHANNEL_CFG_DT(DT_CHILD(DT_NODELABEL(adc), channel_1));
```

// Initializes 'ch0_cfg_dt' to:
// {
//   .channel_id = 0,
//   .gain = ADC_GAIN_1_6,
//   .reference = ADC_REF_INTERNAL,
//   .acquisition_time = ADC_ACQ_TIME(ADC_ACQ_TIME_MICROSECONDS, 20),
//   .differential = true,
//   .input_positive = NRF_SAADC_AIN6,
//   .input_negative = NRF_SAADC_AIN7,
// }
// and 'ch1_cfg_dt' to:
// {
//   .channel_id = 1,
//   .gain = ADC_GAIN_1_6,
//   .reference = ADC_REF_INTERNAL,
//   .acquisition_time = ADC_ACQ_TIME_DEFAULT,
//   .input_positive = NRF_SAADC_AIN0,
// }
```

Parameters

- **node_id** – Devicetree node identifier.

Returns

Static initializer for an `adc_channel_cfg` structure.
Get ADC io-channel information from devicetree.

This returns a static initializer for an `adc_dt_spec` structure given a devicetree node and a channel index. The node must have the “io-channels” property defined.

Example devicetree fragment:

```
/ {
    zephyr,user {
        io-channels =<&adc0 1>, &adc0 3>;
    };

&adc0 {
    #address-cells = <1>;
    #size-cells = <0>;

class03 {
    reg = <3>;
    zephyr,gain = "ADC_GAIN_1_5";
    zephyr,reference = "ADC_REF_VDD_1_4";
    zephyr,vref-mv = <750>;
    zephyr,acquisition-time = <ADC_ACQ_TIME_DEFAULT>;
    zephyr,resolution = <12>;
    zephyr,oversampling = <4>;
};
}
```

Example usage:

```
static const struct adc_dt_spec adc_chan0 = ADC_DT_SPEC_GET_BY_IDX(DT_PATH(zephyr_user), 0);
static const struct adc_dt_spec adc_chan1 = ADC_DT_SPEC_GET_BY_IDX(DT_PATH(zephyr_user), 1));
```

// Initializes 'adc_chan0' to:
// { 
//   .dev = DEVICE_DT_GET(DT_NODELABEL(adc0)),
//   .channel_id = 1,
// } 
// and 'adc_chan1' to:
// { 
//   .dev = DEVICE_DT_GET(DT_NODELABEL(adc0)),
//   .channel_id = 3,
//   .channel_cfg_dt_node_exists = true,
//   .channel_cfg = {
//     .channel_id = 3,
//     .gain = ADC_GAIN_1_5,
//     .reference = ADC_REF_VDD_1_4,
//     .acquisistion_time = ADC_ACQ_TIME_DEFAULT,
//   },
//   .vref_mv = 750,
//   .resolution = 12,
//   .oversampling = 4,
// }

See also:

`ADC_DT_SPEC_GET()`

Parameters
• node_id – Devicetree node identifier.
• idx – Channel index.

**Returns**
Static initializer for an `adc_dt_spec` structure.

`ADC_DT_SPEC_INST_GET_BY_IDX(inst, idx)`
Get ADC io-channel information from a DT_DRV_COMPAT devicetree instance.

**See also:**
`ADC_DT_SPEC_GET_BY_IDX()`

**Parameters**
• inst – DT_DRV_COMPAT instance number
• idx – Channel index.

**Returns**
Static initializer for an `adc_dt_spec` structure.

`ADC_DT_SPEC_GET(node_id)`
Equivalent to `ADC_DT_SPEC_GET_BY_IDX(node_id, 0)`.

**See also:**
`ADC_DT_SPEC_GET_BY_IDX()`

**Parameters**
• node_id – Devicetree node identifier.

**Returns**
Static initializer for an `adc_dt_spec` structure.

`ADC_DT_SPEC_INST_GET(inst)`
Equivalent to `ADC_DT_SPEC_INST_GET_BY_IDX(inst, 0)`.

**See also:**
`ADC_DT_SPEC_GET()`

**Parameters**
• inst – DT_DRV_COMPAT instance number

**Returns**
Static initializer for an `adc_dt_spec` structure.

**Typedefs**

typedef enum `adc_action` (*`adc_sequence_callback`)*
(const struct `device` *dev, const struct `adc_sequence` *sequence, uint16_t sampling_index)

Type definition of the optional callback function to be called after a requested sampling is done.
**Param dev**
Pointer to the device structure for the driver instance.

**Param sequence**
Pointer to the sequence structure that triggered the sampling. This parameter points to a copy of the structure that was supplied to the call that started the sampling sequence, thus it cannot be used with the `CONTAINER_OF()` macro to retrieve some other data associated with the sequence. Instead, the `adc_sequence_options::user_data` field should be used for such purpose.

**Param sampling_index**
Index (0-65535) of the sampling done.

**Return**
Action to be performed by the driver. See `adc_action`.

```c
typedef int (*adc_api_channel_setup)(const struct device *dev, const struct adc_channel_cfg *channel_cfg)
```
Type definition of ADC API function for configuring a channel.
See `adc_channel_setup()` for argument descriptions.

```c
typedef int (*adc_api_read)(const struct device *dev, const struct adc_sequence *sequence)
```
Type definition of ADC API function for setting a read request.
See `adc_read()` for argument descriptions.

```c
typedef int (*adc_api_read_async)(const struct device *dev, const struct adc_sequence *sequence, struct k_poll_signal *async)
```
Type definition of ADC API function for setting an asynchronous read request.
See `adc_read_async()` for argument descriptions.

**Enums**

```c
enum adc_gain
```
ADC channel gain factors.

**Values:**

- enumerator `ADC_GAIN_1_6`
  x 1/6.

- enumerator `ADC_GAIN_1_5`
  x 1/5.

- enumerator `ADC_GAIN_1_4`
  x 1/4.

- enumerator `ADC_GAIN_1_3`
  x 1/3.

- enumerator `ADC_GAIN_2_5`
  x 2/5.
enumerator ADC_GAIN_1_2
x 1/2.

enumerator ADC_GAIN_2_3
x 2/3.

enumerator ADC_GAIN_4_5
x 4/5.

enumerator ADC_GAIN_1
x 1.

enumerator ADC_GAIN_2
x 2.

enumerator ADC_GAIN_3
x 3.

enumerator ADC_GAIN_4
x 4.

enumerator ADC_GAIN_6
x 6.

enumerator ADC_GAIN_8
x 8.

enumerator ADC_GAIN_12
x 12.

enumerator ADC_GAIN_16
x 16.

enumerator ADC_GAIN_24
x 24.

enumerator ADC_GAIN_32
x 32.

enumerator ADC_GAIN_64
x 64.

enumerator ADC_GAIN_128
x 128.

enum adc_reference
ADC references.
Values:
enumerator ADC_REF_VDD_1
    VDD.

denumerator ADC_REF_VDD_1_2
    VDD/2.

denumerator ADC_REF_VDD_1_3
    VDD/3.

denumerator ADC_REF_VDD_1_4
    VDD/4.

denumerator ADC_REF_INTERNAL
    Internal.

denumerator ADC_REF_EXTERNAL0
    External, input 0.

denumerator ADC_REF_EXTERNAL1
    External, input 1.

enum adc_action
    Action to be performed after a sampling is done.
    Values:
        enumerator ADC_ACTION_CONTINUE = 0
            The sequence should be continued normally.

        enumerator ADC_ACTION_REPEAT
            The sampling should be repeated.

                New samples or sample should be read from the ADC and written in the same place
                as the recent ones.

        enumerator ADC_ACTION_FINISH
            The sequence should be finished immediately.

Functions

int adc_gain_invert(enum adc_gain gain, int32_t *value)
    Invert the application of gain to a measurement value.
    For example, if the gain passed in is ADC_GAIN_1_6 and the referenced value is 10, the
    value after the function returns is 60.

    Parameters
        • gain – the gain used to amplify the input signal.
        • value – a pointer to a value that initially has the effect of the applied gain
          but has that effect removed when this function successfully returns. If
          the gain cannot be reversed the value remains unchanged.
Return values

- 0 – if the gain was successfully reversed
- -EINVAL – if the gain could not be interpreted

```c
int adc_channel_setup(const struct device *dev, const struct adc_channel_cfg *channel_cfg)
```

Configure an ADC channel.

It is required to call this function and configure each channel before it is selected for a read request.

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `channel_cfg` – Channel configuration.

Return values

- 0 – On success.
- -EINVAL – If a parameter with an invalid value has been provided.

```c
static inline int adc_channel_setup_dt(const struct adc_dt_spec *spec)
```

Configure an ADC channel from a struct `adc_dt_spec`.

See also:

`adc_channel_setup()`

Parameters

- `spec` – ADC specification from Devicetree.

Returns

A value from `adc_channel_setup()` or -ENOTSUP if information from Devicetree is not valid.

```c
int adc_read(const struct device *dev, const struct adc_sequence *sequence)
```

Set a read request.

If invoked from user mode, any sequence struct options for callback must be NULL.

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `sequence` – Structure specifying requested sequence of samplings.

Return values

- 0 – On success.
- -EINVAL – If a parameter with an invalid value has been provided.
- -ENOMEM – If the provided buffer is too small to hold the results of all requested samplings.
- -ENOTSUP – If the requested mode of operation is not supported.
- -EBUSY – If another sampling was triggered while the previous one was still in progress. This may occur only when samplings are done with intervals, and it indicates that the selected interval was too small. All requested samples are written in the buffer, but at least some of them were taken with an extra delay compared to what was scheduled.
**static inline int adc_read_dt(const struct adc_dt_spec *spec, const struct adc_sequence *sequence)**

Set a read request from a struct *adc_dt_spec*.

**See also:**
*adc_read()*

**Parameters**
- `spec` – ADC specification from Devicetree.
- `sequence` – Structure specifying requested sequence of samplings.

**Returns**
A value from *adc_read()*.

**int adc_read_async(const struct device *dev, const struct adc_sequence *sequence, struct k_poll_signal *async)**

Set an asynchronous read request.

If invoked from user mode, any sequence struct options for callback must be NULL.

**Note:** This function is available only if CONFIG_ADC_ASYNC is selected.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.
- `sequence` – Structure specifying requested sequence of samplings.
- `async` – Pointer to a valid and ready to be signaled struct *k_poll_signal*. (Note: if NULL this function will not notify the end of the transaction, and whether it went successfully or not).

**Returns**
0 on success, negative error code otherwise. See *adc_read()* for a list of possible error codes.

**static inline uint16_t adc_ref_internal(const struct device *dev)**

Get the internal reference voltage.

Returns the voltage corresponding to ADC_REF_INTERNAL, measured in millivolts.

**Returns**
a positive value is the reference voltage value. Returns zero if reference voltage information is not available.

**static inline int adc_raw_to_millivolts(int32_t ref_mv, enum adc_gain gain, uint8_t resolution, int32_t *valp)**

Convert a raw ADC value to millivolts.

This function performs the necessary conversion to transform a raw ADC measurement to a voltage in millivolts.

**Parameters**
- `ref_mv` – the reference voltage used for the measurement, in millivolts. This may be from *adc_ref_internal()* or a known external reference.
- `gain` – the ADC gain configuration used to sample the input
• **resolution** – the number of bits in the absolute value of the sample. For differential sampling this needs to be one less than the resolution in struct `adc_sequence`.

• **valp** – pointer to the raw measurement value on input, and the corresponding millivolt value on successful conversion. If conversion fails the stored value is left unchanged.

**Return values**

- 0 – on successful conversion
- EINVAL – if the gain is not reversible

```c
static inline int adc_raw_to_millivolts_dt(const struct adc_dt_spec *spec, int32_t *valp)
```

Convert a raw ADC value to millivolts using information stored in a struct `adc_dt_spec`.

**See also:**

`adc_raw_to_millivolts()`

**Parameters**

- **spec** – [in] ADC specification from Devicetree.
- **valp** – [inout] Pointer to the raw measurement value on input, and the corresponding millivolt value on successful conversion. If conversion fails the stored value is left unchanged.

**Returns**

A value from `adc_raw_to_millivolts()` or -ENOTSUP if information from Devicetree is not valid.

```c
static inline int adc_sequence_init_dt(const struct adc_dt_spec *spec, struct adc_sequence *seq)
```

Initialize a struct `adc_sequence` from information stored in struct `adc_dt_spec`.

Note that this function only initializes the following fields:

- `adc_sequence::channels`
- `adc_sequence::resolution`
- `adc_sequence::oversampling`

Other fields should be initialized by the caller.

**Parameters**

- **spec** – [in] ADC specification from Devicetree.
- **seq** – [out] Sequence to initialize.

**Return values**

- 0 – On success
- -ENOTSUP – If spec does not have valid channel configuration

```c
static inline bool adc_is_ready_dt(const struct adc_dt_spec *spec)
```

Validate that the ADC device is ready.

**Parameters**

- **spec** – ADC specification from devicetree
Return values

true – if the ADC device is ready for use and false otherwise.

struct adc_channel_cfg

#include <adc.h> Structure for specifying the configuration of an ADC channel.

Public Members

enum adc_gain gain
Gain selection.

enum adc_reference reference
Reference selection.

uint16_t acquisition_time
Acquisition time.

Use the ADC_ACQ_TIME macro to compose the value for this field or pass
ADC_ACQ_TIME_DEFAULT to use the default setting for a given hardware (e.g.
when the hardware does not allow to configure the acquisition time). Particular
drivers do not necessarily support all the possible units. Value range is 0-16383 for
a given unit.

uint8_t channel_id
Channel identifier.

This value primarily identifies the channel within the ADC API - when a read re-
quest is done, the corresponding bit in the “channels” field of the “adc_sequence”
structure must be set to include this channel in the sampling. For hardware that
does not allow selection of analog inputs for given channels, but rather have dedi-
cated ones, this value also selects the physical ADC input to be used in the sampling.
Otherwise, when it is needed to explicitly select an analog input for the channel,
or two inputs when the channel is a differential one, the selection is done in “in-
put_positive” and “input_negative” fields. Particular drivers indicate which one of
the above two cases they support by selecting or not a special hidden Kconfig op-
tion named ADC_CONFIGURABLE_INPUTS. If this option is not selected, the macro
CONFIG_ADC_CONFIGURABLE_INPUTS is not defined and consequently the men-
tioned two fields are not present in this structure. While this API allows identifiers
from range 0-31, particular drivers may support only a limited number of channel
 identifiers (dependent on the underlying hardware capabilities or configured via
a dedicated Kconfig option).

uint8_t differential
Channel type: single-ended or differential.

struct adc_dt_spec

#include <adc.h> Container for ADC channel information specified in devicetree.

See also:
ADC_DT_SPEC_GET_BY_IDX
See also:
ADC_DT_SPEC_GET

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Public Members

const struct device *dev
   Pointer to the device structure for the ADC driver instance used by this io-channel.

uint8_t channel_id
   ADC channel identifier used by this io-channel.

bool channel_cfg_dt_node_exists
   Flag indicating whether configuration of the associated ADC channel is provided as a child node of the corresponding ADC controller in devicetree.

struct adc_channel_cfg channel_cfg
   Configuration of the associated ADC channel specified in devicetree.
   This field is valid only when channel_cfg_dt_node_exists is set to true.

uint16_t vref_mv
   Voltage of the reference selected for the channel or 0 if this value is not provided in devicetree.
   This field is valid only when channel_cfg_dt_node_exists is set to true.

uint8_t resolution
   ADC resolution to be used for that channel.
   This field is valid only when channel_cfg_dt_node_exists is set to true.

uint8_t oversampling
   Oversampling setting to be used for that channel.
   This field is valid only when channel_cfg_dt_node_exists is set to true.

struct adc_sequence_options
   #include <adc.h> Structure defining additional options for an ADC sampling sequence.

Public Members

uint32_t interval_us
   Interval between consecutive samplings (in microseconds), 0 means sample as fast as possible, without involving any timer.
   The accuracy of this interval is dependent on the implementation of a given driver. The default routine that handles the intervals uses a kernel timer for this purpose, thus, it has the accuracy of the kernel's system clock. Particular drivers may use some dedicated hardware timers and achieve a better precision.

adc_sequence_callback callback
   Callback function to be called after each sampling is done.
   Optional - set to NULL if it is not needed.
void *user_data
     Pointer to user data.
     It can be used to associate the sequence with any other data that is needed in the callback function.

uint16_t extra_samplings
     Number of extra samplings to perform (the total number of samplings is 1 + extra_samplings).

struct adc_sequence
     #include <adc.h> Structure defining an ADC sampling sequence.

Public Members

const struct adc_sequence_options *options
     Pointer to a structure defining additional options for the sequence.
     If NULL, the sequence consists of a single sampling.

uint32_t channels
     Bit-mask indicating the channels to be included in each sampling of this sequence.
     All selected channels must be configured with adc_channel_setup() before they are used in a sequence. The least significant bit corresponds to channel 0.

void *buffer
     Pointer to a buffer where the samples are to be written.
     Samples from subsequent samplings are written sequentially in the buffer. The number of samples written for each sampling is determined by the number of channels selected in the “channels” field. The values written to the buffer represent a sample from each selected channel starting from the one with the lowest ID. The buffer must be of an appropriate size, taking into account the number of selected channels and the ADC resolution used, as well as the number of samplings contained in the sequence.

size_t buffer_size
     Specifies the actual size of the buffer pointed by the “buffer” field (in bytes).
     The driver must ensure that samples are not written beyond the limit and it must return an error if the buffer turns out to be not large enough to hold all the requested samples.

uint8_t resolution
     ADC resolution.
     For single-ended channels the sample values are from range: 0 .. 2^resolution - 1, for differential ones:
     • 2^(resolution-1) .. 2^(resolution-1) - 1.

uint8_t oversampling
     Oversampling setting.
Each sample is averaged from \(2^{\text{oversampling}}\) conversion results. This feature may be unsupported by a given ADC hardware, or in a specific mode (e.g. when sampling multiple channels).

```c
bool calibrate
```

Perform calibration before the reading is taken if requested.

The impact of channel configuration on the calibration process is specific to the underlying hardware. ADC implementations that do not support calibration should ignore this flag.

```c
struct adc_driver_api
#include <adc.h> ADC driver API.
```

This is the mandatory API any ADC driver needs to expose.

## 7.6.3 Auxiliary Display (auxdisplay)

### Overview

Auxiliary Displays are text-based displays that have simple interfaces for displaying textual, numeric or alphanumeric data, as opposed to the Display Interface, auxiliary displays do not support custom graphical output to displays (and most often monochrome), the most advanced custom feature supported is generation of custom characters. These inexpensive displays are commonly found with various configurations and sizes, a common display size is 16 characters by 2 lines.

This API is unstable and subject to change.

### Configuration Options

Related configuration options:

- CONFIG_AUXDISPLAY
- CONFIG_AUXDISPLAY_INIT_PRIORITY

### API Reference

#### Related code samples

**Auxiliary display**

Output ”Hello World” to an auxiliary display.

```c
group auxdisplay_interface
Auxiliary (Text) Display Interface.
```

**Defines**

- AUXDISPLAY_LIGHT_NOT_SUPPORTED
  Used for minimum and maximum brightness/backlight values if not supported.
**Typedefs**

typedef uint32_t auxdisplay_mode_t

Used to describe the mode of an auxiliary (text) display.

**Enums**

define auxdisplay_position

Used for moving the cursor or display position.

*Values:*

enumerator AUXDISPLAY_POSITION_ABSOLUTE = 0

Moves to specified X,Y position.

enumerator AUXDISPLAY_POSITION_RELATIVE

Shifts current position by +/- X,Y position, does not take display direction into consideration.

enumerator AUXDISPLAY_POSITION_RELATIVE_DIRECTION

Shifts current position by +/- X,Y position, takes display direction into consideration.

enumerator AUXDISPLAY_POSITION_COUNT

**enum auxdisplay_direction**

Used for setting character append position.

*Values:*

enumerator AUXDISPLAY_DIRECTION_RIGHT = 0

Each character will be placed to the right of existing characters.

enumerator AUXDISPLAY_DIRECTION_LEFT

Each character will be placed to the left of existing characters.

enumerator AUXDISPLAY_DIRECTION_COUNT

**Functions**

int auxdisplay_display_on(const struct device *dev)

Turn display on.

**Parameters**

- dev – Auxiliary display device instance

**Return values**

- 0 – on success.
- -ENOSYS – if not supported/implemented.

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int auxdisplay_display_off(const struct device *dev)
Turn display off.

Parameters
• dev – Auxiliary display device instance

Return values
• 0 – on success.
• -ENOSYS – if not supported/implemented.
• -errno – Negative errno code on other failure.

int auxdisplay_cursor_set_enabled(const struct device *dev, bool enabled)
Set cursor enabled status on an auxiliary display.

Parameters
• dev – Auxiliary display device instance
• enabled – True to enable cursor, false to disable

Return values
• 0 – on success.
• -ENOSYS – if not supported/implemented.
• -errno – Negative errno code on other failure.

int auxdisplay_position_blinking_set_enabled(const struct device *dev, bool enabled)
Set cursor blinking status on an auxiliary display.

Parameters
• dev – Auxiliary display device instance
• enabled – Set to true to enable blinking position, false to disable

Return values
• 0 – on success.
• -ENOSYS – if not supported/implemented.
• -errno – Negative errno code on other failure.

int auxdisplay_cursor_shift_set(const struct device *dev, uint8_t direction, bool display_shift)
Set cursor shift after character write and display shift.

Parameters
• dev – Auxiliary display device instance
• direction – Sets the direction of the display when characters are written
• display_shift – If true, will shift the display when characters are written (which makes it look like the display is moving, not the cursor)

Return values
• 0 – on success.
• -ENOSYS – if not supported/implemented.
• -EINVAL – if provided argument is invalid.
• -errno – Negative errno code on other failure.
int auxdisplay_cursor_position_set(const struct device *dev, enum auxdisplay_position type, int16_t x, int16_t y)

Set cursor (and write position) on an auxiliary display.

**Parameters**
- *dev* – Auxiliary display device instance
- *type* – Type of move, absolute or offset
- *x* – Exact or offset X position
- *y* – Exact or offset Y position

**Return values**
- 0 – on success.
- -ENOSYS – if not supported/implemented.
- -EINVAL – if provided argument is invalid.
- -errno – Negative errno code on other failure.

int auxdisplay_cursor_position_get(const struct device *dev, int16_t *x, int16_t *y)

Get current cursor on an auxiliary display.

**Parameters**
- *dev* – Auxiliary display device instance
- *x* – Will be updated with the exact X position
- *y* – Will be updated with the exact Y position

**Return values**
- 0 – on success.
- -ENOSYS – if not supported/implemented.
- -EINVAL – if provided argument is invalid.
- -errno – Negative errno code on other failure.

int auxdisplay_display_position_set(const struct device *dev, enum auxdisplay_position type, int16_t x, int16_t y)

Set display position on an auxiliary display.

**Parameters**
- *dev* – Auxiliary display device instance
- *type* – Type of move, absolute or offset
- *x* – Exact or offset X position
- *y* – Exact or offset Y position

**Return values**
- 0 – on success.
- -ENOSYS – if not supported/implemented.
- -EINVAL – if provided argument is invalid.
- -errno – Negative errno code on other failure.

int auxdisplay_display_position_get(const struct device *dev, int16_t *x, int16_t *y)

Get current display position on an auxiliary display.

**Parameters**
• `dev` – Auxiliary display device instance
• `x` – Will be updated with the exact X position
• `y` – Will be updated with the exact Y position

Return values
• `0` – on success.
• `-ENOSYS` – if not supported/implemented.
• `-EINVAL` – if provided argument is invalid.
• `-errno` – Negative errno code on other failure.

```c
int auxdisplay_capabilities_get(const struct device *dev, struct auxdisplay_capabilities *capabilities)
```

Fetch capabilities (and details) of auxiliary display.

Parameters
• `dev` – Auxiliary display device instance
• `capabilities` – Will be updated with the details of the auxiliary display

Return values
• `0` – on success.
• `-errno` – Negative errno code on other failure.

```c
int auxdisplay_clear(const struct device *dev)
```

Clear display of auxiliary display and return to home position (note that this does not reset the display configuration, e.g. custom characters and display mode will persist).

Parameters
• `dev` – Auxiliary display device instance

Return values
• `0` – on success.
• `-errno` – Negative errno code on other failure.

```c
int auxdisplay_brightness_get(const struct device *dev, uint8_t *brightness)
```

Get the current brightness level of an auxiliary display.

Parameters
• `dev` – Auxiliary display device instance
• `brightness` – Will be updated with the current brightness

Return values
• `0` – on success.
• `-ENOSYS` – if not supported/implemented.
• `-errno` – Negative errno code on other failure.

```c
int auxdisplay_brightness_set(const struct device *dev, uint8_t brightness)
```

Update the brightness level of an auxiliary display.

Parameters
• `dev` – Auxiliary display device instance
• `brightness` – The brightness level to set
Return values

- \(0\) – on success.
- \(-\text{ENOSYS}\) – if not supported/implemented.
- \(-\text{EINVAL}\) – if provided argument is invalid.
- \(-\text{errno}\) – Negative errno code on other failure.

### auxdisplay_backlight_get

```c
int auxdisplay_backlight_get(const struct device *dev, uint8_t *backlight)
```

Get the backlight level details of an auxiliary display.

**Parameters**

- `dev` – Auxiliary display device instance
- `backlight` – Will be updated with the current backlight level

**Return values**

- \(0\) – on success.
- \(-\text{ENOSYS}\) – if not supported/implemented.
- \(-\text{errno}\) – Negative errno code on other failure.

### auxdisplay_backlight_set

```c
int auxdisplay_backlight_set(const struct device *dev, uint8_t backlight)
```

Update the backlight level of an auxiliary display.

**Parameters**

- `dev` – Auxiliary display device instance
- `backlight` – The backlight level to set

**Return values**

- \(0\) – on success.
- \(-\text{ENOSYS}\) – if not supported/implemented.
- \(-\text{EINVAL}\) – if provided argument is invalid.
- \(-\text{errno}\) – Negative errno code on other failure.

### auxdisplay_is_busy

```c
int auxdisplay_is_busy(const struct device *dev)
```

Check if an auxiliary display driver is busy.

**Parameters**

- `dev` – Auxiliary display device instance

**Return values**

- \(1\) – on success and display busy.
- \(0\) – on success and display not busy.
- \(-\text{ENOSYS}\) – if not supported/implemented.
- \(-\text{errno}\) – Negative errno code on other failure.

### auxdisplay_custom_character_set

```c
int auxdisplay_custom_character_set(const struct device *dev, struct auxdisplay_character *character)
```

Sets a custom character in the display, the custom character struct must contain the pixel data for the custom character to add and valid custom character index, if successful then the character_code variable in the struct will be set to the character code that can be used with the `auxdisplay_write()` function to show it.

A character must be valid for a display consisting of a uint8 array of size character width by character height, values should be 0x00 for pixel off or 0xff for pixel on, if
a display supports shades then values between 0x00 and 0xff may be used (display driver dependent).

Parameters
- dev – Auxiliary display device instance
- character – Pointer to custom character structure

Return values
- 0 – on success.
- -ENOSYS – if not supported/implemented.
- -EINVAL – if provided argument is invalid.
- -errno – Negative errno code on other failure.

int auxdisplay_write(const struct device *dev, const uint8_t *data, uint16_t len)
Write data to auxiliary display screen at current position.

Parameters
- dev – Auxiliary display device instance
- data – Text data to write
- len – Length of text data to write

Return values
- 0 – on success.
- -EINVAL – if provided argument is invalid.
- -errno – Negative errno code on other failure.

int auxdisplay_custom_command(const struct device *dev, struct auxdisplay_custom_data *data)
Send a custom command to the display (if supported by driver)

Parameters
- dev – Auxiliary display device instance
- data – Custom command structure (this may be extended by specific drivers)

Return values
- 0 – on success.
- -ENOSYS – if not supported/implemented.
- -EINVAL – if provided argument is invalid.
- -errno – Negative errno code on other failure.

struct auxdisplay_light

#include <auxdisplay.h> Light levels for brightness and/or backlight.
If not supported by a display/driver, both minimum and maximum will be AUXDISPLAY_LIGHT_NOT_SUPPORTED.

Public Members


```c
uint8_t minimum
   Minimum light level supported.

uint8_t maximum
   Maximum light level supported.
```

```c
struct auxdisplay_capabilities
   #include <auxdisplay.h> Structure holding display capabilities.

Public Members

```c
uint16_t columns
   Number of character columns.

uint16_t rows
   Number of character rows.
```

```c
auxdisplay_mode_t mode
   Display-specific data (e.g. 4-bit or 8-bit mode for HD44780-based displays)
```

```c
struct auxdisplay_light brightness
   Brightness details for display (if supported)

struct auxdisplay_light backlight
   Backlight details for display (if supported)
```

```c
uint8_t custom_characters
   Number of custom characters supported by display (0 if unsupported)

uint8_t custom_character_width
   Width (in pixels) of a custom character, supplied custom characters should match.

uint8_t custom_character_height
   Height (in pixels) of a custom character, supplied custom characters should match.
```

```c
struct auxdisplay_custom_data
   #include <auxdisplay.h> Structure for a custom command.

   This may be extended by specific drivers.

Public Members

```c
uint8_t *data
   Raw command data to be sent.
```
7.6.4 Audio

Audio Codec

Overview The Audio Codec API provides access to digital audio codecs.

Configuration Options Related configuration options:
  • CONFIG_AUDIO_CODEC

API Reference

group audio_codec_interface
  Abstraction for audio codecs.

Typedefs

typedef void (*audio_codec_error_callback_t)(const struct device *dev, uint32_t errors)
  Callback for error interrupt.

  Param dev
  Pointer to the codec device

  Param errors
  Device errors (bitmask of audio_codec_error_type values)
Enums

enum audio_pcm_rate_t
   PCM audio sample rates.
   Values:

   enumerator AUDIO_PCM_RATE_8K = 8000
      8 kHz sample rate

   enumerator AUDIO_PCM_RATE_16K = 16000
      16 kHz sample rate

   enumerator AUDIO_PCM_RATE_24K = 24000
      24 kHz sample rate

   enumerator AUDIO_PCM_RATE_32K = 32000
      32 kHz sample rate

   enumerator AUDIO_PCM_RATE_44P1K = 44100
      44.1 kHz sample rate

   enumerator AUDIO_PCM_RATE_48K = 48000
      48 kHz sample rate

   enumerator AUDIO_PCM_RATE_96K = 96000
      96 kHz sample rate

   enumerator AUDIO_PCM_RATE_192K = 192000
      192 kHz sample rate

enum audio_pcm_width_t
   PCM audio sample bit widths.
   Values:

   enumerator AUDIO_PCM_WIDTH_16_BITS = 16
      16-bit sample width

   enumerator AUDIO_PCM_WIDTH_20_BITS = 20
      20-bit sample width

   enumerator AUDIO_PCM_WIDTH_24_BITS = 24
      24-bit sample width

   enumerator AUDIO_PCM_WIDTH_32_BITS = 32
      32-bit sample width

enum audio_dai_type_t
   Digital Audio Interface (DAI) type.
   Values:
enumerator AUDIO_DAI_TYPE_I2S
   I2S Interface.

enumerator AUDIO_DAI_TYPE_INVALID
   Other interfaces can be added here.

enum audio_property_t
   Codec properties that can be set by audio_codec_set_property().
   Values:

   enumerator AUDIO_PROPERTY_OUTPUT_VOLUME
      Output volume.

   enumerator AUDIO_PROPERTY_OUTPUT_MUTE
      Output mute/unmute.

enum audio_channel_t
   Audio channel identifiers to use in audio_codec_set_property().
   Values:

   enumerator AUDIO_CHANNEL_FRONT_LEFT
      Front left channel.

   enumerator AUDIO_CHANNEL_FRONT_RIGHT
      Front right channel.

   enumerator AUDIO_CHANNEL_LFE
      Low frequency effect channel.

   enumerator AUDIO_CHANNEL_FRONT_CENTER
      Front center channel.

   enumerator AUDIO_CHANNEL_REAR_LEFT
      Rear left channel.

   enumerator AUDIO_CHANNEL_REAR_RIGHT
      Rear right channel.

   enumerator AUDIO_CHANNEL_REAR_CENTER
      Rear center channel.

   enumerator AUDIO_CHANNEL_SIDE_LEFT
      Side left channel.

   enumerator AUDIO_CHANNEL_SIDE_RIGHT
      Side right channel.
enumerator AUDIO_CHANNEL_ALL
  All channels.

genode audio_codec_error_type
  Codec error type.
  Values:

  enumerator AUDIO_CODEC_ERROR_OVERCURRENT = BIT(0)
    Output over-current.

  enumerator AUDIO_CODEC_ERROR_OVERTEMPERATURE = BIT(1)
    Codec over-temperature.

  enumerator AUDIO_CODEC_ERROR_UNDervoltage = BIT(2)
    Power low voltage.

  enumerator AUDIO_CODEC_ERROR_OVERvoltage = BIT(3)
    Power high voltage.

  enumerator AUDIO_CODEC_ERROR_DC = BIT(4)
    Output direct-current.

Functions

static inline int audio_codec_configure(const struct device *dev, struct audio_codec_cfg *cfg)
  Configure the audio codec.
  Configure the audio codec device according to the configuration parameters provided as input
  Parameters
    • dev – Pointer to the device structure for codec driver instance.
    • cfg – Pointer to the structure containing the codec configuration.
  Returns
    0 on success, negative error code on failure

static inline void audio_codec_start_output(const struct device *dev)
  Set codec to start output audio playback.
  Setup the audio codec device to start the audio playback
  Parameters
    • dev – Pointer to the device structure for codec driver instance.

static inline void audio_codec_stop_output(const struct device *dev)
  Set codec to stop output audio playback.
  Setup the audio codec device to stop the audio playback
  Parameters
    • dev – Pointer to the device structure for codec driver instance.
static inline int audio_codec_set_property(const struct device *dev, audio_property_t property, audio_channel_t channel, audio_property_value_t val)

Set a codec property defined by audio_property_t.
Set a property such as volume level, clock configuration etc.

Parameters
   • dev – Pointer to the device structure for codec driver instance.
   • property – The codec property to set
   • channel – The audio channel for which the property has to be set
   • val – pointer to a property value of type audio_codec_property_value_t

Returns
0 on success, negative error code on failure

static inline int audio_codec_apply_properties(const struct device *dev)

Atomically apply any cached properties.
Following one or more invocations of audio_codec_set_property, that may have been
cached by the driver, audio_codec_apply_properties can be invoked to apply all the
properties as atomic as possible

Parameters
   • dev – Pointer to the device structure for codec driver instance.

Returns
0 on success, negative error code on failure

static inline int audio_codec_clear_errors(const struct device *dev)

Clear any codec errors.
Clear all codec errors. If an error interrupt exists, it will be de-asserted.

Parameters
   • dev – Pointer to the device structure for codec driver instance.

Returns
0 on success, negative error code on failure

static inline int audio_codec_register_error_callback(const struct device *dev,
audio_codec_error_callback_t cb)

Register a callback function for codec error.
The callback will be called from a thread, so I2C or SPI operations are safe. However,
the thread’s stack is limited and defined by the driver. It is currently up to the caller to
to ensure that the callback does not overflow the stack.

Parameters
   • dev – Pointer to the audio codec device
   • cb – The function that should be called when an error is detected fires

Returns
0 if successful, negative errno code if failure.

union audio_dai_cfg_t
#include <codec.h> Digital Audio Interface Configuration.
Configuration is dependent on DAI type
Public Members

struct i2s_config i2s
    I2S configuration.

struct audio_codec_cfg
    #include <codec.h> Codec configuration parameters.

Public Members

uint32_t mclk_freq
    MCLK input frequency in Hz.

    audio_dai_type_t dai_type
    Digital interface type.

    audio_dai_cfg_t dai_cfg
    DAI configuration info.

union audio_property_value_t
    #include <codec.h> Codec property values.

Public Members

int vol
    Volume level in 0.5dB resolution.

bool mute
    Mute if true, unmute if false.

Digital Microphone (DMIC)

Overview  The audio DMIC interface provides access to digital microphones.

Configuration Options  Related configuration options:
    • CONFIG_AUDIO_DMIC

API Reference  Related code samples

Digital Microphone (DMIC)
    Perform PDM transfers using different configurations.

X-NUCLEO-IKS02A1 shield - MEMS microphone
    Acquire audio using the digital MEMS microphone on X-NUCLEO-IKS02A1 shield.
group audio_dmic_interface
   Abstraction for digital microphones.

Enums

enum dmic_state
   DMIC driver states.
   Values:
   
   enumerator DMIC_STATE_UNINIT
      Uninitialized.
   
   enumerator DMIC_STATE_INITIALIZED
      Initialized.
   
   enumerator DMIC_STATE_CONFIGURED
      Configured.
   
   enumerator DMIC_STATE_ACTIVE
      Active.
   
   enumerator DMIC_STATE_PAUSED
      Paused.
   
   enumerator DMIC_STATE_ERROR
      Error.

enum dmic_trigger
   DMIC driver trigger commands.
   Values:
   
   enumerator DMIC_TRIGGER_STOP
      Stop stream.
   
   enumerator DMIC_TRIGGER_START
      Start stream.
   
   enumerator DMIC_TRIGGER_PAUSE
      Pause stream.
   
   enumerator DMIC_TRIGGER_RELEASE
      Release paused stream.
   
   enumerator DMIC_TRIGGER_RESET
      Reset stream.
enum pdm_lr
    PDM Channels LEFT / RIGHT.
    Values:
    enumerator PDM_CHAN_LEFT
        Left channel.
    enumerator PDM_CHAN_RIGHT
        Right channel.

Functions

static inline uint32_t dmic_build_channel_map(uint8_t channel, uint8_t pdm, enum pdm_lr lr)
    Build the channel map to populate struct pdm_chan_cfg.
    Returns the map of PDM controller and LEFT/RIGHT channel shifted to the bit position corresponding to the input logical channel value
    Parameters
    • channel – The logical channel number
    • pdm – The PDM hardware controller number
    • lr – LEFT/RIGHT channel within the chosen PDM hardware controller
    Returns
    Bit-map containing the PDM and L/R channel information

static inline void dmic_parse_channel_map(uint32_t channel_map_lo, uint32_t channel_map_hi, uint8_t channel, uint8_t *pdm, enum pdm_lr *lr)
    Helper function to parse the channel map in pdm_chan_cfg.
    Returns the PDM controller and LEFT/RIGHT channel corresponding to the channel map and the logical channel provided as input
    Parameters
    • channel_map_lo – Lower order/significant bits of the channel map
    • channel_map_hi – Higher order/significant bits of the channel map
    • channel – The logical channel number
    • pdm – Pointer to the PDM hardware controller number
    • lr – Pointer to the LEFT/RIGHT channel within the PDM controller
    Returns
    Bit-map containing the clock skew information

7.6. Peripherals
static inline int dmic_configure(const struct device *dev, struct dmic_cfg *cfg)
Configure the DMIC driver and controller(s)
Configures the DMIC driver device according to the number of channels, channel mapping, PDM I/O configuration, PCM stream configuration, etc.

Parameters

- **dev** – Pointer to the device structure for DMIC driver instance
- **cfg** – Pointer to the structure containing the DMIC configuration

Returns
0 on success, a negative error code on failure

static inline int dmic_trigger(const struct device *dev, enum dmic_trigger cmd)
Send a command to the DMIC driver.
Sends a command to the driver to perform a specific action

Parameters

- **dev** – Pointer to the device structure for DMIC driver instance
- **cmd** – The command to be sent to the driver instance

Returns
0 on success, a negative error code on failure

static inline int dmic_read(const struct device *dev, uint8_t stream, void **buffer, size_t *size, int32_t timeout)
Read received decimated PCM data stream.
Optionally waits for audio to be received and provides the received audio buffer from the requested stream

Parameters

- **dev** – Pointer to the device structure for DMIC driver instance
- **stream** – Stream identifier
- **buffer** – Pointer to the received buffer address
- **size** – Pointer to the received buffer size
- **timeout** – Timeout in milliseconds to wait in case audio is not yet received, or SYS_FOREVER_MS

Returns
0 on success, a negative error code on failure

struct pdm_io_cfg

#include <dmic.h> PDM Input/Output signal configuration.

Parameters common to all PDM controllers

uint32_t min_pdm_clk_freq
Minimum clock frequency supported by the mic.

uint32_t max_pdm_clk_freq
Maximum clock frequency supported by the mic.
Parameters unique to each PDM controller

uint8_t pdm_clk_pol
Bit mask to optionally invert PDM clock.

uint8_t pdm_data_pol
Bit mask to optionally invert mic data.

uint32_t pdm_clk_skew
Collection of clock skew values for each PDM port.

struct pcm_stream_cfg
#include <dmic.h> Configuration of the PCM streams to be output by the PDM hardware.

Note: if either pcm_rate or pcm_width is set to 0 for a stream, the stream would be disabled

Public Members

uint32_t pcm_rate
PCM sample rate of stream.

uint8_t pcm_width
PCM sample width of stream.

uint16_t block_size
PCM sample block size per transfer.

struct k_mem_slab *mem_slab
SLAB for DMIC driver to allocate buffers for stream.

struct pdm_chan_cfg
#include <dmic.h> Mapping/ordering of the PDM channels to logical PCM output channel.

Since each controller can have 2 audio channels (stereo), there can be a total of 8x2=16 channels. The actual number of channels shall be described in act_num-chan.

If 2 streams are enabled, the channel order will be the same for both streams.

Each channel is described as a 4-bit number, the least significant bit indicates LEFT/RIGHT selection of the PDM controller.

The most significant 3 bits indicate the PDM controller number:
• bits 0-3 are for channel 0, bit 0 indicates LEFT or RIGHT
• bits 4-7 are for channel 1, bit 4 indicates LEFT or RIGHT and so on.

CONSTRAINT: The LEFT and RIGHT channels of EACH PDM controller needs to be ad-
jacent to each other.

**Requested channel map**

`uint32_t req_chan_map_lo`
Channels 0 to 7.

`uint32_t req_chan_map_hi`
Channels 8 to 15.

**Actual channel map that the driver could configure**

`uint32_t act_chan_map_lo`
Channels 0 to 7.

`uint32_t act_chan_map_hi`
Channels 8 to 15.

**Public Members**

`uint8_t req_num_chan`
Requested number of channels.

`uint8_t act_num_chan`
Actual number of channels that the driver could configure.

`uint8_t req_num_streams`
Requested number of streams for each channel.

`uint8_t act_num_streams`
Actual number of streams that the driver could configure.

```c
struct dmic_cfg
#include <dmic.h> // Input configuration structure for the DMIC configuration API.
```

**Public Members**

```c
struct pcm_stream_cfg *streams
Array of pcm_stream_cfg for application to provide configuration for each stream.
```
Inter-IC Sound (I2S) Bus

Overview  The I2S (Inter-IC Sound) API provides support for the standard I2S interface as well as common non-standard extensions such as PCM Short/Long Frame Sync and Left/Right Justified Data Formats.

Configuration Options  Related configuration options:
  • CONFIG_I2S

API Reference  Related code samples

I2S echo
  Process an audio stream to add an echo effect.

I2S output
  Send I2S output stream

USB Audio asynchronous explicit feedback sample
  USB Audio 2 explicit feedback sample playing audio on I2S.


group i2s_interface
  I2S (Inter-IC Sound) Interface.

  The I2S API provides support for the standard I2S interface standard as well as common non-standard extensions such as PCM Short/Long Frame Sync, Left/Right Justified Data Format.

Defines

I2S_FMT_DATA_FORMAT_SHIFT
  Data Format bit field position.

I2S_FMT_DATA_FORMAT_MASK
  Data Format bit field mask.

I2S_FMT_DATA_FORMAT_I2S
  Standard I2S Data Format.

  Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the rising edge of the clock signal (SCK). The MSB is always sent one clock period after the WS changes. Left channel data are sent first indicated by WS = 0, followed by right channel data indicated by WS = 1.

I2S_FMT_DATA_FORMAT_PCM_SHORT

PCM Short Frame Sync Data Format.

Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the falling edge of the clock signal (SCK). The falling edge of the frame sync signal (WS) indicates the start of the PCM word. The frame sync is one clock cycle long. An arbitrary number of data words can be sent in one frame.

| SCK | WS | SD | | Word 1 | | Word 2 | | Word 3 | | Word n |
|-----|----|----|-----|-----|-----|-----|-----|-----|
|     |    |    |     |     |     |     |     |     |

I2S_FMT_DATA_FORMAT_PCM_LONG

PCM Long Frame Sync Data Format.

Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the falling edge of the clock signal (SCK). The rising edge of the frame sync signal (WS) indicates the start of the PCM word. The frame sync has an arbitrary length, however it has to fall before the start of the next frame. An arbitrary number of data words can be sent in one frame.

| SCK | WS | SD | | Word 1 | | Word 2 | | Word 3 | | Word n |
|-----|----|----|-----|-----|-----|-----|-----|-----|
|     |    |    |     |     |     |     |     |     |

I2S_FMT_DATA_FORMAT_LEFT_JUSTIFIED

Left Justified Data Format.

Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the rising edge of the clock signal (SCK). The bits within the data word are left justified such that the MSB is always sent in the clock period following the WS transition. Left channel data are sent first indicated by WS = 1, followed by right channel data indicated by WS = 0.

| SCK | WS | SD | | Left channel | | Right channel |
|-----|----|----|-----|-----|-----|
|     |    |    |     |     |     |

I2S_FMT_DATA_FORMAT_RIGHT_JUSTIFIED

Right Justified Data Format.

Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the rising edge of the clock signal.
The bits within the data word are right justified such that the LSB is always sent in the clock period preceding the WS transition. Left channel data are sent first indicated by WS = 1, followed by right channel data indicated by WS = 0.

<table>
<thead>
<tr>
<th>SCK</th>
<th>WS</th>
<th>SD</th>
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<td>x</td>
</tr>
</tbody>
</table>

| Left channel | Right channel |

I2S_FMT_DATA_ORDER_MSB
Send MSB first.

I2S_FMT_DATA_ORDER_LSB
Send LSB first.

I2S_FMT_DATA_ORDER_INV
Invert bit ordering, send LSB first.

I2S_FMT_CLK_FORMAT_SHIFT
Data Format bit field position.

I2S_FMT_CLK_FORMAT_MASK
Data Format bit field mask.

I2S_FMT_BIT_CLK_INV
Invert bit clock.

I2S_FMT_FRAME_CLK_INV
Invert frame clock.

I2S_FMT_CLK_NF_NB
Normal Frame, Normal Bit Clk.

I2S_FMT_CLK_NF_IB
Normal Frame, Inverted Bit Clk.

I2S_FMT_CLK_IF_NB
Inverted Frame, Normal Bit Clk.

I2S_FMT_CLK_IF_IB
Inverted Frame, Inverted Bit Clk.

I2S_FMT_BIT_CLK_CONT
Run bit clock continuously.

I2S_FMT_BIT_CLK_GATED
Run bit clock when sending data only.
I2S_OPT_BIT_CLK_MASTER
I2S driver is bit clock master.

I2S_OPT_BIT_CLK_SLAVE
I2S driver is bit clock slave.

I2S_OPT_FRAME_CLK_MASTER
I2S driver is frame clock master.

I2S_OPT_FRAME_CLK_SLAVE
I2S driver is frame clock slave.

I2S_OPT_LOOPBACK
Loop back mode.
In loop back mode RX input will be connected internally to TX output. This is used primarily for testing.

I2S_OPT_PINGPONG
Ping pong mode.
In ping pong mode TX output will keep alternating between a ping buffer and a pong buffer. This is normally used in audio streams when one buffer is being populated while the other is being played (DMAed) and vice versa. So, in this mode, 2 sets of buffers fixed in size are used. Static Arrays are used to achieve this and hence they are never freed.

**Typedefs**

typedef uint8_t i2s_fmt_t
I2S data stream format options.

typedef uint8_t i2s_opt_t
I2S configuration options.

** Enums**

enum i2s_dir
I2C Direction.

*Values:*

enumerator I2S_DIR_RX
Receive data.

enumerator I2S_DIR_TX
Transmit data.

enumerator I2S_DIR_BOTH
Both receive and transmit data.
enum i2s_state

Interface state.

Values:

enumerator I2S_STATE_NOT_READY
The interface is not ready.

The interface was initialized but is not yet ready to receive / transmit data. Call i2s_configure() to configure interface and change its state to READY.

enumerator I2S_STATE_READY
The interface is ready to receive / transmit data.

enumerator I2S_STATE_RUNNING
The interface is receiving / transmitting data.

enumerator I2S_STATE_STOPPING
The interface is draining its transmit queue.

enumerator I2S_STATE_ERROR
TX buffer underrun or RX buffer overrun has occurred.

enum i2s_trigger_cmd

Trigger command.

Values:

enumerator I2S_TRIGGER_START
Start the transmission / reception of data.

If I2S_DIR_TX is set some data has to be queued for transmission by the i2s_write() function. This trigger can be used in READY state only and changes the interface state to RUNNING.

enumerator I2S_TRIGGER_STOP
Stop the transmission / reception of data.

Stop the transmission / reception of data at the end of the current memory block. This trigger can be used in RUNNING state only and at first changes the interface state to STOPPING. When the current TX / RX block is transmitted / received the state is changed to READY. Subsequent START trigger will resume transmission / reception where it stopped.

enumerator I2S_TRIGGER_DRAIN
Empty the transmit queue.

Send all data in the transmit queue and stop the transmission. If the trigger is applied to the RX queue it has the same effect as I2S_TRIGGER_STOP. This trigger can be used in RUNNING state only and at first changes the interface state to STOPPING. When all TX blocks are transmitted the state is changed to READY.
enumerator **I2S_TRIGGER_DROP**  
Discard the transmit / receive queue.

Stop the transmission / reception immediately and discard the contents of the respective queue. This trigger can be used in any state other than NOT_READY and changes the interface state to READY.

enumerator **I2S_TRIGGER_PREPARE**  
Prepare the queues after underrun/overrun error has occurred.

This trigger can be used in ERROR state only and changes the interface state to READY.

### Functions

```c
int i2s_configure(const struct device *dev, enum i2s_dir dir, const struct i2s_config *cfg)
```

Configure operation of a host I2S controller.

The dir parameter specifies if Transmit (TX) or Receive (RX) direction will be configured by data provided via cfg parameter.

The function can be called in NOT_READY or READY state only. If executed successfully the function will change the interface state to READY.

If the function is called with the parameter cfg->frame_clk_freq set to 0 the interface state will be changed to NOT_READY.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `dir` – Stream direction: RX, TX, or both, as defined by I2S_DIR_. The I2S_DIR_BOTH value may not be supported by some drivers. For those, the RX and TX streams need to be configured separately.
- `cfg` – Pointer to the structure containing configuration parameters.

**Return values**

- `0` – If successful.
- `-EINVAL` – Invalid argument.
- `-ENOSYS` – I2S_DIR_BOTH value is not supported.

```c
static inline const struct i2s_config *i2s_config_get(const struct device *dev, enum i2s_dir dir)
```

Fetch configuration information of a host I2S controller.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance
- `dir` – Stream direction: RX or TX as defined by I2S_DIR_*

**Return values**

- Pointer to the structure containing configuration parameters, or NULL if un-configured

```c
static inline int i2s_read(const struct device *dev, void **mem_block, size_t *size)
```

Read data from the RX queue.

Data received by the I2S interface is stored in the RX queue consisting of memory blocks preallocated by this function from rx_mem_slab (as defined by i2s_configure).
Ownership of the RX memory block is passed on to the user application which has to release it.

The data is read in chunks equal to the size of the memory block. If the interface is in READY state the number of bytes read can be smaller.

If there is no data in the RX queue the function will block waiting for the next RX memory block to fill in. This operation can timeout as defined by i2s_configure. If the timeout value is set to K_NO_WAIT the function is non-blocking.

Reading from the RX queue is possible in any state other than NOT_READY. If the interface is in the ERROR state it is still possible to read all the valid data stored in RX queue. Afterwards the function will return -EIO error.

Parameters

- **dev** – Pointer to the device structure for the driver instance.
- **mem_block** – Pointer to the RX memory block containing received data.
- **size** – Pointer to the variable storing the number of bytes read.

Return values

- **0** – If successful.
- **-EIO** – The interface is in NOT_READY or ERROR state and there are no more data blocks in the RX queue.
- **-EBUSY** – Returned without waiting.
- **-EAGAIN** – Waiting period timed out.

```c
int i2s_buf_read(const struct device *dev, void *buf, size_t *size)
```

Read data from the RX queue into a provided buffer.

Data received by the I2S interface is stored in the RX queue consisting of memory blocks preallocated by this function from rx_mem_slab (as defined by i2s_configure). Calling this function removes one block from the queue which is copied into the provided buffer and then freed.

The provided buffer must be large enough to contain a full memory block of data, which is parameterized for the channel via i2s_configure().

This function is otherwise equivalent to i2s_read().

Parameters

- **dev** – Pointer to the device structure for the driver instance.
- **buf** – Destination buffer for read data, which must be at least as large as the configured memory block size for the RX channel.
- **size** – Pointer to the variable storing the number of bytes read.

Return values

- **0** – If successful.
- **-EIO** – The interface is in NOT_READY or ERROR state and there are no more data blocks in the RX queue.
- **-EBUSY** – Returned without waiting.
- **-EAGAIN** – Waiting period timed out.

```c
static inline int i2s_write(const struct device *dev, void *mem_block, size_t size)
```

Write data to the TX queue.

Data to be sent by the I2S interface is stored first in the TX queue. TX queue consists of memory blocks preallocated by the user from tx_mem_slab (as defined by
i2s_configure). This function takes ownership of the memory block and will release it when all data are transmitted.

If there are no free slots in the TX queue the function will block waiting for the next TX memory block to be send and removed from the queue. This operation can timeout as defined by i2s_configure. If the timeout value is set to K_NO_WAIT the function is non-blocking.

Writing to the TX queue is only possible if the interface is in READY or RUNNING state.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
- **mem_block** – Pointer to the TX memory block containing data to be sent.
- **size** – Number of bytes to write. This value has to be equal or smaller than the size of the memory block.

**Return values**

- **0** – If successful.
- **-EIO** – The interface is not in READY or RUNNING state.
- **-EBUSY** – Returned without waiting.
- **-EAGAIN** – Waiting period timed out.

```
int i2s_buf_write(const struct device *dev, void *buf, size_t size)
```

Write data to the TX queue from a provided buffer.

This function acquires a memory block from the I2S channel TX queue and copies the provided data buffer into it. It is otherwise equivalent to `i2s_write()`.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
- **buf** – Pointer to a buffer containing the data to transmit.
- **size** – Number of bytes to write. This value has to be equal or smaller than the size of the channel’s TX memory block configuration.

**Return values**

- **0** – If successful.
- **-EIO** – The interface is not in READY or RUNNING state.
- **-EBUSY** – Returned without waiting.
- **-EAGAIN** – Waiting period timed out.
- **-ENOMEM** – No memory in TX slab queue.
- **-EINVAL** – Size parameter larger than TX queue memory block.

```
int i2s_trigger(const struct device *dev, enum i2s_dir dir, enum i2s_trigger_cmd cmd)
```

Send a trigger command.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
- **dir** – Stream direction: RX, TX, or both, as defined by I2S_DIR_*.
- **cmd** – Trigger command.

**Return values**
• 0 – If successful.
• -EINVAL – Invalid argument.
• -EIO – The trigger cannot be executed in the current state or a DMA channel cannot be allocated.
• -ENOMEM – RX/TX memory block not available.
• -ENOSYS – I2S_DIR_BOTH value is not supported.

struct i2s_config

```c
#include <i2s.h> Interface configuration options.
```

Memory slab pointed to by the mem_slab field has to be defined and initialized by the user. For I2S driver to function correctly number of memory blocks in a slab has to be at least 2 per queue. Size of the memory block should be multiple of frame_size where frame_size = (channels * word_size_bytes). As an example 16 bit word will occupy 2 bytes, 24 or 32 bit word will occupy 4 bytes.

Please check Zephyr Kernel Primer for more information on memory slabs.

**Remark**

When I2S data format is selected parameter channels is ignored, number of words in a frame is always 2.

**Public Members**

```c
uint8_t word_size
    Number of bits representing one data word.
```

```c
uint8_t channels
    Number of words per frame.
```

```c
i2s_fmt_t format
    Data stream format as defined by I2S_FMT_* constants.
```

```c
i2s_opt_t options
    Configuration options as defined by I2S_OPT_* constants.
```

```c
uint32_t frame_clk_freq
    Frame clock (WS) frequency, this is sampling rate.
```

```c
struct k_mem_slab *mem_slab
    Memory slab to store RX/TX data.
```

```c
size_t block_size
    Size of one RX/TX memory block (buffer) in bytes.
```

7.6. Peripherals
**Digital Audio Interface (DAI)**

**Overview**  The DAI (Digital Audio Interface) is a generic high level API for audio drivers. It can be configured with bespoke data for vendor specific configuration.

**Configuration Options**  Related configuration options:
- `CONFIG_DAI`

**API Reference**

**group dai_interface**

DAI Interface.

The DAI API provides support for the standard I2S (SSP) and its common variants. It supports also DMIC, HDA and SDW backends. The API has a config function with bespoke data argument for device/vendor specific config. There are also optional timestamping functions to get device specific audio clock time.

**Defines**

`DAI_FORMAT_CLOCK_PROVIDER_MASK`

Used to extract the clock configuration from the format attribute of struct `dai_config`.

`DAI_FORMAT_PROTOCOL_MASK`

Used to extract the protocol from the format attribute of struct `dai_config`.

`DAI_FORMAT_CLOCK_INVERSION_MASK`

Used to extract the clock inversion from the format attribute of struct `dai_config`.

** Enums**

**enum dai_clock_provider**

DAI clock configurations.

This is used to describe all of the possible clock-related configurations w.r.t the DAI and the codec.

**Values:**

- `DAI_CBP_CFP = (0 « 12)`
  - codec BCLK provider, codec FSYNC provider
  - codec BCLK consumer, codec FSYNC provider
enumerator DAI_CBC_CFP = (2 « 12)
codec BCLK provider, codec FSYNC consumer

denumerator DAI_CB_P_CFC = (3 « 12)
codec BCLK consumer, codec FSYNC consumer

denumerator DAI_CBC_CFC = (4 « 12)

d enum dai_protocol
DAI protocol.
The communication between the DAI and the CODEC may use different protocols depending on the scenario.

Values:

denumerator DAI_PROTO_I2S = 1
I2S.

denumerator DAI_PROTO_RIGHT_J
Right Justified.

denumerator DAI_PROTO_LEFT_J
Left Justified.

denumerator DAI_PROTO_DSP_A
TDM, FSYNC asserted 1 BCLK early.

denumerator DAI_PROTO_DSP_B
TDM, FSYNC asserted at the same time as MSB.

denumerator DAI_PROTO_PDM
Pulse Density Modulation.

d enum dai_clock_inversion
DAI clock inversion.
Some applications may require a different clock polarity (FSYNC/BCLK) compared to the default one chosen based on the protocol.

Values:

denumerator DAI_INVERSION_NB_NF = 0
no BCLK inversion, no FSYNC inversion
no BCLK inversion, FSYNC inversion

denumerator DAI_INVERSION_NB_IF = (2 « 8)
BCLK inversion, no FSYNC inversion.

denumerator DAI_INVERSION_IB_NF = (3 « 8)
BCLK inversion, FSYNC inversion.
enumerator DAI_INVERSION_IB_IF = (4 * 8)

denum dai_type

Types of DAI.
The type of the DAI. This ID type is used to configure bespoke DAI HW settings.
DAIs have a lot of physical link feature variability and therefore need different configuration data to cater for different use cases. We usually need to pass extra bespoke configuration prior to DAI start.

Values:

enumerator DAI_LEGACY_I2S = 0
    Legacy I2S compatible with i2s.h.

enumerator DAI_INTEL_SSP
    Intel SSP.

enumerator DAI_INTEL_DMIC
    Intel DMIC.

enumerator DAI_INTEL_HDA
    Intel HD/A.

enumerator DAI_INTEL_ALH
    Intel ALH.

enumerator DAI_IMX_SAI
    i.MX SAI

enumerator DAI_IMX_ESAI
    i.MX ESAI

enumerator DAI_AMD_BT
    Amd BT.

enumerator DAI_AMD_SP
    Amd SP.

enumerator DAI_AMD_DMIC
    Amd DMIC.

enumerator DAI_MEDIATEK_AFE
    Mtk AFE.

enumerator DAI_INTEL_SSP_NHLT
    nhlt ssp

enumerator DAI_INTEL_DMIC_NHLT
    nhlt ssp

enumerator DAI_INTEL_SSP_NHLT
    nhlt ssp

enumerator DAI_INTEL_DMIC_NHLT
    nhlt ssp

enumerator DAI_INTEL_SSP_NHLT
    nhlt ssp
enumerator DAI_INTEL_HDA_NHLT
  nhlt Intel HD/A

enumerator DAI_INTEL_ALH_NHLT
  nhlt Intel ALH

enum dai_dir
  DAI Direction.
  Values:

  enumerator DAI_DIR_TX = 0
    Transmit data.

  enumerator DAI_DIR_RX
    Receive data.

  enumerator DAI_DIR_BOTH
    Both receive and transmit data.

enum dai_state
  Interface state.
  Values:

  enumerator DAI_STATE_NOT_READY = 0
    The interface is not ready.
    The interface was initialized but is not yet ready to receive / transmit data. Call dai_config_set() to configure interface and change its state to READY.

  enumerator DAI_STATE_READY
    The interface is ready to receive / transmit data.

  enumerator DAI_STATE_RUNNING
    The interface is receiving / transmitting data.

  enumerator DAI_STATE_PRE_RUNNING
    The interface is clocking but not receiving / transmitting data.

  enumerator DAI_STATE_PAUSED
    The interface paused.

  enumerator DAI_STATE_STOPPING
    The interface is draining its transmit queue.

  enumerator DAI_STATE_ERROR
    TX buffer underrun or RX buffer overrun has occurred.
```markdown
enum dai_trigger_cmd

Trigger command.

Values:

<table>
<thead>
<tr>
<th>Enumerator</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>DAI_TRIGGER_START</td>
<td>Start the transmission / reception of data.</td>
</tr>
<tr>
<td></td>
<td>If DAI_DIR_TX is set some data has to be queued for transmission by the dai_write() function. This trigger can be used in READY state only and changes the interface state to RUNNING.</td>
</tr>
<tr>
<td>DAI_TRIGGER_PRE_START</td>
<td>Optional - Pre Start the transmission / reception of data.</td>
</tr>
<tr>
<td></td>
<td>Allows the DAI and downstream codecs to prepare for audio Tx/Rx by starting any required clocks for downstream PLL/FLL locking.</td>
</tr>
<tr>
<td>DAI_TRIGGER_STOP</td>
<td>Stop the transmission / reception of data.</td>
</tr>
<tr>
<td></td>
<td>Stop the transmission / reception of data at the end of the current memory block. This trigger can be used in RUNNING state only and at first changes the interface state to STOPPING. When the current TX / RX block is transmitted / received the state is changed to READY. Subsequent START trigger will resume transmission / reception where it stopped.</td>
</tr>
<tr>
<td>DAI_TRIGGER_PAUSE</td>
<td>Pause the transmission / reception of data.</td>
</tr>
<tr>
<td></td>
<td>Pause the transmission / reception of data at the end of the current memory block. Behavior is implementation specific but usually this state doesn't completely stop the clocks or transmission. The DAI could be transmitting 0's (silence), but it is not consuming data from outside.</td>
</tr>
<tr>
<td>DAI_TRIGGER_POST_STOP</td>
<td>Optional - Post Stop the transmission / reception of data.</td>
</tr>
<tr>
<td></td>
<td>Allows the DAI and downstream codecs to shutdown cleanly after audio Tx/Rx by stopping any required clocks for downstream audio completion.</td>
</tr>
<tr>
<td>DAI_TRIGGER_DRAIN</td>
<td>Empty the transmit queue.</td>
</tr>
<tr>
<td></td>
<td>Send all data in the transmit queue and stop the transmission. If the trigger is applied to the RX queue it has the same effect as DAI_TRIGGER_STOP. This trigger can be used in RUNNING state only and at first changes the interface state to STOPPING. When all TX blocks are transmitted the state is changed to READY.</td>
</tr>
<tr>
<td>DAI_TRIGGER_DROP</td>
<td>Discard the transmit / receive queue.</td>
</tr>
</tbody>
</table>
```

Stop the transmission / reception immediately and discard the contents of the respective queue. This trigger can be used in any state other than NOT_READY and changes the interface state to READY.

enumerator DAI_TRIGGER_PREPARE
Prepare the queues after underrun/overrun error has occurred.
This trigger can be used in ERROR state only and changes the interface state to READY.

enumerator DAI_TRIGGER_RESET
Reset.
This trigger frees resources and moves the driver back to initial state.

enumerator DAI_TRIGGER_COPY
Copy.
This trigger prepares for data copying.

**Functions**

static inline int dai_probe(const struct device *dev)
Probe operation of DAI driver.
The function will be called to power up the device and update for example possible reference count of the users. It can be used also to initialize internal variables and memory allocation.

**Parameters**
- *dev – Pointer to the device structure for the driver instance.

**Return values**
- 0 – If successful.

static inline int dai_remove(const struct device *dev)
Remove operation of DAI driver.
The function will be called to unregister/unbind the device, for example to power down the device or decrease the usage reference count.

**Parameters**
- *dev – Pointer to the device structure for the driver instance.

**Return values**
- 0 – If successful.

static inline int dai_config_set(const struct device *dev, const struct dai_config *cfg, const void *bespoke_cfg)
Configure operation of a DAI driver.
The dir parameter specifies if Transmit (TX) or Receive (RX) direction will be configured by data provided via cfg parameter.
The function can be called in NOT_READY or READY state only. If executed successfully the function will change the interface state to READY.
If the function is called with the parameter cfg->frame_clk_freq set to 0 the interface state will be changed to NOT_READY.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.
- `cfg` – Pointer to the structure containing configuration parameters.
- `bespoke_cfg` – Pointer to the structure containing bespoke config.

**Return values**
- `0` – If successful.
- `-EINVAL` – Invalid argument.
- `-ENOSYS` – DAI_DIR_BOTH value is not supported.

```c
static inline int dai_config_get(const struct device *dev, struct dai_config *cfg, enum dai_dir dir)
```

Fetch configuration information of a DAI driver.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance
- `cfg` – Pointer to the config structure to be filled by the instance
- `dir` – Stream direction: RX or TX as defined by DAI_DIR_*

**Return values**
- `0` – if success, negative if invalid parameters or DAI un-configured

```c
static inline const struct dai_properties *dai_get_properties(const struct device *dev, enum dai_dir dir, int stream_id)
```

Fetch properties of a DAI driver.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance
- `dir` – Stream direction: RX or TX as defined by DAI_DIR_*
- `stream_id` – Stream id: some drivers may have stream specific properties, this id specifies the stream.

**Return values**
- Pointer to the structure containing properties, or NULL if error or no properties

```c
static inline int dai_trigger(const struct device *dev, enum dai_dir dir, enum dai_trigger_cmd cmd)
```

Send a trigger command.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.
- `dir` – Stream direction: RX, TX, or both, as defined by DAI_DIR_* The DAI_DIR_BOTH value may not be supported by some drivers. For those, triggering need to be done separately for the RX and TX streams.
- `cmd` – Trigger command.

**Return values**
- `0` – If successful.
- `-EINVAL` – Invalid argument.
• -EIO – The trigger cannot be executed in the current state or a DMA channel cannot be allocated.
• -ENOMEM – RX/TX memory block not available.
• -ENOSYS – DAI_DIR_BOTH value is not supported.

static inline int dai_ts_config(const struct device *dev, struct dai_ts_cfg *cfg)
Configures timestamping in attached DAI.

Optional method.

Parameters
• dev – Component device.
• cfg – Timestamp config.

Return values
0 – If successful.

static inline int dai_ts_start(const struct device *dev, struct dai_ts_cfg *cfg)
Starts timestamping.

Optional method

Parameters
• dev – Component device.
• cfg – Timestamp config.

Return values
0 – If successful.

static inline int dai_ts_stop(const struct device *dev, struct dai_ts_cfg *cfg)
Stops timestamping.

Optional method.

Parameters
• dev – Component device.
• cfg – Timestamp config.

Return values
0 – If successful.

static inline int dai_ts_get(const struct device *dev, struct dai_ts_cfg *cfg, struct dai_ts_data *tsd)
Gets timestamp.

Optional method.

Parameters
• dev – Component device.
• cfg – Timestamp config.
• tsd – Receives timestamp data.

Return values
0 – If successful.
struct dai_properties
#include <dai.h> DAI properties.
This struct is used with APIs get_properties function to query DAI properties like fifo address and dma handshake. These are needed for example to setup dma outside the driver code.

Public Members

uint32_t fifo_address
Fifo hw address for e.g. when connecting to dma.

uint32_t fifo_depth
Fifo depth.

uint32_t dma_hs_id
DMA handshake id.

uint32_t reg_init_delay
Delay for initializing registers.

int stream_id
Stream ID.

struct dai_config
#include <dai.h> Main DAI config structure.
Generic DAI interface configuration options.

Public Members

enum dai_type type
Type of the DAI.

uint32_t dai_index
Index of the DAI.

uint8_t channels
Number of audio channels, words in frame.

uint32_t rate
Frame clock (WS) frequency, sampling rate.

uint16_t format
DAI specific data stream format.
uint8_t options
    DAI specific configuration options.

typedef uint8_t word_size
    Number of bits representing one data word.

typsizet block_size
    Size of one RX/TX memory block (buffer) in bytes.

typedef uint16_t link_config
    DAI specific link configuration.

struct dai_ts_cfg
    #include <dai.h> DAI timestamp configuration.

Public Members

uint32_t walclk_rate
    Rate in Hz, e.g.
    192000000

int type
    Type of the DAI (SSP, DMIC, HDA, etc.).

int direction
    Direction (playback/capture)

int index
    Index for SSPx to select correct timestamp register.

int dma_id
    DMA instance id.

int dma_chan_index
    Used DMA channel index.

int dma_chan_count
    Number of channels in single DMA.

struct dai_ts_data
    #include <dai.h> DAI timestamp data.

Public Members

uint64_t walclk
    Wall clock.
uint64_t sample
Sample count.

uint32_t walclk_rate
Rate in Hz, e.g.
19200000

7.6.5 Battery Backed RAM (BBRAM)

The BBRAM APIs allow interfacing with the unique properties of this memory region. The following common types of BBRAM properties are easily accessed via this API:

- IBBR (invalid) state - check that the BBRAM is not corrupt.
- VSBY (voltage standby) state - check if the BBRAM is using standby voltage.
- VCC (active power) state - check if the BBRAM is on normal power.
- Size - get the size (in bytes) of the BBRAM region.

Along with these, the API provides a means for reading and writing to the memory region via \texttt{bbram\_read()} and \texttt{bbram\_write()} respectively. Both functions are expected to only succeed if the BBRAM is in a valid state and the operation is bounded to the memory region.

API Reference

\texttt{group bbram\_interface}\n\texttt{BBRAM Interface.}\n
**Typedefs**

typedef int (*\texttt{bbram\_api\_check\_invalid\_t})(const struct \texttt{device} *\texttt{dev})
API template to check if the BBRAM is invalid.

\texttt{See also:}\n\texttt{bbram\_check\_invalid}\n
typedef int (*\texttt{bbram\_api\_check\_standby\_power\_t})(const struct \texttt{device} *\texttt{dev})
API template to check for standby power failure.

\texttt{See also:}\n\texttt{bbram\_check\_standby\_power}\n
typedef int (*\texttt{bbram\_api\_check\_power\_t})(const struct \texttt{device} *\texttt{dev})
API template to check for VCC1 power failure.

\texttt{See also:}\n\texttt{bbram\_check\_power}
typedef int (*bbram_api_get_size_t)(const struct device *dev, size_t *size)
    API template to check the size of the BBRAM.

    See also:
    bbram_get_size

typedef int (*bbram_api_read_t)(const struct device *dev, size_t offset, size_t size, uint8_t *data)
    API template to read from BBRAM.

    See also:
    bbram_read

typedef int (*bbram_api_write_t)(const struct device *dev, size_t offset, size_t size, const uint8_t *data)
    API template to write to BBRAM.

    See also:
    bbram_write

Functions

int bbram_check_invalid(const struct device *dev)
    Check if BBRAM is invalid.
    Check if “Invalid Battery-Backed RAM” status is set then reset the status bit. This may occur as a result to low voltage at the VBAT pin.

    Parameters
    • dev – [in] BBRAM device pointer.

    Returns
    0 if the Battery-Backed RAM data is valid, -EFAULT otherwise.

int bbram_check_standby_power(const struct device *dev)
    Check for standby (Volt SBY) power failure.
    Check if the V standby power domain is turned on after it was off then reset the status bit.

    Parameters
    • dev – [in] BBRAM device pointer.

    Returns
    0 if V SBY power domain is in normal operation.

int bbram_check_power(const struct device *dev)
    Check for V CC1 power failure.
    This will return an error if the V CC1 power domain is turned on after it was off and reset the status bit.

    Parameters
• dev – [in] BBRAM device pointer.

Returns
0 if the V CC1 power domain is in normal operation, -EFAULT otherwise.

int bbram_get_size(const struct device *dev, size_t *size)
Get the size of the BBRAM (in bytes).

Parameters
• dev – [in] BBRAM device pointer.
• size – [out] Pointer to write the size to.

Returns
0 for success, -EFAULT otherwise.

int bbram_read(const struct device *dev, size_t offset, size_t size, uint8_t *data)
Read bytes from BBRAM.

Parameters
• dev – [in] The BBRAM device pointer to read from.
• offset – [in] The offset into the RAM address to start reading from.
• size – [in] The number of bytes to read.
• data – [out] The buffer to load the data into.

Returns
0 on success, -EFAULT if the address range is out of bounds.

int bbram_write(const struct device *dev, size_t offset, size_t size, const uint8_t *data)
Write bytes to BBRAM.

Parameters
• dev – [in] The BBRAM device pointer to write to.
• offset – [in] The offset into the RAM address to start writing to.
• size – [in] The number of bytes to write.
• data – [out] Pointer to the start of data to write.

Returns
0 on success, -EFAULT if the address range is out of bounds.

int bbram_emul_set_invalid(const struct device *dev, bool is_invalid)
Set the emulated BBRAM driver's invalid state.
Calling this will affect the emulated behavior of bbram_check_invalid().

Parameters
• dev – [in] The emulated device to modify
• is_invalid – [in] The new invalid state

Returns
0 on success, negative values on error.

int bbram_emul_set_standby_power_state(const struct device *dev, bool failure)
Set the emulated BBRAM driver's standby power state.
Calling this will affect the emulated behavior of bbram_check_standby_power().

Parameters
• dev – [in] The emulated device to modify
• failure – [in] Whether or not standby power failure should be emulated

**Returns**
0 on success, negative values on error.

```c
int bbram_emul_set_power_state(const struct device *dev, bool failure)
```

Set the emulated BBRAM driver's power state.

Calling this will affect the emulated behavior of `bbram_check_power()`.

**Parameters**

• dev – [in] The emulated device to modify

• failure – [in] Whether or not a power failure should be emulated

**Returns**
0 on success, negative values on error.

```c
struct bbram_driver_api
#include <bbram.h>
```

### 7.6.6 BC1.2 Devices (Experimental)

The Battery Charging specification, currently at revision 1.2, is commonly referred to as just BC1.2. BC1.2 defines limits and detection mechanisms for USB devices to draw current exceeding the USB 2.0 specification limit of 0.5A, 2.5W.

The BC1.2 specification uses the term Charging Port for the device that supplies VBUS on the USB connection and the term Portable Device for the device that sinks current from the USB connection.

**Note that the BC1.2 Specification** uses the acronym PD for Portable Device. This should not be confused with the USB-C Power Delivery, which also uses the acronym PD.

On many devices, BC1.2 is the fallback mechanism to determine the connected charger capability on USB type C ports when the attached type-C partner does not support Power Delivery.

**Key parameters from the BC1.2 Specification** include:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Symbol</th>
<th>Range</th>
</tr>
</thead>
<tbody>
<tr>
<td>Allowed PD (portable device) Current Draw from Charging Port</td>
<td>IDEV_CHG</td>
<td>1.5 A</td>
</tr>
<tr>
<td>Charging Downstream Port Rated Current</td>
<td>ICDP</td>
<td>1.5 - 5.0 A</td>
</tr>
<tr>
<td>Maximum Configured Current when connected to a SDP</td>
<td>ICFG_MAX</td>
<td>500 mA</td>
</tr>
<tr>
<td>Dedicated Charging Port Rated Current</td>
<td>IDCP</td>
<td>1.5 - 5.0 A</td>
</tr>
<tr>
<td>Suspend current</td>
<td>ISUSP</td>
<td>2.5 mA</td>
</tr>
<tr>
<td>Unit load current</td>
<td>IUNIT</td>
<td>100 mA</td>
</tr>
</tbody>
</table>

While the ICDP and IDCP rated currents go up to 5.0 A, the BC1.2 current is limited by the IDEV_CHG parameter. So the BC1.2 support is capped at 1.5 A in the Zephyr implementation when using portable-device mode.

**Basic Operation**

The BC1.2 device driver provides only two APIs, `bc12_set_role()` and `bc12_set_result_cb()`. The application calls `bc12_set_role()` to transition the BC1.2 device to either a disconnected, portable-device, or charging port mode.
For the disconnected state, the BC1.2 driver powers down the detection chip. The power down operation is vendor specific.

The application calls `bc12_set_role()` with the type set to `BC12_PORTABLE_DEVICE` when both the following conditions are true:

- The application configured the port as an upstream facing port, i.e. a USB device port.
- The application detects VBUS on the USB connection.

For portable-device mode, the BC1.2 driver powers up the detection chip and starts charger detection. At completion of the charger detection, the BC1.2 driver notifies the callback registered with `bc12_set_result_cb()`. By default, the BC1.2 driver clamps the current to 1.5A to comply with the BC1.2 specification.

To comply with the USB 2.0 specification, when the driver detects a SDP (Standard Downstream Port) charging partner or if BC1.2 detection fails, the driver reports the available current as ISUSP (2.5 mA). The application may increase the current draw to IUNIT (100 mA) when the connected USB host resumes the USB bus and may increase the current draw to ICFG_MAX (500 mA) when the USB host configures the USB device.

Charging port mode is used by the application when the USB port is configured as a downstream facing port, i.e. a USB host port. For charging port mode, the BC1.2 driver powers up the detection chip and configures the charger type specified by a devicetree property. If the driver supports detection of plug and unplug events, the BC1.2 driver notifies the callback registered with `bc12_set_result_cb()` to indicate the current connection state of the portable device partner.

### Configuration Options

Related configuration options:

- `CONFIG_USB_BC12`

### API Reference

**group b12_interface**

BC1.2 driver APIs.

**BC1.2 constants**

**BC12_CHARGER_VOLTAGE_UV**

BC1.2 USB charger voltage.

**BC12_CHARGER_MIN_CURR_UA**

BC1.2 USB charger minimum current.

Set to match the Isusp of 2.5 mA parameter. This is returned by the driver when either BC1.2 detection fails, or the attached partner is a SDP (standard downstream port).

The application may increase the current draw after determining the USB device state of suspended/unconfigured/configured. Suspended: 2.5 mA Unconfigured: 100 mA Configured: 500 mA (USB 2.0)

**BC12_CHARGER_MAX_CURR_UA**

BC1.2 USB charger maximum current.
Typedefs

typedef void (*bc12_callback_t)(const struct device *dev, struct bc12_partner_state *state, void *user_data)

BC1.2 callback for charger configuration.

**Param dev**
BC1.2 device which is notifying of the new charger state.

**Param state**
Current state of the BC1.2 client, including BC1.2 type detected, voltage, and current limits. If NULL, then the partner charger is disconnected or the BC1.2 device is operating in host mode.

**Param user_data**
Requester supplied data which is passed along to the callback.

Enums

enum bc12_role
BC1.2 device role.

*Values:*

enumerator BC12_DISCONNECTED
enumerator BC12_PORTABLE_DEVICE
enumerator BC12_CHARGING_PORT

enum bc12_type
BC1.2 charging partner type.

*Values:*

enumerator BC12_TYPE_NONE
No partner connected.

enumerator BC12_TYPE_SDG
Standard Downstream Port.

enumerator BC12_TYPE_DCP
Dedicated Charging Port.

enumerator BC12_TYPE_CDP
Charging Downstream Port.

enumerator BC12_TYPE_PROPRIETARY
Proprietary charging port.

enumerator BC12_TYPE_UNKNOWN
Unknown charging port, BC1.2 detection failed.
enumerator BC12_TYPE_COUNT
Count of valid BC12 types.

Functions

int bc12_set_role(const struct device *dev, enum bc12_role role)
Set the BC1.2 role.

Parameters
• dev – Pointer to the device structure for the BC1.2 driver instance.
• role – New role for the BC1.2 device.

Return values
• 0 – If successful.
• -EIO – general input/output error.

int bc12_set_result_cb(const struct device *dev, bc12_callback_t cb, void *user_data)
Register a callback for BC1.2 results.

Parameters
• dev – Pointer to the device structure for the BC1.2 driver instance.
• cb – Function pointer for the result callback.
• user_data – Requester supplied data which is passed along to the call-back.

Return values
• 0 – If successful.
• -EIO – general input/output error.

struct bc12_partner_state
#include <usb_bc12.h> BC1.2 detected partner state.

Param bc12_role
Current role of the BC1.2 device.

Param type
Charging partner type. Valid when bc12_role is BC12_PORTABLE_DEVICE.

Param current_ma
Current, in uA, that the charging partner provides. Valid when bc12_role is BC12_PORTABLE_DEVICE.

Param voltage_mv
Voltage, in uV, that the charging partner provides. Valid when bc12_role is BC12_PORTABLE_DEVICE.

Param pd_partner_connected
True if a PD partner is currently connected. Valid when bc12_role is BC12_CHARGING_PORT.

group b12_emulator_backend
BC1.2 backend emulator APIs.
Functions

static inline int bc12_emul_set_charging_partner(const struct emul *target, enum bc12_type partner_type)

Set the charging partner type connected to the BC1.2 device.
The corresponding BC1.2 emulator updates the vendor specific registers to simulate connection of the specified charging partner type. The emulator also generates an interrupt for processing by the real driver, if supported.

Parameters
- **target** – Pointer to the emulator structure for the BC1.2 emulator instance.
- **partner_type** – The simulated partner type. Set to BC12_TYPE_NONE to disconnect the charging partner.

Return values
- **0** – If successful.
- **-EINVAL** – if the partner type is not supported.

static inline int bc12_emul_set_pd_partner(const struct emul *target, bool connected)

Set the portable device partner state.
The corresponding BC1.2 emulator updates the vendor specific registers to simulate connection or disconnection of a portable device partner. The emulator also generates an interrupt for processing by the real driver, if supported.

Parameters
- **target** – Pointer to the emulator structure for the BC1.2 emulator instance.
- **connected** – If true, emulate a connection of a portable device partner. If false, emulate a disconnect event.

Return values
- **0** – If successful.
- **-EINVAL** – if the connection/disconnection of PD partner is not supported.

7.6.7 Clock Control

Overview

The clock control API provides access to clocks in the system, including the ability to turn them on and off.

Configuration Options

Related configuration options:
- **CONFIG_CLOCK_CONTROL**
Related code samples

**LiteX clock control driver**
Use LiteX clock control driver to generate multiple clock signals.

---

*groupp* clock_control_interface
Clock Control Interface.

**Defines**

CLOCK_CONTROL_SUBSYS_ALL

**Typedefs**

typedef void *clock_control_subsys_t

clock_control_subsys_t is a type to identify a clock controller sub-system.
Such data pointed is opaque and relevant only to the clock controller driver instance being used.

typedef void *clock_control_subsys_rate_t

clock_control_subsys_rate_t is a type to identify a clock controller sub-system rate.
Such data pointed is opaque and relevant only to set the clock controller rate of the driver instance being used.

typedef void (*clock_control_cb_t)(const struct device *dev, clock_control_subsys_t subsys, void *user_data)
Callback called on clock started.

**Param dev**
Device structure whose driver controls the clock.

**Param subsys**
Opaque data representing the clock.

**Param user_data**
User data.

typedef int (*clock_control)(const struct device *dev, clock_control_subsys_t sys)

typedef int (*clock_control_get)(const struct device *dev, clock_control_subsys_t sys, uint32_t *rate)

typedef int (*clock_control_async_on_fn)(const struct device *dev, clock_control_subsys_t sys, clock_control_cb_t cb, void *user_data)

typedef enum clock_control_status (*clock_control_get_status_fn)(const struct device *dev, clock_control_subsys_t sys)
typedef int (*clock_control_set)(const struct device *dev, clock_control_subsys_t sys, clock_control_subsys_rate_t rate)

typedef int (*clock_control_configure_fn)(const struct device *dev, clock_control_subsys_t sys, void *data)

Enums

define clock_control_status
    Current clock status.
    Values:
    enumerator CLOCK_CONTROL_STATUS_STARTING
    enumerator CLOCK_CONTROL_STATUS_OFF
    enumerator CLOCK_CONTROL_STATUS_ON
    enumerator CLOCK_CONTROL_STATUS_UNKNOWN

Functions

static inline int clock_control_on(const struct device *dev, clock_control_subsys_t sys)
    Enable a clock controlled by the device.
    On success, the clock is enabled and ready when this function returns. This function
    may sleep, and thus can only be called from thread context.
    Use clock_control_async_on() for non-blocking operation.
    Parameters
    • dev – Device structure whose driver controls the clock.
    • sys – Opaque data representing the clock.
    Returns
    0 on success, negative errno on failure.

static inline int clock_control_off(const struct device *dev, clock_control_subsys_t sys)
    Disable a clock controlled by the device.
    This function is non-blocking and can be called from any context. On success, the clock
    is disabled when this function returns.
    Parameters
    • dev – Device structure whose driver controls the clock
    • sys – Opaque data representing the clock
    Returns
    0 on success, negative errno on failure.
static inline int clock_control_async_on(const struct device *dev, clock_control_subsys_t sys, clock_control_cb_t cb, void *user_data)

Request clock to start with notification when clock has been started.
Function is non-blocking and can be called from any context. User callback is called when clock is started.

**Parameters**
- dev – Device.
- sys – A pointer to an opaque data representing the sub-system.
- cb – Callback.
- user_data – User context passed to the callback.

**Return values**
- 0 – if start is successfully initiated.
- -EALREADY – if clock was already started and is starting or running.
- -ENOTSUP – If the requested mode of operation is not supported.
- -ENOSYS – if the interface is not implemented.
- other – negative errno on vendor specific error.

static inline enum clock_control_status clock_control_get_status(const struct device *dev, clock_control_subsys_t sys)

Get clock status.

**Parameters**
- dev – Device.
- sys – A pointer to an opaque data representing the sub-system.

**Returns**
Status.

static inline int clock_control_get_rate(const struct device *dev, clock_control_subsys_t sys, uint32_t *rate)

Obtain the clock rate of given sub-system.

**Parameters**
- dev – Pointer to the device structure for the clock controller driver instance
- sys – A pointer to an opaque data representing the sub-system
- rate – [out] Subsystem clock rate

**Return values**
- 0 – on successful rate reading.
- -EAGAIN – if rate cannot be read. Some drivers do not support returning the rate when the clock is off.
- -ENOTSUP – if reading the clock rate is not supported for the given sub-system.
- -ENOSYS – if the interface is not implemented.
static inline int clock_control_set_rate(const struct device *dev, clock_control_subsys_t sys, clock_control_subsys_rate_t rate)

Set the rate of the clock controlled by the device.

On success, the new clock rate is set and ready when this function returns. This function may sleep, and thus can only be called from thread context.

Parameters

- dev – Device structure whose driver controls the clock.
- sys – Opaque data representing the clock.
- rate – Opaque data representing the clock rate to be used.

Return values

- -EALREADY – if clock was already in the given rate.
- -ENOTSUP – If the requested mode of operation is not supported.
- -ENOSYS – if the interface is not implemented.
- other – negative errno on vendor specific error.

static inline int clock_control_configure(const struct device *dev, clock_control_subsys_t sys, void *data)

Configure a source clock.

This function is non-blocking and can be called from any context. On success, the selected clock is configured as per caller's request.

It is caller's responsibility to ensure that subsequent calls to the API provide the right information to allows clock_control driver to perform the right action (such as using the right clock source on clock_control_get_rate call).

data is implementation specific and could be used to convey supplementary information required for expected clock configuration.

Parameters

- dev – Device structure whose driver controls the clock
- sys – Opaque data representing the clock
- data – Opaque data providing additional input for clock configuration

Return values

- 0 – On success
- -ENOSYS – If the device driver does not implement this call
- -errno – Other negative errno on failure.

struct clock_control_driver_api

#include <clock_control.h>

7.6.8 Controller Area Network (CAN)

CAN Controller
Overview

Controller Area Network is a two-wire serial bus specified by the Bosch CAN Specification, Bosch CAN with Flexible Data-Rate specification and the ISO 11898-1:2003 standard. CAN is mostly known for its application in the automotive domain. However, it is also used in home and industrial automation and other products.

Warning: CAN controllers can only initialize when the bus is in the idle (recessive) state for at least 11 recessive bits. Therefore you have to make sure that CAN RX is high, at least for a short time. This is also necessary for loopback mode.

The bit-timing as defined in ISO 11898-1:2003 looks as following:

A single bit is split into four segments.

- Sync_Seg: The nodes synchronize at the edge of the Sync_Seg. It is always one time quantum in length.
- Prop_Seg: The signal propagation delay of the bus and other delays of the transceiver and node.
- Phase_Seg1 and Phase_Seg2: Define the sampling point. The bit is sampled at the end of Phase_Seg1.

The bit-rate is calculated from the time of a time quantum and the values defined above. A bit has the length of Sync_Seg plus Prop_Seg plus Phase_Seg1 plus Phase_Seg2 multiplied by the time of single time quantum. The bit-rate is the inverse of the length of a single bit.

A bit is sampled at the sampling point. The sample point is between Phase_Seg1 and PhaseSeg2 and therefore is a parameter that the user needs to choose. The CiA recommends setting the sample point to 87.5% of the bit.

The resynchronization jump width (SJW) defines the amount of time quantum the sample point can be moved. The sample point is moved when resynchronization is needed.

The timing parameters (SJW, bitrate and sampling point, or bitrate, Prop_Seg, Phase_Seg1 and Phase_Seg2) are initially set from the device-tree and can be changed at run-time from the timing-API.

CAN uses so-called identifiers to identify the frame instead of addresses to identify a node. This identifier can either have 11-bit width (Standard or Basic Frame) or 29-bit in case of an Extended Frame. The Zephyr CAN API supports both Standard and Extended identifiers concurrently. A CAN frame starts with a dominant Start Of Frame bit. After that, the identifiers follow. This phase is called the arbitration phase. During the arbitration phase, write collisions are allowed. They resolve by the fact that dominant bits override recessive bits. Nodes monitor the bus and notice when their transmission is being overridden and in case, abort their transmission. This effectively gives lower number identifiers priority over higher number identifiers.
Filters are used to whitelist identifiers that are of interest for the specific node. An identifier that doesn’t match any filter is ignored. Filters can either match exactly or a specified part of the identifier. This method is called masking. As an example, a mask with 11 bits set for standard or 29 bits set for extended identifiers must match perfectly. Bits that are set to zero in the mask are ignored when matching an identifier. Most CAN controllers implement a limited number of filters in hardware. The number of filters is also limited in Kconfig to save memory.

Errors may occur during transmission. In case a node detects an erroneous frame, it partially overrides the current frame with an error-frame. Error-frames can either be error passive or error active, depending on the state of the controller. In case the controller is in error active state, it sends six consecutive dominant bits, which is a violation of the stuffing rule that all nodes can detect. The sender may resend the frame right after.

An initialized node can be in one of the following states:

- Error-active
- Error-passive
- Bus-off

After initialization, the node is in the error-active state. In this state, the node is allowed to send active error frames, ACK, and overload frames. Every node has a receive- and transmit-error counter. If either the receive- or the transmit-error counter exceeds 127, the node changes to error-passive state. In this state, the node is not allowed to send error-active frames anymore. If the transmit-error counter increases further to 255, the node changes to the bus-off state. In this state, the node is not allowed to send any dominant bits to the bus. Nodes in the bus-off state may recover after receiving 128 occurrences of 11 concurrent recessive bits.

You can read more about CAN bus in this CAN Wikipedia article.

Zephyr supports following CAN features:
- Standard and Extended Identifiers
- Filters with Masking
- Loopback and Silent mode
- Remote Request

**Sending** The following code snippets show how to send data.

This basic sample sends a CAN frame with standard identifier 0x123 and eight bytes of data. When passing NULL as the callback, as shown in this example, the send function blocks until the frame is sent and acknowledged by at least one other node or an error occurred. The timeout only takes effect on acquiring a mailbox. When a transmitting mailbox is assigned, sending cannot be canceled.

```c
struct can_frame frame = {
    .flags = 0,
    .id = 0x123,
    .dlc = 8,
    .data = {1,2,3,4,5,6,7,8}
};
const struct device *const can_dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_canbus));
int ret;
ret = can_send(can_dev, &frame, K_MSEC(100), NULL, NULL);
if (ret != 0) {
    LOG_ERR("Sending failed [%d]", ret);
}
```

This example shows how to send a frame with extended identifier 0x1234567 and two bytes of data. The provided callback is called when the message is sent, or an error occurred. Passing
void tx_callback(const struct device *dev, int error, void *user_data)
{
    char *sender = (char *)user_data;
    if (error != 0) {
        LOG_ERR("Sending failed [%d]\Sender: %s\n", error, sender);
    }
}

int send_function(const struct device *can_dev)
{
    struct can_frame frame = {
        .flags = CAN_FRAME_IDE,
        .id = 0x1234567,
        .dlc = 2
    };
    frame.data[0] = 1;
    frame.data[1] = 2;
    return can_send(can_dev, &frame, K_FOREVER, tx_callback, "Sender 1");
}

Receiving Frames are only received when they match a filter. The following code snippets show how to receive frames by adding filters.

Here we have an example for a receiving callback as used for can_add_rx_filter(). The user data argument is passed when the filter is added.

void rx_callback_function(const struct device *dev, struct can_frame *frame, void *user_data)
{
    ... do something with the frame ...
}

The following snippet shows how to add a filter with a callback function. It is the most efficient but also the most critical way to receive messages. The callback function is called from an interrupt context, which means that the callback function should be as short as possible and must not block. Adding callback functions is not allowed from userspace context.

The filter for this example is configured to match the identifier 0x123 exactly.

const struct can_filter my_filter = {
    .flags = 0U,
    .id = 0x123,
    .mask = CAN_STD_ID_MASK
};
int filter_id;
const struct device *const can_dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_canbus));
filter_id = can_add_rx_filter(can_dev, rx_callback_function, callback_arg, &my_filter);
if (filter_id < 0) {
    LOG_ERR("Unable to add rx filter [%d]", filter_id);
}

Here an example for can_add_rx_filter_msgq() is shown. With this function, it is possible to receive frames synchronously. This function can be called from userspace context. The size of the message queue should be as big as the expected backlog.
The filter for this example is configured to match the extended identifier 0x1234567 exactly.

```c
const struct can_filter my_filter = {
    .flags = CAN_FILTER_IDE,
    .id = 0x1234567,
    .mask = CAN_EXT_ID_MASK
};

CAN_MSGQ_DEFINE(my_can_msgq, 2);
struct can_frame rx_frame;
int filter_id;
const struct device *const can_dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_canbus));

filter_id = can_add_rx_filter_msgq(can_dev, &my_can_msgq, &my_filter);
if (filter_id < 0) {
    LOG_ERR("Unable to add rx msgq [%d]", filter_id);
    return;
}

while (true) {
    k_msgq_get(&my_can_msgq, &rx_frame, K_FOREVER);
    ... do something with the frame ...
}

can_remove_rx_filter() removes the given filter.

can_remove_rx_filter(can_dev, filter_id);
```

**Setting the bitrate**  The bitrate and sampling point is initially set at runtime. To change it from the application, one can use the `can_set_timing()` API. The `can_calc_timing()` function can calculate timing from a bitrate and sampling point in permille. The following example sets the bitrate to 250k baud with the sampling point at 87.5%.

```c
struct can_timing timing;
const struct device *const can_dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_canbus));

int ret;

ret = can_calc_timing(can_dev, &timing, 250000, 875);
if (ret > 0) {
    LOG_INF("Sample-Point error: %d", ret);
}

if (ret < 0) {
    LOG_ERR("Failed to calc a valid timing");
    return;
}

ret = can_stop(can_dev);
if (ret != 0) {
    LOG_ERR("Failed to stop CAN controller");
}

ret = can_set_timing(can_dev, &timing);
if (ret != 0) {
    LOG_ERR("Failed to set timing");
}

ret = can_start(can_dev);
if (ret != 0) {
    LOG_ERR("Failed to start CAN controller");
}
```

---

**7.6. Peripherals**
A similar API exists for calculating and setting the timing for the data phase for CAN FD capable controllers. See `can_set_timing_data()` and `can_calc_timing_data()`.

**SocketCAN** Zephyr additionally supports SocketCAN, a BSD socket implementation of the Zephyr CAN API. SocketCAN brings the convenience of the well-known BSD Socket API to Controller Area Networks. It is compatible with the Linux SocketCAN implementation, where many other high-level CAN projects build on top. Note that frames are routed to the network stack instead of passed directly, which adds some computation and memory overhead.

**Samples** We have two ready-to-build samples demonstrating use of the Zephyr CAN API: Zephyr CAN counter sample and SocketCAN sample.

---

### CAN Controller API Reference

#### Related code samples

**Controller Area Network (CAN) babbling node**
Simulate a babbling CAN node.

**Controller Area Network (CAN) counter**
Send and receive CAN messages.

---

```c
group can_interface

 CAN Interface.

---

#### CAN controller configuration

```c
int can_get_core_clock(const struct device *dev, uint32_t *rate)

Get the CAN core clock rate.

  Returns the CAN core clock rate. One time quantum is 1/(core clock rate).

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `rate` – **[out]** CAN core clock rate in Hz.

**Returns**

0 on success, or a negative error code on error

```c
int can_get_max_bitrate(const struct device *dev, uint32_t *max_bitrate)

Get the maximum supported bitrate.

Get the maximum supported bitrate for the CAN controller/transceiver combination.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `max_bitrate` – **[out]** Maximum supported bitrate in bits/s

**Return values**

- 0 – If successful.
- -EIO – General input/output error.
- -ENOSYS – If this function is not implemented by the driver.
const struct can_timing *can_get_timing_min(const struct device *dev)
Get the minimum supported timing parameter values.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.

**Returns**

Pointer to the minimum supported timing parameter values.

const struct can_timing *can_get_timing_max(const struct device *dev)
Get the maximum supported timing parameter values.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.

**Returns**

Pointer to the maximum supported timing parameter values.

int can_calc_timing(const struct device *dev, struct can_timing *res, uint32_t bitrate, uint16_t sample_pnt)
Calculate timing parameters from bitrate and sample point.

Calculate the timing parameters from a given bitrate in bits/s and the sampling point in permill (1/1000) of the entire bit time. The bitrate must always match perfectly. If no result can be reached for the given parameters, -EINVAL is returned.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `res` – [out] Result is written into the `can_timing` struct provided.
- `bitrate` – Target bitrate in bits/s.
- `sample_pnt` – Sampling point in permill of the entire bit time.

**Return values**

- 0 – or positive sample point error on success.
- -EINVAL – if the requested bitrate or sample point is out of range.
- -ENOTSUP – if the requested bitrate is not supported.
- -EIO – if `can_get_core_clock()` is not available.

const struct can_timing *can_get_timing_data_min(const struct device *dev)
Get the minimum supported timing parameter values for the data phase.

Same as `can_get_timing_min()` but for the minimum values for the data phase.

**Note:** CONFIG_CAN_FD_MODE must be selected for this function to be available.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.

**Returns**

Pointer to the minimum supported timing parameter values, or NULL if CAN FD support is not implemented by the driver.
const struct can_timing *can_get_timing_data_max(const struct device *dev)
Get the maximum supported timing parameter values for the data phase.
Same as can_get_timing_max() but for the maximum values for the data phase.

**Note:** CONFIG_CAN_FD_MODE must be selected for this function to be available.

**Parameters**
- dev – Pointer to the device structure for the driver instance.

**Returns**
Pointer to the maximum supported timing parameter values, or NULL if CAN FD support is not implemented by the driver.

int can_calc_timing_data(const struct device *dev, struct can_timing *res, uint32_t bitrate, uint16_t sample_pnt)
Calculate timing parameters for the data phase.
Same as can_calc_timing() but with the maximum and minimum values from the data phase.

**Note:** CONFIG_CAN_FD_MODE must be selected for this function to be available.

**Parameters**
- dev – Pointer to the device structure for the driver instance.
- res – [out] Result is written into the can_timing struct provided.
- bitrate – Target bitrate for the data phase in bits/s
- sample_pnt – Sampling point for the data phase in permille of the entire bit time.

**Return values**
- 0 – or positive sample point error on success.
- -EINVAL – if the requested bitrate or sample point is out of range.
- -ENOTSUP – if the requested bitrate is not supported.
- -EIO – if can_get_core_clock() is not available.

int can_set_timing_data(const struct device *dev, const struct can_timing *timing_data)
Configure the bus timing for the data phase of a CAN FD controller.

**See also:**
can_set_timing()
### Return values

- **0** – If successful.
- **-EBUSY** – if the CAN controller is not in stopped state.
- **-EINVAL** – if the requested bitrate is out of range.
- **-ENOTSUP** – if the requested bitrate not supported by the CAN controller/transceiver combination.
- **-ERANGE** – if the resulting sample point is off by more than +/- 5%.
- **-EIO** – General input/output error, failed to set bitrate.

```c
int can_set_bitrate_data(const struct device *dev, uint32_t bitrate_data)
```

Set the bitrate for the data phase of the CAN FD controller.

CAN in Automation (CiA) 301 v4.2.0 recommends a sample point location of 87.5% percent for all bitrates. However, some CAN controllers have difficulties meeting this for higher bitrates.

This function defaults to using a sample point of 75.0% for bitrates over 800 kbit/s, 80.0% for bitrates over 500 kbit/s, and 87.5% for all other bitrates. This is in line with the sample point locations used by the Linux kernel.

### See also:

`can_set_bitrate()`

**Note:** `CONFIG_CAN_FD_MODE` must be selected for this function to be available.

### Parameters

- **dev** – Pointer to the device structure for the driver instance.
- **bitrate_data** – Desired data phase bitrate.

### Return values

- **0** – If successful.
- **-EBUSY** – if the CAN controller is not in stopped state.
- **-EINVAL** – if the requested bitrate is out of range.
- **-ENOTSUP** – if the timing parameters are not supported by the driver.
- **-ENOSYS** – if CAN FD support is not implemented by the driver.

```c
int can_calc_prescaler(const struct device *dev, struct can_timing *timing, uint32_t bitrate)
```

Fill in the prescaler value for a given bitrate and timing.

Fill the prescaler value in the timing struct. The sjw, prop_seg, phase_seg1 and phase_seg2 must be given.

The returned bitrate error is remainder of the division of the clock rate by the bitrate times the timing segments.

### Parameters

- **dev** – Pointer to the device structure for the driver instance.
- **timing** – Result is written into the `can_timing` struct provided.
- **bitrate** – Target bitrate.
Return values

- 0 – or positive bitrate error.
- Negative – error code on error.

`int can_set_timing(const struct device *dev, const struct can_timing *timing)`

Configure the bus timing of a CAN controller.

See also:

`can_set_timing_data()`

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `timing` – Bus timings.

Return values

- 0 – If successful.
- -EBUSY – if the CAN controller is not in stopped state.
- -ENOTSUP – if the timing parameters are not supported by the driver.
- -EIO – General input/output error, failed to configure device.

`int can_get_capabilities(const struct device *dev, can_mode_t *cap)`

Get the supported modes of the CAN controller.

The returned capabilities may not necessarily be supported at the same time (e.g. some CAN controllers support both CAN_MODE_LOOPBACK and CAN_MODE_LISTENONLY, but not at the same time).

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `cap` – [out] Supported capabilities.

Return values

- 0 – If successful.
- -EIO – General input/output error, failed to get capabilities.

`const struct device *can_get_transceiver(const struct device *dev)`

Get the CAN transceiver associated with the CAN controller.

Get a pointer to the device structure for the CAN transceiver associated with the CAN controller.

Parameters

- `dev` – Pointer to the device structure for the driver instance.

Returns

Pointer to the device structure for the associated CAN transceiver driver instance, or NULL if no transceiver is associated.

`int can_start(const struct device *dev)`

Start the CAN controller.

Bring the CAN controller out of CAN_STATE_STOPPED. This will reset the RX/TX error counters, enable the CAN controller to participate in CAN communication, and enable the CAN tranceiver, if supported.
Starting the CAN controller resets all the CAN controller statistics.

See also:
`can_stop()`

See also:
`can_transceiver_enable()`

Parameters
- `dev` – Pointer to the device structure for the driver instance.

Return values
- 0 – if successful.
- `EALREADY` – if the device is already started.
- `EIO` – General input/output error; failed to start device.

```c
int can_stop(const struct device *dev)
```
Stop the CAN controller.
Bring the CAN controller into `CAN_STATE_STOPPED`. This will disallow the CAN controller from participating in CAN communication, abort any pending CAN frame transmissions, and disable the CAN transceiver, if supported.

See also:
`can_start()`

See also:
`can_transceiver_disable()`

Parameters
- `dev` – Pointer to the device structure for the driver instance.

Return values
- 0 – if successful.
- `EALREADY` – if the device is already stopped.
- `EIO` – General input/output error; failed to stop device.

```c
int can_stop(const struct device *dev)
```

Set the CAN controller to the given operation mode.

Parameters
- `dev` – Pointer to the device structure for the driver instance.
- `mode` – Operation mode.

Return values
- 0 – If successful.
- `EBUSY` – if the CAN controller is not in stopped state.
- `EIO` – General input/output error; failed to configure device.
**can_mode_t** `can_get_mode(const struct device *dev)`

Get the operation mode of the CAN controller.

**Parameters**

- *dev* – Pointer to the device structure for the driver instance.

**Returns**

Current operation mode.

**int** `can_set_bitrate(const struct device *dev, uint32_t bitrate)`

Set the bitrate of the CAN controller.

CAN in Automation (CiA) 301 v4.2.0 recommends a sample point location of 87.5% percent for all bitrates. However, some CAN controllers have difficulties meeting this for higher bitrates.

This function defaults to using a sample point of 75.0% for bitrates over 800 kbit/s, 80.0% for bitrates over 500 kbit/s, and 87.5% for all other bitrates. This is in line with the sample point locations used by the Linux kernel.

**See also:**

`can_set_bitrate_data()`

**Parameters**

- *dev* – Pointer to the device structure for the driver instance.
- *bitrate* – Desired arbitration phase bitrate.

**Return values**

- 0 – If successful.
- -EBUSY – if the CAN controller is not in stopped state.
- -EINVAL – if the requested bitrate is out of range.
- -ENOTSUP – if the requested bitrate not supported by the CAN controller/transceiver combination.
- -ERANGE – if the resulting sample point is off by more than +/- 5%.
- -EIO – General input/output error, failed to set bitrate.

**Transmitting CAN frames**

**int** `can_send(const struct device *dev, const struct can_frame *frame, k_timeout_t timeout, can_tx_callback_t callback, void *user_data)`

Queue a CAN frame for transmission on the CAN bus.

Queue a CAN frame for transmission on the CAN bus with optional timeout and completion callback function.

Queued CAN frames are transmitted in order according to their priority:

- The lower the CAN-ID, the higher the priority.
- Data frames have higher priority than Remote Transmission Request (RTR) frames with identical CAN-IDs.
- Frames with standard (11-bit) identifiers have higher priority than frames with extended (29-bit) identifiers with identical base IDs (the higher 11 bits of the extended identifier).
• Transmission order for queued frames with the same priority is hardware dependent.

By default, the CAN controller will automatically retry transmission in case of lost bus arbitration or missing acknowledge. Some CAN controllers support disabling automatic retransmissions via CAN_MODE_ONE_SHOT.

**Note:** If transmitting segmented messages spanning multiple CAN frames with identical CAN-IDs, the sender must ensure to only queue one frame at a time if FIFO order is required.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
- **frame** – CAN frame to transmit.
- **timeout** – Timeout waiting for an empty TX mailbox or K_FOREVER.
- **callback** – Optional callback for when the frame was sent or a transmission error occurred. If NULL, this function is blocking until frame is sent. The callback must be NULL if called from user mode.
- **user_data** – User data to pass to callback function.

**Return values**

- 0 – if successful.
- -EINVAL – if an invalid parameter was passed to the function.
- -ENOTSUP – if an unsupported parameter was passed to the function.
- -ENETDOWN – if the CAN controller is in stopped state.
- -ENETUNREACH – if the CAN controller is in bus-off state.
- -EBUSY – if CAN bus arbitration was lost (only applicable if automatic retransmissions are disabled).
- -EIO – if a general transmit error occurred (e.g. missing ACK if automatic retransmissions are disabled).
- -EAGAIN – on timeout.

**Receiving CAN frames**

```
static inline int can_add_rx_filter(const struct device *dev, can_rx_callback_t callback, void *user_data, const struct can_filter *filter)
```

Add a callback function for a given CAN filter.

Add a callback to CAN identifiers specified by a filter. When a received CAN frame matching the filter is received by the CAN controller, the callback function is called in interrupt context.

If a received frame matches more than one filter (i.e., the filter IDs/masks or flags overlap), the priority of the match is hardware dependent.

The same callback function can be used for multiple filters.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
• **callback** – This function is called by the CAN controller driver whenever a frame matching the filter is received.

• **user_data** – User data to pass to callback function.

• **filter** – Pointer to a `can_filter` structure defining the filter.

### Return values

• **filter_id** – on success.

• **-ENOSPC** – if there are no free filters.

• **-EINVAL** – if the requested filter type is invalid.

• **-ENOTSUP** – if the requested filter type is not supported.

```c
int can_add_rx_filter_msgq(const struct device *dev, struct k_msgq *msgq, const struct can_filter *filter)
```

Simple wrapper function for adding a message queue for a given filter.

Wrapper function for `can_add_rx_filter()` which puts received CAN frames matching the filter in a message queue instead of calling a callback.

If a received frame matches more than one filter (i.e., the filter IDs/masks or flags overlap), the priority of the match is hardware dependent.

The same message queue can be used for multiple filters.

**Note:** The message queue must be initialized before calling this function and the caller must have appropriate permissions on it.

---

**Warning:** Message queue overruns are silently ignored and overrun frames discarded. Custom error handling can be implemented by using `can_add_rx_filter()` and `k_msgq_put()` directly.

### Parameters

• **dev** – Pointer to the device structure for the driver instance.

• **msgq** – Pointer to the already initialized `k_msgq` struct.

• **filter** – Pointer to a `can_filter` structure defining the filter.

### Return values

• **filter_id** – on success.

• **-ENOSPC** – if there are no free filters.

• **-ENOTSUP** – if the requested filter type is not supported.

```c
void can_remove_rx_filter(const struct device *dev, int filter_id)
```

Remove a CAN RX filter.

This routine removes a CAN RX filter based on the filter ID returned by `can_add_rx_filter()` or `can_add_rx_filter_msgq()`.

### Parameters

• **dev** – Pointer to the device structure for the driver instance.

• **filter_id** – Filter ID
int can_get_max_filters(const struct device *dev, bool ide)
Get maximum number of RX filters.
Get the maximum number of concurrent RX filters for the CAN controller.

Parameters
- dev – Pointer to the device structure for the driver instance.
- ide – Get the maximum standard (11-bit) CAN ID filters if false, or extended (29-bit) CAN ID filters if true.

Return values
- Positive – number of maximum concurrent filters.
- -EIO – General input/output error.
- -ENOSYS – If this function is not implemented by the driver.

CAN_MSGQ_DEFINE(name, max_frames)
Statically define and initialize a CAN RX message queue.
The message queue's ring buffer contains space for max_frames CAN frames.

See also:
can_add_rx_filter_msgq()

Parameters
- name – Name of the message queue.
- max_frames – Maximum number of CAN frames that can be queued.

CAN bus error reporting and handling

int can_get_state(const struct device *dev, enum can_state *state, struct can_bus_err_cnt *err_cnt)
Get current CAN controller state.
Returns the current state and optionally the error counter values of the CAN controller.

Parameters
- dev – Pointer to the device structure for the driver instance.
- state – [out] Pointer to the state destination enum or NULL.
- err_cnt – [out] Pointer to the err_cnt destination structure or NULL.

Return values
- 0 – If successful.
- -EIO – General input/output error, failed to get state.

int can_recover(const struct device *dev, k_timeout_t timeout)
Recover from bus-off state.
Recover the CAN controller from bus-off state to error-active state.

Note: CONFIG_CAN_AUTO_BUS_OFF_RECOVERY must be deselected for this function to be available.
Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `timeout` – Timeout for waiting for the recovery or K_FOREVER.

Return values

- 0 – on success.
- -ENETDOWN – if the CAN controller is in stopped state.
- -EAGAIN – on timeout.

```c
static inline void can_set_state_change_callback(const struct device *dev, can_state_change_callback_t callback, void *user_data)
```

Set a callback for CAN controller state change events.

Set the callback for CAN controller state change events. The callback function will be called in interrupt context.

Only one callback can be registered per controller. Calling this function again over-
rides any previously registered callback.

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `callback` – Callback function.
- `user_data` – User data to pass to callback function.

CAN statistics

```c
uint32_t can_stats_get_bit_errors(const struct device *dev)
```

Get the bit error counter for a CAN device.

The bit error counter is incremented when the CAN controller is unable to transmit either a dominant or a recessive bit.

**Note:** CONFIG_CAN_STATS must be selected for this function to be available.

```c
uint32_t can_stats_get_bit0_errors(const struct device *dev)
```

Get the bit0 error counter for a CAN device.

The bit0 error counter is incremented when the CAN controller is unable to transmit a dominant bit.

See also:

`can_stats_get_bit_errors()`

**Note:** CONFIG_CAN_STATS must be selected for this function to be available.
Parameters

• dev – Pointer to the device structure for the driver instance.

Returns

bit0 error counter

uint32_t can_stats_get_bit1_errors(const struct device *dev)
Get the bit1 error counter for a CAN device.

The bit1 error counter is incremented when the CAN controller is unable to transmit
a recessive bit.

See also:

can_stats_get_bit_errors()

Note: CONFIG_CAN_STATS must be selected for this function to be available.

Parameters

• dev – Pointer to the device structure for the driver instance.

Returns

bit1 error counter

uint32_t can_stats_get_stuff_errors(const struct device *dev)
Get the stuffing error counter for a CAN device.

The stuffing error counter is incremented when the CAN controller detects a bit stuffing
error.

Note: CONFIG_CAN_STATS must be selected for this function to be available.

Parameters

• dev – Pointer to the device structure for the driver instance.

Returns

stufing error counter

uint32_t can_stats_get_crc_errors(const struct device *dev)
Get the CRC error counter for a CAN device.

The CRC error counter is incremented when the CAN controller detects a frame with
an invalid CRC.

Note: CONFIG_CAN_STATS must be selected for this function to be available.

Parameters

• dev – Pointer to the device structure for the driver instance.

Returns

CRC error counter
```c
uint32_t can_stats_get_form_errors(const struct device *dev)
Get the form error counter for a CAN device.
The form error counter is incremented when the CAN controller detects a fixed-form bit field containing illegal bits.

**Note:** CONFIG_CAN_STATS must be selected for this function to be available.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.

**Returns**
- Form error counter
```
```c
uint32_t can_stats_get_ack_errors(const struct device *dev)
Get the acknowledge error counter for a CAN device.
The acknowledge error counter is incremented when the CAN controller does not monitor a dominant bit in the ACK slot.

**Note:** CONFIG_CAN_STATS must be selected for this function to be available.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.

**Returns**
- Acknowledge error counter
```
```c
uint32_t can_stats_get_rx_overruns(const struct device *dev)
Get the RX overrun counter for a CAN device.
The RX overrun counter is incremented when the CAN controller receives a CAN frame matching an installed filter but lacks the capacity to store it (either due to an already full RX mailbox or a full RX FIFO).

**Note:** CONFIG_CAN_STATS must be selected for this function to be available.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.

**Returns**
- RX overrun counter
```

### CAN utility functions

```c
static inline uint8_t can_dlc_to_bytes(uint8_t dlc)
Convert from Data Length Code (DLC) to the number of data bytes.

**Parameters**
- `dlc` – Data Length Code (DLC).

**Return values**
- Number – of bytes.
```
static inline uint8_t can_bytes_to_dlc(uint8_t num_bytes)
    Convert from number of bytes to Data Length Code (DLC)

Parameters
• num_bytes – Number of bytes.

Return values
Data – Length Code (DLC).

static inline bool can_frame_matches_filter(const struct can_frame *frame,
                                             const struct can_filter *filter)
    Check if a CAN frame matches a CAN filter.

Parameters
• frame – CAN frame.
• filter – CAN filter.

Returns
true if the CAN frame matches the CAN filter, false otherwise

CAN frame definitions

CAN_STD_ID_MASK
    Bit mask for a standard (11-bit) CAN identifier.

CAN_MAX_STD_ID
    Maximum value for a standard (11-bit) CAN identifier.

CAN_EXT_ID_MASK
    Bit mask for an extended (29-bit) CAN identifier.

CAN_MAX_EXT_ID
    Maximum value for an extended (29-bit) CAN identifier.

CAN_MAX_DLC
    Maximum data length code for CAN 2.0A/2.0B.

CANFD_MAX_DLC
    Maximum data length code for CAN FD.

CAN controller mode flags

CAN_MODE_NORMAL
    Normal mode.

CAN_MODE_LOOPBACK
    Controller is in loopback mode (receives own frames).
CAN_MODE_LISTENONLY
Controller is not allowed to send dominant bits.

CAN_MODE_FD
Controller allows transmitting/receiving CAN FD frames.

CAN_MODE_ONE_SHOT
Controller does not retransmit in case of lost arbitration or missing ACK.

CAN_MODE_3_SAMPLES
Controller uses triple sampling mode.

CAN frame flags

CAN_FRAME_IDE
Frame uses extended (29-bit) CAN ID.

CAN_FRAME_RTR
Frame is a Remote Transmission Request (RTR)

CAN_FRAME_FDF
Frame uses CAN FD format (FDF)

CAN_FRAME_BRS
Frame uses CAN FD Baud Rate Switch (BRS).
Only valid in combination with CAN_FRAME_FDF.

CAN_FRAME_ESI
CAN FD Error State Indicator (ESI).
Indicates that the transmitting node is in error-passive state. Only valid in combination with CAN_FRAME_FDF.

CAN filter flags

CAN_FILTER_IDE
Filter matches frames with extended (29-bit) CAN IDs.

Defines

CAN_STATS_BIT_ERROR_INC(dev_)
Increment the bit error counter for a CAN device.
The bit error counter is incremented when the CAN controller is unable to transmit either a dominant or a recessive bit.
See also:

\texttt{CAN\_STATS\_BIT0\_ERROR\_INC()}

See also:

\texttt{CAN\_STATS\_BIT1\_ERROR\_INC()}

\textbf{Note:} This error counter should only be incremented if the CAN controller is unable to distinguish between failure to transmit a dominant versus failure to transmit a recessive bit. If the CAN controller supports distinguishing between the two, the bit0 or bit1 error counter shall be incremented instead.

\textbf{Parameters}

- dev_ – Pointer to the device structure for the driver instance.

\texttt{CAN\_STATS\_BIT0\_ERROR\_INC(dev_)}

Increment the bit0 error counter for a CAN device.

The bit0 error counter is incremented when the CAN controller is unable to transmit a dominant bit.

Incrementing this counter will automatically increment the bit error counter.

See also:

\texttt{CAN\_STATS\_BIT\_ERROR\_INC()}

\textbf{Parameters}

- dev_ – Pointer to the device structure for the driver instance.

\texttt{CAN\_STATS\_BIT1\_ERROR\_INC(dev_)}

Increment the bit1 (recessive) error counter for a CAN device.

The bit1 error counter is incremented when the CAN controller is unable to transmit a recessive bit.

Incrementing this counter will automatically increment the bit error counter.

See also:

\texttt{CAN\_STATS\_BIT\_ERROR\_INC()}

\textbf{Parameters}

- dev_ – Pointer to the device structure for the driver instance.

\texttt{CAN\_STATS\_STUFF\_ERROR\_INC(dev_)}

Increment the stuffing error counter for a CAN device.

The stuffing error counter is incremented when the CAN controller detects a bit stuffing error.

\textbf{Parameters}

- dev_ – Pointer to the device structure for the driver instance.

\texttt{CAN\_STATS\_CRC\_ERROR\_INC(dev_)}

Increment the CRC error counter for a CAN device.

The CRC error counter is incremented when the CAN controller detects a frame with an invalid CRC.
Parameters

• dev_ – Pointer to the device structure for the driver instance.

CAN_STATS_FORM_ERROR_INC(dev_)
Increment the form error counter for a CAN device.
The form error counter is incremented when the CAN controller detects a fixed-form bit field containing illegal bits.

Parameters

• dev_ – Pointer to the device structure for the driver instance.

CAN_STATS_ACK_ERROR_INC(dev_)
Increment the acknowledge error counter for a CAN device.
The acknowledge error counter is incremented when the CAN controller does not monitor a dominant bit in the ACK slot.

Parameters

• dev_ – Pointer to the device structure for the driver instance.

CAN_STATS_RX_OVERRUN_INC(dev_)
Increment the RX overrun counter for a CAN device.
The RX overrun counter is incremented when the CAN controller receives a CAN frame matching an installed filter but lacks the capacity to store it (either due to an already full RX mailbox or a full RX FIFO).

Parameters

• dev_ – Pointer to the device structure for the driver instance.

CAN_STATS_RESET(dev_)
Zero all statistics for a CAN device.
The driver is responsible for resetting the statistics before starting the CAN controller.

Parameters

• dev_ – Pointer to the device structure for the driver instance.

CAN_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, level, prio, api, ...)
Like DEVICE_DT_DEFINE() with CAN device specifics.
Defines a device which implements the CAN API. May generate a custom device state container struct and init_fn wrapper when needed depending on CONFIG_CAN_STATS.

Parameters

• node_id – The devicetree node identifier.
• init_fn – Name of the init function of the driver.
• pm – PM device resources reference (NULL if device does not use PM).
• data – Pointer to the device's private data.
• config – The address to the structure containing the configuration information for this instance of the driver.
• level – The initialization level. See SYS_INIT() for details.
• prio – Priority within the selected initialization level. See SYS_INIT() for details.
• api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
CAN_DEVICE_DT_INST_DEFINE(inst, ...)

Like CAN_DEVICE_DT_DEFINE() for an instance of a DT_DRV_COMPAT compatible.

**Parameters**

- **inst** – Instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to CAN DEVICE DT DEFINE().
- **...** – Other parameters as expected by CAN_DEVICE_DT_DEFINE().

**Typedefs**

typedef uint32_t can_mode_t

Provides a type to hold CAN controller configuration flags.
The lower 24 bits are reserved for common CAN controller mode flags. The upper 8 bits are reserved for CAN controller/driver specific flags.

**See also:**

CAN_MODE_FLAGS.

typedef void (*can_tx_callback_t)(const struct device *dev, int error, void *user_data)

Defines the application callback handler function signature.

**Param dev**

Pointer to the device structure for the driver instance.

**Param error**

Status of the performed send operation. See the list of return values for can_send() for value descriptions.

**Param user_data**

User data provided when the frame was sent.

typedef void (*can_rx_callback_t)(const struct device *dev, struct can_frame *frame, void *user_data)

Defines the application callback handler function signature for receiving.

**Param dev**

Pointer to the device structure for the driver instance.

**Param frame**

Received frame.

**Param user_data**

User data provided when the filter was added.

typedef void (*can_state_change_callback_t)(const struct device *dev, enum can_state state, struct can_bus_err_cnt err_cnt, void *user_data)

Defines the state change callback handler function signature.

**Param dev**

Pointer to the device structure for the driver instance.

**Param state**

State of the CAN controller.

**Param err_cnt**

CAN controller error counter values.
**Param user_data**
User data provided the callback was set.

**Enums**

```c
enum can_state
{
    CAN_STATE_ERROR_ACTIVE,
    CAN_STATE_ERROR_WARNING,
    CAN_STATE_ERROR_PASSIVE,
    CAN_STATE_BUS_OFF,
    CAN_STATE_STOPPED,
};
```

**Public Members**

```c
struct can_frame
{
    #include <can.h>  // CAN frame structure.

    uint32_t id
    {
        Standard (11-bit) or extended (29-bit) CAN identifier.
    }

    uint8_t dlc
    {
        Data Length Code (DLC) indicating data length in bytes.
    }

    uint8_t flags
    {
        Flags.
    }

    See also:
    
    CAN_FRAME_FLAGS.

    uint16_t timestamp
    {
        Captured value of the free-running timer in the CAN controller when this frame was received.
        The timer is incremented every bit time and captured at the start of frame bit (SOF).
    }
```
Note: CONFIG_CAN_RX_TIMESTAMP must be selected for this field to be available.

```c
uint8_t data[CAN_MAX_DLEN]
    Payload data accessed as unsigned 8 bit values.
```

```c
uint32_t data_32[DIV_ROUND_UP(CAN_MAX_DLEN, sizeof(uint32_t))]
    Payload data accessed as unsigned 32 bit values.
```

```c
union can_frame
    The frame payload data.
```

```c
struct can_filter
    #include <can.h> CAN filter structure.
```

**Public Members**

```c
uint32_t id
    CAN identifier to match.
```

```c
uint32_t mask
    CAN identifier matching mask.
    If a bit in this mask is 0, the value of the corresponding bit in the id field is ignored by the filter.
```

```c
uint8_t flags
    Flags.
```

See also:

- `CAN_FILTER_FLAGS`

```c
struct can_bus_err_cnt
    #include <can.h> CAN controller error counters.
```

**Public Members**

```c
uint8_t tx_err_cnt
    Value of the CAN controller transmit error counter.
```

```c
uint8_t rx_err_cnt
    Value of the CAN controller receive error counter.
```

```c
struct can_timing
    #include <can.h> CAN bus timing structure.
    This struct is used to pass bus timing values to the configuration and bitrate calculation functions.
```
The propagation segment represents the time of the signal propagation. Phase segment 1 and phase segment 2 define the sampling point. The `prop_seg` and `phase_seg1` values affect the sampling point in the same way and some controllers only have a register for the sum of those two. The sync segment always has a length of 1 time quantum (see below).

1 time quantum (tq) has the length of 1/(core_clock / prescaler). The bitrate is defined by the core clock divided by the prescaler and the sum of the segments:

\[
\text{br} = \frac{\text{core_clock}}{\text{prescaler}} \div (1 + \text{prop}_\text{seg} + \text{phase}_\text{seg1} + \text{phase}_\text{seg2})
\]

The Synchronization Jump Width (SJW) defines the amount of time quanta the sample point can be moved. The sample point is moved when resynchronization is needed.

**Public Members**

```c
#include <can.h>

struct can_device_state
#include <can.h> CAN specific device state which allows for CAN device class specific additions.

Public Members

struct device_state devstate
Common device state.

struct stats_can stats
CAN device statistics.
```
CAN Transceiver

Overview

A CAN transceiver is an external device that converts the logic level signals from the CAN controller to the bus-levels. The bus lines are called CAN High (CAN H) and CAN Low (CAN L). The transmit wire from the controller to the transceiver is called CAN TX, and the receive wire is called CAN RX. These wires use the logic levels whereas the bus-level is interpreted differentially between CAN H and CAN L. The bus can be either in the recessive (logical one) or dominant (logical zero) state. The recessive state is when both lines, CAN H and CAN L, are roughly at the same voltage level. This state is also the idle state. To write a dominant bit to the bus, open-drain transistors tie CAN H to Vdd and CAN L to ground. The first and last node use a 120-ohm resistor between CAN H and CAN L to terminate the bus. The dominant state always overrides the recessive state. This structure is called a wired-AND.

![CAN Transceiver Diagram](image)

Figure 1: CAN Transceiver, from Logic Levels to Bus Levels. ©Alexander Wachtel

CAN Transceiver API Reference

**group** can_transceiver

CAN Transceiver Driver APIs.

**Functions**

static inline int can_transceiver_enable(const struct device *dev, can_mode_t mode)

Enable CAN transceiver.

Enable the CAN transceiver.

**See also:**

can_start()

**Note:** The CAN transceiver is controlled by the CAN controller driver and should not normally be controlled by the application.
Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `mode` – Operation mode.

Return values

- 0 – If successful.
- -EIO – General input/output error, failed to enable device.

static inline int can_transceiver_disable(const struct device *dev)

Disable CAN transceiver.

Disable the CAN transceiver.

See also:

can_stop()

Note: The CAN transceiver is controlled by the CAN controller driver and should not normally be controlled by the application.

Parameters

- `dev` – Pointer to the device structure for the driver instance.

Return values

- 0 – If successful.
- -EIO – General input/output error, failed to disable device.

CAN Shell

- Overview
- Inspection
- Configuration
- Receiving
- Sending
- Bus Recovery

Overview  The CAN shell provides a can command with a set of subcommands for the `shell` module. It allows for testing and exploring the CAN Controller driver API through an interactive interface without having to write a dedicated application. The CAN shell can also be enabled in existing applications to aid in interactive debugging of CAN issues.

The CAN shell provides access to most CAN controller features, including inspection, configuration, sending and receiving of CAN frames, and bus recovery.

In order to enable the CAN shell, the following `Kconfig` options must be enabled:

- CONFIG_SHELL
- CONFIG_CAN
• CONFIG_CAN_SHELL

The following Kconfig options enable additional subcommands and features of the can command:

• CONFIG_CAN_FD_MODE enables CAN FD specific subcommands (e.g. for setting the timing for the CAN FD data phase).
• CONFIG_CAN_RX_TIMESTAMP enables printing of timestamps for received CAN frames.
• CONFIG_CAN_STATS enables printing of various statistics for the CAN controller in the can show subcommand. This depends on CONFIG_STATS being enabled as well.
• CONFIG_CAN_AUTO_BUS_OFF_RECOVERY enables the can recover subcommand when disabled.

For example, building the hello_world sample for the frdm_k64f with the CAN shell and CAN statistics enabled:

```bash
# From the root of the zephyr repository
west build -b frdm_k64f samples/hello_world -- -DCONFIG_SHELL=y -DCONFIG_CAN=y -DCONFIG_CAN_SHELL=y -DCONFIG_STATS=y -DCONFIG_CAN_STATS=y
```

See the shell documentation for general instructions on how to connect and interact with the shell. The CAN shell comes with built-in help (unless CONFIG_SHELL_HELP is disabled). The built-in help messages can be printed by passing -h or --help to the can command or any of its subcommands. All subcommands also support tab-completion of their arguments.

**Tip:** All of the CAN shell subcommands take the name of a CAN controller as their first argument, which also supports tab-completion. A list of all devices available can be obtained using the device list shell command when CONFIG_DEVICE_SHELL is enabled. The examples below all use the device name can@0.

**Inspection** The properties of a given CAN controller can be inspected using the can show subcommand as shown below. The properties include the core CAN clock rate, the maximum supported bitrate, the number of RX filters supported, capabilities, current mode, current state, error counters, timing limits, and more:

```
uart:~$ can show can@0  
   core clock: 144000000 Hz  
   max bitrate: 5000000 bps  
   max std filters: 15  
   max ext filters: 15  
   capabilities: normal loopback listen-only fd  
   mode: normal  
   state: stopped  
   rx errors: 0  
   tx errors: 0  
   timing: sjw 1..128, prop_seg 0..0, phase_seg1 2..256, phase_seg2 2..128, prescaler 1..512  
   timing data: sjw 1..16, prop_seg 0..0, phase_seg1 1..32, phase_seg2 1..16, prescaler 1..32  
   transceiver: passive/none  
   statistics:  
     bit errors: 0  
     bit0 errors: 0  
     bit1 errors: 0  
     stuff errors: 0  
     crc errors: 0  
     form errors: 0
```

(continues on next page)
Configuration  The CAN shell allows for configuring the CAN controller mode and timing, along with starting and stopping the processing of CAN frames.

Note: The CAN controller mode and timing can only be changed while the CAN controller is stopped, which is the initial setting upon boot-up. The initial CAN controller mode is set to normal and the initial timing is set according to the bus-speed, sample-point, bus-speed-data, and sample-point-data Devicetree properties.

Timing  The classic CAN bitrate/CAN FD arbitration phase bitrate can be configured using the can bitrate subcommand as shown below. The bitrate is specified in bits per second.

```
uart:~$ can bitrate can@0 125000
setting bitrate to 125000 bps
```

If CONFIG_CAN_FD_MODE is enabled, the data phase bitrate can be configured using the can dbitrate subcommand as shown below. The bitrate is specified in bits per second.

```
uart:~$ can dbitrate can@0 1000000
setting data bitrate to 1000000 bps
```

Both of these subcommands allow specifying an optional sample point in per mille and a (Re)Synchronization Jump Width (SJW) in Time Quanta as positional arguments. Refer to the interactive help of the subcommands for more details.

It is also possible to configure the raw bit timing using the can timing and can dtiming subcommands. Refer to the interactive help output for these subcommands for details on the required arguments.

Mode  The CAN shell allows for setting the mode of the CAN controller using the can mode subcommand. An example for enabling loopback mode is shown below.

```
uart:~$ can mode can@0 loopback
setting mode 0x00000001
```

The subcommand accepts multiple modes given on the same command line (e.g. can mode can@0 fd loopback for setting CAN FD and loopback mode). Vendor-specific modes can be specified in hexadecimal.

Starting and Stopping  After the timing and mode has been configured as needed, the CAN controller can be started using the can start subcommand as shown below. This will enable reception and transmission of CAN frames.

```
uart:~$ can start can@0
starting can@0
```

Prior to reconfiguring the timing or mode, the CAN controller needs to be stopped using the can stop subcommand as shown below:
Receiving  In order to receive CAN frames, one or more CAN RX filters need to be configured. CAN RX filters are added using the `can filter add` subcommand as shown below. The subcommand accepts a CAN ID in hexadecimal format along with an optional CAN ID mask, also in hexadecimal format, for setting which bits in the CAN ID are to be matched. Refer to the interactive help output for this subcommand for further details on the supported arguments.

The filter ID (0 in the example above) returned is to be used when removing the CAN RX filter. Received CAN frames matching the added filter(s) are printed to the shell. A few examples are shown below:

<table>
<thead>
<tr>
<th>Flags</th>
<th>ID</th>
<th>Size</th>
<th>Data bytes</th>
</tr>
</thead>
<tbody>
<tr>
<td>--</td>
<td>010</td>
<td>[8]</td>
<td>01 02 03 04 05 06 07 08</td>
</tr>
<tr>
<td>B</td>
<td>010</td>
<td>[08]</td>
<td>01 02 03 04 05 06 07 08</td>
</tr>
<tr>
<td>P</td>
<td>010</td>
<td>[03]</td>
<td>01 aa bb</td>
</tr>
<tr>
<td>--</td>
<td>00000010</td>
<td>[0]</td>
<td></td>
</tr>
<tr>
<td>--</td>
<td>010</td>
<td>[1]</td>
<td>20</td>
</tr>
<tr>
<td>--</td>
<td>010</td>
<td>[8]</td>
<td>remote transmission request</td>
</tr>
</tbody>
</table>

The columns have the following meaning:

- Flags
  - B: The frame has the CAN FD Baud Rate Switch (BRS) flag set.
  - P: The frame has the CAN FD Error State Indicator (ESI) flag set. The transmitting node is in error-passive state.
  - -: Unset flag.

- ID
  - 010: The standard (11-bit) CAN ID of the frame in hexadecimal format, here 10h.
  - 00000010: The extended (29-bit) CAN ID of the frame in hexadecimal format, here 10h.

- Size
  - [8]: The number of frame data bytes in decimal format, here a classic CAN frame with 8 data bytes.
  - [08]: The number of frame data bytes in decimal format, here a CAN FD frame with 8 data bytes.

- Data bytes
  - 01 02 03 04 05 06 07 08: The frame data bytes in hexadecimal format, here the numbers from 1 through 8.
  - remote transmission request: The frame is a Remote Transmission Request (RTR) frame and thus carries no data bytes.

**Tip:** If `CONFIG_CAN_RX_TIMESTAMP` is enabled, each line will be prepended with a timestamp from the free-running timestamp counter in the CAN controller.
Configured CAN RX filters can be removed again using the `can filter remove` subcommand as shown below. The filter ID is the ID returned by the `can filter add` subcommand (0 in the example below).

```
uart:$ can filter remove can@0 0
removing filter with ID 0
```

**Sending**  CAN frames can be queued for transmission using the `can send` subcommand as shown below. The subcommand accepts a CAN ID in hexadecimal format and optionally a number of data bytes, also specified in hexadecimal. Refer to the interactive help output for this subcommand for further details on the supported arguments.

```
uart:$ can send can@0 010 1 2 3 4 5 6 7 8
enqueuing CAN frame #2 with standard (11-bit) CAN ID 0x010, RTR 0, CAN FD 0, BRS 0, DLC 8
CAN frame #2 successfully sent
```

**Bus Recovery**  The `can recover` subcommand can be used for initiating recovery from a CAN bus-off event as shown below:

```
uart:$ can recover can@0
recovering, no timeout
```

The subcommand accepts an optional bus recovery timeout in milliseconds. If no timeout is specified, the command will wait indefinitely for the bus recovery to succeed.

---

**Note:** The `recover` subcommand is only available if `CONFIG_CAN_AUTO_BUS_OFF_RECOVERY` is disabled.

---

### 7.6.9 Chargers

The charger subsystem exposes an API to uniformly access battery charger devices.

**Basic Operation**

**Initiating a Charge Cycle**  A charge cycle is initiated or terminated using `charger_charge_enable()`.

**Properties**  Fundamentally, a property is a configurable setting, state, or quantity that a charger device can measure.

Chargers typically support multiple properties, such as temperature readings of the battery-pack or present-time current/voltage.

Properties are fetched by the client one at a time using `charger_get_prop()`. Properties are set by the client one at a time using `charger_set_prop()`.

**API Reference**

```
group charger_interface
    Charger Interface.
```
Typedefs

typedef uint16_t charger_prop_t
    A charger property's identifier.
    See charger_property for a list of identifiers

typedef int (*charger_get_property_t)(const struct device *dev, const charger_prop_t prop, union charger_propval *val)
    Callback API for getting a charger property.
    See charger_get_property() for argument description

typedef int (*charger_set_property_t)(const struct device *dev, const charger_prop_t prop, const union charger_propval *val)
    Callback API for setting a charger property.
    See charger_set_property() for argument description

typedef int (*charger_charge_enable_t)(const struct device *dev, const bool enable)
    Callback API enabling or disabling a charge cycle.
    See charger_charge_enable() for argument description

Enums

enum charger_property
    Runtime Dynamic Battery Parameters.
    Values:

    enumerator CHARGER_PROP_ONLINE = 0
        Indicates if external supply is present for the charger.
        Value should be of type enum charger_online

    enumerator CHARGER_PROP_PRESENT
        Reports whether or not a battery is present.
        Value should be of type bool

    enumerator CHARGER_PROP_STATUS
        Represents the charging status of the charger.
        Value should be of type enum charger_status

    enumerator CHARGER_PROP_CHARGE_TYPE
        Represents the charging algo type of the charger.
        Value should be of type enum charger_charge_type

    enumerator CHARGER_PROP_HEALTH
        Represents the health of the charger.
        Value should be of type enum charger_health
enumerator CHARGER_PROP_CONSTANT_CHARGE_CURRENT_UA
    Configuration of current sink used for charging in µA.

denumerator CHARGER_PROP_PRECHARGE_CURRENT_UA
    Configuration of current sink used for conditioning in µA.

denumerator CHARGER_PROP_CHARGE_TERM_CURRENT_UA
    Configuration of charge termination target in µA.

denumerator CHARGER_PROP_CONSTANT_CHARGE_VOLTAGE_UV
    Configuration of charge voltage regulation target in µV.

denumerator CHARGER_PROP_INPUT_REGULATION_CURRENT_UA
    Configuration of the input current regulation target in µA.
    This value is a rising current threshold that is regulated by reducing the charge current output

denumerator CHARGER_PROP_INPUT_REGULATION_VOLTAGE_UV
    Configuration of the input voltage regulation target in µV.
    This value is a falling voltage threshold that is regulated by reducing the charge current output

denumerator CHARGER_PROP_INPUT_CURRENT_NOTIFICATION
    Configuration to issue a notification to the system based on the input current level and timing.
    Value should be of type struct charger_input_current_notifier

denumerator CHARGER_PROP_COMMON_COUNT
    Reserved to demark end of common charger properties.

denumerator CHARGER_PROP_CUSTOM_BEGIN = CHARGER_PROP_COMMON_COUNT + 1
    Reserved to demark downstream custom properties - use this value as the actual value may change over future versions of this API.

denumerator CHARGER_PROP_MAX = UINT16_MAX
    Reserved to demark end of valid enum properties.

denum charger_online
    External supply states.
    Values:

denumerator CHARGER_ONLINE_OFFLINE = 0
    External supply not present.

denumerator CHARGER_ONLINE_FIXED
    External supply is present and of fixed output.
enumerator CHARGER_ONLINE_PROGRAMMABLE
   External supply is present and of programmable output.

enum charger_status
   Charging states.
   Values:

   enumerator CHARGER_STATUS_UNKNOWN = 0
      Charging device state is unknown.

   enumerator CHARGER_STATUS_CHARGING
      Charging device is charging a battery.

   enumerator CHARGER_STATUS_DISCHARGING
      Charging device is not able to charge a battery.

   enumerator CHARGER_STATUS_NOT_CHARGING
      Charging device is not charging a battery.

   enumerator CHARGER_STATUS_FULL
      The battery is full and the charging device will not attempt charging.

enum charger_charge_type
   Charge algorithm types.
   Values:

   enumerator CHARGER_CHARGE_TYPE_UNKNOWN = 0
      Charge type is unknown.

   enumerator CHARGER_CHARGE_TYPE_NONE
      Charging is not occurring.

   enumerator CHARGER_CHARGE_TYPE_TRICKLE
      Charging is occurring at the slowest desired charge rate, typically for battery de-
      tection or preconditioning.

   enumerator CHARGER_CHARGE_TYPE_FAST
      Charging is occurring at the fastest desired charge rate.

   enumerator CHARGER_CHARGE_TYPE_STANDARD
      Charging is occurring at a moderate charge rate.

   enumerator CHARGER_CHARGE_TYPE_ADAPTIVE

   enumerator CHARGER_CHARGE_TYPE_LONGLIFE

   enumerator CHARGER_CHARGE_TYPE_BYPASS

7.6. Peripherals
enum charger_health
Charger health conditions.
These conditions determine the ability to, or the rate of, charge
Values:

enumerator CHARGER_HEALTH_UNKNOWN = 0
Charger health condition is unknown.

enumerator CHARGER_HEALTH_GOOD
Charger health condition is good.

enumerator CHARGER_HEALTH_OVERHEAT
The charger device is overheated.

enumerator CHARGER_HEALTH_OVERVOLTAGE
The battery voltage has exceeded its overvoltage threshold.

enumerator CHARGER_HEALTH_UNSPEC_FAILURE
The battery or charger device is experiencing an unspecified failure.

enumerator CHARGER_HEALTH_COLD
The battery temperature is below the “cold” threshold.

enumerator CHARGER_HEALTH_WATCHDOG_TIMER_EXPIRE
The charger device's watchdog timer has expired.

enumerator CHARGER_HEALTH_SAFETY_TIMER_EXPIRE
The charger device's safety timer has expired.

enumerator CHARGER_HEALTH_CALIBRATION_REQUIRED
The charger device requires calibration.

enumerator CHARGER_HEALTH_WARM
The battery temperature is in the “warm” range.

enumerator CHARGER_HEALTH_COOL
The battery temperature is in the “cool” range.

enumerator CHARGER_HEALTH_HOT
The battery temperature is below the “hot” threshold.

enumerator CHARGER_HEALTH_NO_BATTERY
The charger device does not detect a battery.

enum charger_notification_severity
Charger severity levels for system notifications.
Values:
enumerator CHARGER_SEVERITY_PEAK = 0
   Most severe level, typically triggered instantaneously.

enumerator CHARGER_SEVERITY_CRITICAL
   More severe than the warning level, less severe than peak.

enumerator CHARGER_SEVERITY_WARNING
   Base severity level.

Functions

int charger_get_prop(const struct device *dev, const charger_prop_t prop, union charger_propval *val)
Fetch a battery charger property.

Parameters
   • dev – Pointer to the battery charger device
   • prop – Charger property to get
   • val – Pointer to charger_propval union

Return values
   • 0 – if successful
   • < 0 if getting property failed

int charger_set_prop(const struct device *dev, const charger_prop_t prop, const union charger_propval *val)
Set a battery charger property.

Parameters
   • dev – Pointer to the battery charger device
   • prop – Charger property to set
   • val – Pointer to charger_propval union

Return values
   • 0 – if successful
   • < 0 if setting property failed

int charger_charge_enable(const struct device *dev, const bool enable)
Enable or disable a charge cycle.

Parameters
   • dev – Pointer to the battery charger device
   • enable – true enables a charge cycle, false disables a charge cycle

Return values
   • 0 – if successful
   • -EIO – if communication with the charger failed
   • -EINVAL – if the conditions for initiating charging are invalid

struct charger_current_notifier
#include <charger.h> The input current thresholds for the charger to notify the system.
Public Members

`uint8_t severity`

The severity of the notification where CHARGER_SEVERITY_PEAK is the most severe.

`uint32_t current_ua`

The current threshold to be exceeded.

`uint32_t duration_us`

The duration of excess current before notifying the system.

union `charger_propval`

#include <charger.h> container for a charger_property value

Public Members

`enum charger_online online`

CHARGER_PROP_ONLINE.

`bool present`

CHARGER_PROP_PRESENT.

`enum charger_status status`

CHARGER_PROP_STATUS.

`enum charger_charge_type charge_type`

CHARGER_PROP_CHARGE_TYPE.

`enum charger_health health`

CHARGER_PROP_HEALTH.

`uint32_t const_charge_current_ua`

CHARGER_PROP_CONSTANT_CHARGE_CURRENT_UA.

`uint32_t precharge_current_ua`

CHARGER_PROP_PRECHARGE_CURRENT_UA.

`uint32_t charge_term_current_ua`

CHARGER_PROP_CHARGE_TERM_CURRENT_UA.

`uint32_t const_charge_voltage_uv`

CHARGER_PROP_CONSTANT_CHARGE_VOLTAGE_UV.

`uint32_t input_current_regulation_current_ua`

CHARGER_PROP_INPUT_REGULATION_CURRENT_UA.
7.6.10 Coredump Device

Overview

The coredump device is a pseudo-device driver with two types. A COREDUMP_TYPE_MEMCPY type exposes device tree bindings for memory address/size values to be included in any dump. And the driver exposes an API to add/remove dump memory regions at runtime. A COREDUMP_TYPE_CALLBACK device requires exactly one entry in the memory-regions array with a size of 0 and a desired size. The driver will statically allocate memory of the desired size and provide an API to register a callback function to fill that memory when a dump occurs.

Configuration Options

Related configuration options:

- CONFIG_COREDUMP_DEVICE

API Reference

group coredump_device_interface

Coredump pseudo-device driver APIs.

Typedefs

typedef void (*coredump_dump_callback_t)(uintptr_t dump_area, size_t dump_area_size)

Callback that occurs at dump time, data copied into dump_area will be included in the dump that is generated.

Param dump_area
Pointer to area to copy data into for inclusion in dump

Param dump_area_size
Size of available memory at dump_area

Functions
static inline bool coredump_device_register_memory(const struct device *dev, struct coredump_mem_region_node *region)

Register a region of memory to be stored in core dump at the time it is generated.

Parameters
• dev – Pointer to the device structure for the driver instance.
• region – Struct describing memory to be collected

Returns
true if registration succeeded

static inline bool coredump_device_unregister_memory(const struct device *dev, struct coredump_mem_region_node *region)

Unregister a region of memory to be stored in core dump at the time it is generated.

Parameters
• dev – Pointer to the device structure for the driver instance.
• region – Struct describing memory to be collected

Returns
true if unregistration succeeded

static inline bool coredump_device_register_callback(const struct device *dev, coredump_dump_callback_t callback)

Register a callback to be invoked at dump time.

Parameters
• dev – Pointer to the device structure for the driver instance.
• callback – Callback to be invoked at dump time

Returns
true if registration succeeded

Returns
false if registration failed

struct coredump_mem_region_node
#include <coredump.h> Structure describing a region in memory that may be stored in core dump at the time it is generated.

Instances of this are passed to the coredump_device_register_memory() and coredump_device_unregister_memory() functions to indicate addition and removal of memory regions to be captured

Public Members

sys_snodet node
Node of single-linked list, do not modify.
uintptr_t start
   Address of start of memory region.

size_t size
   Size of memory region.

7.6.11 Counter

Overview

API Reference

Related code samples

Counter Alarm
   Implement an alarm application using the counter API.

DS3231 TCXO RTC
   Interact with a DS3231 real-time clock using the counter API and dedicated driver API.


group counter_interface
   Counter Interface.

Counter device capabilities

COUNTER_CONFIG_INFO_COUNT_UP
   Counter count up flag.

Flags used by counter_top_cfg.

COUNTER_TOP_CFG_DONT_RESET
   Flag preventing counter reset when top value is changed.
   If flags is set then counter is free running while top value is updated, otherwise counter is reset (see counter_set_top_value()).

COUNTER_TOP_CFG_RESET_WHEN_LATE
   Flag instructing counter to reset itself if changing top value results in counter going out of new top value bound.
   See COUNTER_TOP_CFG_DONT_RESET.
Alarm configuration flags

Used in alarm configuration structure (counter_alarm_cfg).

COUNTER_ALARM_CFG_ABSOLUTE
Counter alarm absolute value flag.
Ticks relation to counter value. If set ticks are treated as absolute value, else it is relative to the counter reading performed during the call.

COUNTER_ALARM_CFG_EXPIRE_WHEN_LATE
Alarm flag enabling immediate expiration when driver detects that absolute alarm was set too late.
Alarm callback must be called from the same context as if it was set on time.

Counter guard period flags

Used by counter_set_guard_period and counter_get_guard_period.

COUNTER_GUARD_PERIOD_LATE_TO_SET
Identifies guard period needed for detection of late setting of absolute alarm (see counter_set_channel_alarm).

Typedefs

typedef void (*counter_alarm_callback_t)(const struct device *dev, uint8_t chan_id, uint32_t ticks, void *user_data)
   Alarm callback.
   
   Param dev
       Pointer to the device structure for the driver instance.

   Param chan_id
       Channel ID.

   Param ticks
       Counter value that triggered the alarm.

   Param user_data
       User data.

typedef void (*counter_top_callback_t)(const struct device *dev, void *user_data)
   Callback called when counter turns around.
   
   Param dev
       Pointer to the device structure for the driver instance.

   Param user_data
       User data provided in counter_set_top_value.

typedef int (*counter_api_start)(const struct device *dev)

typedef int (*counter_api_stop)(const struct device *dev)
typedef int (*counter_api_get_value)(const struct device *dev, uint32_t *ticks)

typedef int (*counter_api_get_value_64)(const struct device *dev, uint64_t *ticks)

typedef int (*counter_api_set_alarm)(const struct device *dev, uint8_t chan_id, const struct counter_alarm_cfg *alarm_cfg)

typedef int (*counter_api_cancel_alarm)(const struct device *dev, uint8_t chan_id)

typedef int (*counter_api_set_top_value)(const struct device *dev, const struct counter_top_cfg *cfg)

typedef uint32_t (*counter_api_get_pending_int)(const struct device *dev)

typedef uint32_t (*counter_api_get_top_value)(const struct device *dev)

typedef uint32_t (*counter_api_get_guard_period)(const struct device *dev, uint32_t flags)

typedef int (*counter_api_set_guard_period)(const struct device *dev, uint32_t ticks, uint32_t flags)

typedef uint32_t (*counter_api_get_freq)(const struct device *dev)

Functions

bool counter_is_counting_up(const struct device *dev)
Function to check if counter is counting up.

   Parameters
     • dev – [in] Pointer to the device structure for the driver instance.

   Return values
     • true – if counter is counting up.
     • false – if counter is counting down.

uint8_t counter_get_num_of_channels(const struct device *dev)
Function to get number of alarm channels.

   Parameters
     • dev – [in] Pointer to the device structure for the driver instance.

   Returns
     Number of alarm channels.

uint32_t counter_get_frequency(const struct device *dev)
Function to get counter frequency.

   Parameters
     • dev – [in] Pointer to the device structure for the driver instance.
Returns
Frequency of the counter in Hz, or zero if the counter does not have a fixed
frequency.

uint32_t counter_us_to_ticks(const struct device *dev, uint64_t us)
Function to convert microseconds to ticks.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Returns
Converted ticks. Ticks will be saturated if exceed 32 bits.

uint64_t counter_ticks_to_us(const struct device *dev, uint32_t ticks)
Function to convert ticks to microseconds.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• ticks – [in] Ticks.

Returns
Converted microseconds.

uint32_t counter_get_max_top_value(const struct device *dev)
Function to retrieve maximum top value that can be set.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Returns
Max top value.

int counter_start(const struct device *dev)
Start counter device in free running mode.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• Negative – errno code if failure.

int counter_stop(const struct device *dev)
Stop counter device.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• -ENOTSUP – if the device doesn’t support stopping the counter.

int counter_get_value(const struct device *dev, uint32_t *ticks)
Get current counter value.

Parameters
• dev – Pointer to the device structure for the driver instance.
• ticks – Pointer to where to store the current counter value
Return values

- 0 – If successful.
- Negative – error code on failure getting the counter value

```c
int counter_get_value_64(const struct device *dev, uint64_t *ticks)
```
Get current counter 64-bit value.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `ticks` – Pointer to where to store the current counter value

**Return values**

- 0 – If successful.
- Negative – error code on failure getting the counter value

```c
int counter_set_channel_alarm(const struct device *dev, uint8_t chan_id, const struct counter_alarm_cfg *alarm_cfg)
```
Set a single shot alarm on a channel.

After expiration alarm can be set again, disabling is not needed. When alarm expiration handler is called, channel is considered available and can be set again in that context.

**Note:** API is not thread safe.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `chan_id` – Channel ID.
- `alarm_cfg` – Alarm configuration.

**Return values**

- 0 – If successful.
- -ENOTSUP – if request is not supported (device does not support interrupts or requested channel).
- -EINVAL – if alarm settings are invalid.
- -ETIME – if absolute alarm was set too late.
- -EBUSY – if alarm is already active.

```c
int counter_cancel_channel_alarm(const struct device *dev, uint8_t chan_id)
```
Cancel an alarm on a channel.

**Note:** API is not thread safe.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `chan_id` – Channel ID.

**Return values**

- 0 – If successful.
-ENOTSUP – if request is not supported or the counter was not started yet.

```c
int counter_set_top_value(const struct device *dev, const struct counter_top_cfg *cfg)
```

Set counter top value.

Function sets top value and optionally resets the counter to 0 or top value depending on counter direction. On turnaround, counter can be reset and optional callback is periodically called. Top value can only be changed when there is no active channel alarm.

`COUNTER_TOP_CFG_DONT_RESET` prevents counter reset. When counter is running while top value is updated, it is possible that counter progresses outside the new top value. In that case, error is returned and optionally driver can reset the counter (see `COUNTER_TOP_CFG_RESET_WHEN_LATE`).

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
- **cfg** – Configuration. Cannot be NULL.

**Return values**

- **0** – If successful.
- -ENOTSUP – if request is not supported (e.g. top value cannot be changed or counter cannot/must be reset during top value update).
- -EBUSY – if any alarm is active.
- -ETIME – if `COUNTER_TOP_CFG_DONT_RESET` was set and new top value is smaller than current counter value (counter counting up).

```c
int counter_get_pending_int(const struct device *dev)
```

Function to get pending interrupts.

The purpose of this function is to return the interrupt status register for the device. This is especially useful when waking up from low power states to check the wake up source.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.

**Return values**

- **1** – if any counter interrupt is pending.
- **0** – if no counter interrupt is pending.

```c
uint32_t counter_get_top_value(const struct device *dev)
```

Function to retrieve current top value.

**Parameters**

- **dev** – [in] Pointer to the device structure for the driver instance.

**Returns**

Top value.

```c
int counter_set_guard_period(const struct device *dev, uint32_t ticks, uint32_t flags)
```

Set guard period in counter ticks.

When setting an absolute alarm value close to the current counter value there is a risk that the counter will have counted past the given absolute value before the driver manages to activate the alarm. If this would go unnoticed then the alarm would only expire after the timer has wrapped and reached the given absolute value again after a full timer period. This could take a long time in case of a 32 bit timer. Setting a
sufficiently large guard period will help the driver detect unambiguously whether it is late or not.

The guard period should be as many counter ticks as the driver will need at most to actually activate the alarm after the driver API has been called. If the driver finds that the counter has just passed beyond the given absolute tick value but is still close enough to fall within the guard period, it will assume that it is “late”, i.e. that the intended expiry time has already passed. Depending on the `COUNTER_ALARM_CFG_EXPIRE_WHEN_LATE` flag the driver will either ignore the alarm or expire it immediately in such a case.

If, however, the counter is past the given absolute tick value but outside the guard period, then the driver will assume that this is intentional and let the counter wrap around to/from zero before it expires.

More precisely:

- When counting upwards (see `COUNTER_CONFIG_INFO_COUNT_UP`) the given absolute tick value must be above `(now + guard_period) % top_value` to be accepted by the driver.

- When counting downwards, the given absolute tick value must be less than `(now + top_value - guard_period) % top_value` to be accepted.

Examples:

- counting upwards, now = 4950, top value = 5000, guard period = 100: absolute tick value >= `(4950 + 100) % 5000 = 50`

- counting downwards, now = 50, top value = 5000, guard period = 100: absolute tick value <= `(50 + 5000 - * 100) % 5000 = 4950`

If you need only short alarm periods, you can set the guard period very high (e.g. half of the counter top value) which will make it highly unlikely that the counter will ever unintentionally wrap.

The guard period is set to 0 on initialization (no protection).

**Parameters**

- dev – Pointer to the device structure for the driver instance.

- ticks – Guard period in counter ticks.

- flags – See `COUNTER_GUARD_PERIOD_FLAGS`.

**Return values**

- 0 – if successful.

- -ENOTSUP – if function or flags are not supported.

- -EINVAL – if ticks value is invalid.

```c
uint32_t counter_get_guard_period(const struct device *dev, uint32_t flags)
```

Return guard period.

**See also:**

`counter_set_guard_period`.

**Parameters**

- dev – Pointer to the device structure for the driver instance.
• **flags** – See `COUNTER_GUARD_PERIOD_FLAGS`.

**Returns**

Guard period given in counter ticks or 0 if function or flags are not supported.

```c
struct counter_alarm_cfg
#include <counter.h> Alarm callback structure.
```

**Public Members**

- `counter_alarm_callback_t callback`  
  Callback called on alarm (cannot be NULL).

```c
uint32_t ticks
Number of ticks that triggers the alarm.
```

It can be relative (to now) or an absolute value (see `COUNTER_ALARM_CFG_ABSOLUTE`). Both, relative and absolute, alarm values can be any value between zero and the current top value (see `counter_get_top_value`). When setting an absolute alarm value close to the current counter value there is a risk that the counter will have counted past the given absolute value before the driver manages to activate the alarm. Therefore a guard period can be defined that lets the driver decide unambiguously whether it is late or not (see `counter_set_guard_period`). If the counter is clock driven then ticks can be converted to microseconds (see `counter_ticks_to_us`). Alternatively, the counter implementation may count asynchronous events.

```c
void *user_data
User data returned in callback.
```

```c
uint32_t flags
Alarm flags (see `COUNTER_ALARM_FLAGS`).
```

```c
struct counter_top_cfg
#include <counter.h> Top value configuration structure.
```

**Public Members**

```c
uint32_t ticks
Top value.
```

```c
counter_top_callback_t callback
Callback function (can be NULL).
```

```c
void *user_data
User data passed to callback function (not valid if callback is NULL).
```

```c
uint32_t flags
Flags (see `COUNTER_TOP_FLAGS`).
```
struct counter_config_info

#include <counter.h> Structure with generic counter features.

Public Members

uint32_t max_top_value
Maximal (default) top value on which counter is reset (cleared or reloaded).

uint32_t freq
Frequency of the source clock if synchronous events are counted.

uint8_t flags
Flags (see COUNTER_FLAGS).

uint8_t channels
Number of channels that can be used for setting alarm.

See also:
counter_set_channel_alarm

struct counter_driver_api

#include <counter.h>

7.6.12 Digital-to-Analog Converter (DAC)

Overview

The DAC API provides access to Digital-to-Analog Converter (DAC) devices.

Configuration Options

Related configuration options:

- CONFIG_DAC

API Reference

Related code samples

Digital-to-Analog Converter (DAC)
Generate an analog sawtooth signal using the DAC driver API.

group dac_interface
DAC driver APIs.
Functions

int dac_channel_setup(const struct device *dev, const struct dac_channel_cfg *channel_cfg)

Configure a DAC channel.

It is required to call this function and configure each channel before it is selected for a write request.

Parameters

• dev – Pointer to the device structure for the driver instance.
• channel_cfg – Channel configuration.

Return values

• 0 – On success.
• -EINVAL – If a parameter with an invalid value has been provided.
• -ENOTSUP – If the requested resolution is not supported.

int dac_write_value(const struct device *dev, uint8_t channel, uint32_t value)

Write a single value to a DAC channel.

Parameters

• dev – Pointer to the device structure for the driver instance.
• channel – Number of the channel to be used.
• value – Data to be written to DAC output registers.

Return values

• 0 – On success.
• -EINVAL – If a parameter with an invalid value has been provided.

struct dac_channel_cfg

#include <dac.h> Structure for specifying the configuration of a DAC channel.

Public Members

uint8_t channel_id
    Channel identifier of the DAC that should be configured.

uint8_t resolution
    Desired resolution of the DAC (depends on device capabilities).

bool buffered
    Enable output buffer for this channel.
    This is relevant for instance if the output is directly connected to the load, without an amplifier in between. The actual details on this are hardware dependent.
7.6.13 Direct Memory Access (DMA)

Overview

Direct Memory Access (Controller) is a commonly provided type of co-processor that can typically offload transferring data to and from peripherals and memory.

The DMA API is not a portable API and really cannot be as each DMA has unique memory requirements, peripheral interactions, and features. The API in effect provides a union of all useful DMA functionality drivers have needed in the tree. It can still be a good abstraction, with care, for peripheral devices for vendors where the DMA IP might be very similar but have slight variances.

Driver Implementation Expectations

Synchronization and Ownership From an API point of view, a DMA channel is a single-owner object, meaning the drivers should not attempt to wrap a channel with kernel synchronization primitives such as mutexes or semaphores. If DMA channels require mutating shared registers, those register updates should be wrapped in a spin lock.

This enables the entire API to be low-cost and callable from any call context, including ISRs where it may be very useful to start/stop/suspend/resume/reload a channel transfer.

Transfer Descriptor Memory Management Drivers should not attempt to use heap allocations of any kind. If object pools are needed for transfer descriptors then those should be setup in a way that does not break the promise of ISR-allowable calls. Many drivers choose to create a simple static descriptor array per channel with the size of the descriptor array adjustable using Kconfig.

Channel State Machine Expectations DMA channels should be viewed as state machines that the DMA API provides transition events for in the form of API calls. Every driver is expected to maintain its own channel state tracking. The busy state of the channel should be inspectable at any time with `dma_get_status()`.

A diagram showing those expected possible state transitions and their API calls is provided here for reference.

API Reference

```markdown

group dma_interface

DMA Interface.

Defines

DMA_STATUS_COMPLETE
    The DMA callback event has occurred at the completion of a transfer list.

DMA_STATUS_BLOCK
    The DMA callback has occurred at the completion of a single transfer block in a transfer list.
```

7.6. Peripherals
Fig. 2: DMA state finite state machine
DMA_MAGIC
Magic code to identify context content.

DMA_BUF_ADDR_ALIGNMENT(node)
Get the device tree property describing the buffer address alignment.
Useful when statically defining or allocating buffers for DMA usage where memory alignment often matters.

Parameters
- node – Node identifier, e.g. DT_NODELABEL(dma_0)

Returns
alignment Memory byte alignment required for DMA buffers

DMA_BUF_SIZE_ALIGNMENT(node)
Get the device tree property describing the buffer size alignment.
Useful when statically defining or allocating buffers for DMA usage where memory alignment often matters.

Parameters
- node – Node identifier, e.g. DT_NODELABEL(dma_0)

Returns
alignment Memory byte alignment required for DMA buffers

DMA_COPY_ALIGNMENT(node)
Get the device tree property describing the minimal chunk of data possible to be copied.

Parameters
- node – Node identifier, e.g. DT_NODELABEL(dma_0)

Returns
minimal Minimal chunk of data possible to be copied

TypeDefs

typedef void (*dma_callback_t)(const struct device *dev, void *user_data, uint32_t
channel, int status)
Callback function for DMA transfer completion.
If enabled, callback function will be invoked at transfer or block completion, or when an error happens. In circular mode, status indicates that the DMA device has reached either the end of the buffer (DMA_STATUS_COMPLETE) or a water mark (DMA_STATUS_BLOCK).

Param dev
Pointer to the DMA device calling the callback.

Param user_data
A pointer to some user data or NULL

Param channel
The channel number

Param status
Status of the transfer
- DMA_STATUS_COMPLETE buffer fully consumed
- DMA_STATUS_BLOCK buffer consumption reached a configured block or water mark
- A negative errno otherwise

**Enums**

```c
enum dma_channel_direction
    DMA channel direction.
    Values:

    enumerator MEMORY_TO_MEMORY = 0x0
        Memory to memory.

    enumerator MEMORY_TO_PERIPHERAL
        Memory to peripheral.

    enumerator PERIPHERAL_TO_MEMORY
        Peripheral to memory.

    enumerator PERIPHERAL_TO_PERIPHERAL
        Peripheral to peripheral.

    enumerator HOST_TO_MEMORY
        Host to memory.

    enumerator MEMORY_TO_HOST
        Memory to host.

    enumerator DMA_CHANNEL_DIRECTION_COMMON_COUNT
        Number of all common channel directions.

    enumerator DMA_CHANNEL_DIRECTION_PRIV_START = DMA_CHANNEL_DIRECTION_COMMON_COUNT
        This and higher values are dma controller or soc specific.
        Refer to the specified dma driver header file.

    enumerator DMA_CHANNEL_DIRECTION_MAX = 0x7
        Maximum allowed value (3 bit field!)

enum dma_addr_adj
    DMA address adjustment.
    Valid values for source_addr_adj and dest_addr_adj
    Values:

    enumerator DMA_ADDR_ADJ_INCREMENT
        Increment the address.
```
enumerator DMA_ADDR_ADJ_DECREMENT
    Decrement the address.

dma_channel_filter
    DMA channel attributes.
    Values:
    enumerator DMA_CHANNEL_NORMAL
    enumerator DMA_CHANNEL_PERIODIC

dma_attribute_type
    DMA attributes.
    Values:
    enumerator DMA_ATTR_BUFFER_ADDRESS_ALIGNMENT
    enumerator DMA_ATTR_BUFFER_SIZE_ALIGNMENT
    enumerator DMA_ATTR_COPY_ALIGNMENT
    enumerator DMA_ATTR_MAX_BLOCK_COUNT

Functions

static inline int dma_config(const struct device *dev, uint32_t channel, struct dma_config *config)

Configure individual channel for DMA transfer.

Parameters

• dev – Pointer to the device structure for the driver instance.
• channel – Numeric identification of the channel to configure
• config – Data structure containing the intended configuration for the selected channel

Return values

• 0 – if successful.
• Negative – errno code if failure.

static inline int dma_reload(const struct device *dev, uint32_t channel, uint32_t src, uint32_t dst, size_t size)

Reload buffer(s) for a DMA channel.

Parameters

• dev – Pointer to the device structure for the driver instance.
• **channel** – Numeric identification of the channel to configure selected channel
• **src** – source address for the DMA transfer
• **dst** – destination address for the DMA transfer
• **size** – size of DMA transfer

**Return values**
• **0** – if successful.
• **Negative** – errno code if failure.

```c
int dma_start(const struct device *dev, uint32_t channel)
```

Enables DMA channel and starts the transfer, the channel must be configured beforehand.

Implementations must check the validity of the channel ID passed in and return -EINVAL if it is invalid.

Start is allowed on channels that have already been started and must report success.

**Function properties (list may not be complete)**

**isr-ok**

**Parameters**
• **dev** – Pointer to the device structure for the driver instance.
• **channel** – Numeric identification of the channel where the transfer will be processed

**Return values**
• **0** – if successful.
• **Negative** – errno code if failure.

```c
int dma_stop(const struct device *dev, uint32_t channel)
```

Stops the DMA transfer and disables the channel.

Implementations must check the validity of the channel ID passed in and return -EINVAL if it is invalid.

Stop is allowed on channels that have already been stopped and must report success.

**Function properties (list may not be complete)**

**isr-ok**

**Parameters**
• **dev** – Pointer to the device structure for the driver instance.
• **channel** – Numeric identification of the channel where the transfer was being processed

**Return values**
• **0** – if successful.
• **Negative** – errno code if failure.
int dma_suspend(const struct device *dev, uint32_t channel)
    Suspend a DMA channel transfer.
    Implementations must check the validity of the channel state and ID passed in and return -EINVAL if either are invalid.

Function properties (list may not be complete)
isr-ok

Parameters
• dev – Pointer to the device structure for the driver instance.
• channel – Numeric identification of the channel to suspend

Return values
• 0 – If successful.
• -ENOSYS – If not implemented.
• -EINVAL – If invalid channel id or state.
• -errno – Other negative errno code failure.

int dma_resume(const struct device *dev, uint32_t channel)
    Resume a DMA channel transfer.
    Implementations must check the validity of the channel state and ID passed in and return -EINVAL if either are invalid.

Function properties (list may not be complete)
isr-ok

Parameters
• dev – Pointer to the device structure for the driver instance.
• channel – Numeric identification of the channel to resume

Return values
• 0 – If successful.
• -ENOSYS – If not implemented
• -EINVAL – If invalid channel id or state.
• -errno – Other negative errno code failure.

int dma_request_channel(const struct device *dev, void *filter_param)
    request DMA channel.
    request DMA channel resources return -EINVAL if there is no valid channel available.

Function properties (list may not be complete)
isr-ok

Parameters
• dev – Pointer to the device structure for the driver instance.
• filter_param – filter function parameter
Return values

• *dma* – channel if successful.
• *Negative* – errno code if failure.

```c
void dma_release_channel(const struct device *dev, uint32_t channel)
```

release DMA channel.
release DMA channel resources

Function properties (list may not be complete)

`isr-ok`

Parameters

• *dev* – Pointer to the device structure for the driver instance.
• *channel* – channel number

```c
int dma_chan_filter(const struct device *dev, int channel, void *filter_param)
```

DMA channel filter.
filter channel by attribute

Parameters

• *dev* – Pointer to the device structure for the driver instance.
• *channel* – channel number
• *filter_param* – filter attribute

Return values

• *Negative* – errno code if not support

```c
static inline int dma_get_status(const struct device *dev, uint32_t channel, struct dma_status *stat)
```

get current runtime status of DMA transfer
Implementations must check the validity of the channel ID passed in and return -EINVAL if it is invalid or -ENOSYS if not supported.

Function properties (list may not be complete)

`isr-ok`

Parameters

• *dev* – Pointer to the device structure for the driver instance.
• *channel* – Numeric identification of the channel where the transfer was being processed
• *stat* – a non-NULL *dma_status* object for storing DMA status

Return values

• *non-negative* – if successful.
• *Negative* – errno code if failure.
static inline int dma_get_attribute(const struct device *dev, uint32_t type, uint32_t *value)

get attribute of a dma controller

This function allows to get a device specific static or runtime attribute like required address and size alignment of a buffer. Implementations must check the validity of the type passed in and return -EINVAL if it is invalid or -ENOSYS if not supported.

Function properties (list may not be complete)

isr-ok

Parameters

• dev – Pointer to the device structure for the driver instance.
• type – Numeric identification of the attribute
• value – A non-NULL pointer to the variable where the read value is to be placed

Return values

• non-negative – if successful.
• Negative – errno code if failure.

static inline uint32_t dma_width_index(uint32_t size)

Look-up generic width index to be used in registers.

Warning: This look-up works for most controllers, but may not work for yours. Ensure your controller expects the most common register bit values before using this convenience function. If your controller does not support these values, you will have to write your own look-up inside the controller driver.

Parameters

• size – width of bus (in bytes)

Return values

common – DMA index to be placed into registers.

static inline uint32_t dma_burst_index(uint32_t burst)

Look-up generic burst index to be used in registers.

Warning: This look-up works for most controllers, but may not work for yours. Ensure your controller expects the most common register bit values before using this convenience function. If your controller does not support these values, you will have to write your own look-up inside the controller driver.

Parameters

• burst – number of bytes to be sent in a single burst

Return values

common – DMA index to be placed into registers.
struct dma_block_config

#include <dma.h> DMA block configuration structure.

Aside from source address, destination address, and block size many of these options are hardware and driver dependent.

**Public Members**

```c
uint32_t source_address
    block starting address at source
```

```c
uint32_t dest_address
    block starting address at destination
```

```c
uint32_t source_gather_interval
    Address adjustment at gather boundary.
```

```c
uint32_t dest_scatter_interval
    Address adjustment at scatter boundary.
```

```c
uint16_t dest_scatter_count
    Continuous transfer count between scatter boundaries.
```

```c
uint16_t source_gather_count
    Continuous transfer count between gather boundaries.
```

```c
uint32_t block_size
    Number of bytes to be transferred for this block.
```

```c
struct dma_block_config *next_block
    Pointer to next block in a transfer list.
```

```c
uint16_t source_gather_en
    Enable source gathering when set to 1.
```

```c
uint16_t dest_scatter_en
    Enable destination scattering when set to 1.
```

```c
uint16_t source_addr_adj
    Source address adjustment option.
```

- 0b00 increment
- 0b01 decrement
- 0b10 no change

```c
uint16_t dest_addr_adj
    Destination address adjustment.
```

- 0b00 increment
• 0b01 decrement
• 0b10 no change

uint16_t source_reload_en
Reload source address at the end of block transfer.

uint16_t dest_reload_en
Reload destination address at the end of block transfer.

uint16_t fifo_mode_control
FIFO fill before starting transfer, HW specific meaning.

uint16_t flow_control_mode
Transfer flow control mode.

• 0b0 source request service upon data availability
• 0b1 source request postponed until destination request happens

struct dma_config
#include <dma.h> DMA configuration structure.

**Public Members**

uint32_t dma_slot
Which peripheral and direction, HW specific.

uint32_t channel_direction
Direction the transfers are occurring.

• 0b000 memory to memory,
• 0b001 memory to peripheral,
• 0b010 peripheral to memory,
• 0b011 peripheral to peripheral,
• 0b100 host to memory
• 0b101 memory to host
• others hardware specific

uint32_t complete_callback_en
Completion callback enable.

• 0b0 callback invoked at transfer list completion only
• 0b1 callback invoked at completion of each block

uint32_t error_callback_en
Error callback enable.

• 0b0 error callback enabled
• 0b1 error callback disabled
uint32_t source_handshake
    Source handshake, HW specific.
    • 0b0 HW
    • 0b1 SW

uint32_t dest_handshake
    Destination handshake, HW specific.
    • 0b0 HW
    • 0b1 SW

uint32_t channel_priority
    Channel priority for arbitration, HW specific.

uint32_t source_chaining_en
    Source chaining enable, HW specific.

uint32_t dest_chaining_en
    Destination chaining enable, HW specific.

uint32_t linked_channel
    Linked channel, HW specific.

uint32_t cyclic
    Cyclic transfer list, HW specific.

uint32_t source_data_size
    Width of source data (in bytes)

uint32_t dest_data_size
    Width of destination data (in bytes)

uint32_t source_burst_length
    Source burst length in bytes.

uint32_t dest_burst_length
    Destination burst length in bytes.

uint32_t block_count
    Number of blocks in transfer list.

struct dma_block_config *head_block
    Pointer to the first block in the transfer list.

void *user_data
    Optional attached user data for callbacks.
dma_callback_t dma_callback
   Optional callback for completion and error events.

struct dma_status
   #include <dma.h> DMA runtime status structure.

Public Members

bool busy
   Is the current DMA transfer busy or idle.

enum dma_channel_direction dir
   Direction fo the transfer.

uint32_t pending_length
   Pending length to be transferred in bytes, HW specific.

uint32_t free
   Available buffers space, HW specific.

uint32_t write_position
   Write position in circular DMA buffer, HW specific.

uint32_t read_position
   Read position in circular DMA buffer, HW specific.

uint64_t total_copied
   Total copied, HW specific.

struct dma_context
   #include <dma.h> DMA context structure Note: the dma_context shall be the first member of DMA client driver Data, got by dev->data.

Public Members

int32_t magic
   magic code to identify the context

int dma_channels
   number of dma channels

atomic_t *atomic
   atomic holding bit flags for each channel to mark as used/unused
7.6.14 Display Interface

API Reference

Generic Display Interface

Related code samples

Display
Draw basic rectangles on a display device.

LVGL basic sample
Display a "Hello World" and react to user input using LVGL.

LVGL demos
Run LVGL built-in demos.

LVGL line chart with accelerometer data
Display acceleration data on a real-time chart using LVGL.

group display_interface
Display Interface.

Defines

DISPLAY_BITS_PER_PIXEL(fmt)
Bits required per pixel for display format.
This macro expands to the number of bits required for a given display format. It can
be used to allocate a framebuffer based on a given display format type

Typedefs

typedef int (*display_blanking_on_api)(const struct device *dev)
Callback API to turn on display blanking See display_blanking_on() for argument descrip-
tion.

typedef int (*display_blanking_off_api)(const struct device *dev)
Callback API to turn off display blanking See display_blanking_off() for argument descrip-
tion.

typedef int (*display_write_api)(const struct device *dev, const uint16_t x, const uint16_t y, const struct display_buffer_descriptor *desc, void *buf)
Callback API for writing data to the display See display_write() for argument descrip-
tion.

typedef int (*display_read_api)(const struct device *dev, const uint16_t x, const uint16_t y, const struct display_buffer_descriptor *desc, void *buf)
Callback API for reading data from the display See display_read() for argument descrip-
tion.

typedef void *(*display_get_framebuffer_api)(const struct device *dev)
Callback API to get framebuffer pointer See display_get_framebuffer() for argument descrip-
tion.
typedef int (*display_set_brightness_api)(const struct device *dev, const uint8_t brightness)
   Callback API to set display brightness See display_set_brightness() for argument description.

typedef int (*display_set_contrast_api)(const struct device *dev, const uint8_t contrast)
   Callback API to set display contrast See display_set_contrast() for argument description.

typedef void (*display_get_capabilities_api)(const struct device *dev, struct display_capabilities *capabilities)
   Callback API to get display capabilities See display_get_capabilities() for argument description.

typedef int (*display_set_pixel_format_api)(const struct device *dev, const enum display_pixel_format pixel_format)
   Callback API to set pixel format used by the display See display_set_pixel_format() for argument description.

typedef int (*display_set_orientation_api)(const struct device *dev, const enum display_orientation orientation)
   Callback API to set orientation used by the display See display_set_orientation() for argument description.

Enums

enum display_pixel_format
   Display pixel formats.
   Display pixel format enumeration.
   In case a pixel format consists out of multiple bytes the byte order is big endian.
   Values:

   enumerator PIXEL_FORMAT_RGB_888 = BIT(0)
      24-bit RGB

   enumerator PIXEL_FORMAT_MONO01 = BIT(1)
      Monochrome (0=Black 1=White)

   enumerator PIXEL_FORMAT_MONO10 = BIT(2)
      Monochrome (1=Black 0=White)

   enumerator PIXEL_FORMAT_ARGB_8888 = BIT(3)
      32-bit ARGB

   enumerator PIXEL_FORMAT_RGB_565 = BIT(4)
      16-bit RGB

  enumerator PIXEL_FORMAT_BGR_565 = BIT(5)
      16-bit BGR
enum display_screen_info
Display screen information.

Values:

enumerator SCREEN_INFO_MONO_VTILED = BIT(0)
If selected, one octet represents 8 pixels ordered vertically, otherwise ordered horizontally.

enumerator SCREEN_INFO_MONO_MSB_FIRST = BIT(1)
If selected, the MSB represents the first pixel, otherwise MSB represents the last pixel.

enumerator SCREEN_INFO_EPD = BIT(2)
Electrophoretic Display.

enumerator SCREEN_INFO_DOUBLE_BUFFER = BIT(3)
Screen has two alternating ram buffers.

enumerator SCREEN_INFO_X_ALIGNMENT_WIDTH = BIT(4)
Screen has x alignment constrained to width.

enum display_orientation
Enumeration with possible display orientation.

Values:

enumerator DISPLAY_ORIENTATION_NORMAL
No rotation.

enumerator DISPLAY_ORIENTATION_ROTATED_90
Rotated 90 degrees clockwise.

enumerator DISPLAY_ORIENTATION_ROTATED_180
Rotated 180 degrees clockwise.

enumerator DISPLAY_ORIENTATION_ROTATED_270
Rotated 270 degrees clockwise.

Functions

static inline int display_write(const struct device *dev, const uint16_t x, const uint16_t y, const struct display_buffer_descriptor *desc, const void *buf)
Write data to display.

Parameters

• dev – Pointer to device structure
• x – x Coordinate of the upper left corner where to write the buffer
• y – y Coordinate of the upper left corner where to write the buffer
• `desc` – Pointer to a structure describing the buffer layout
• `buf` – Pointer to buffer array

**Return values**

0 – on success else negative errno code.

static inline int display_read(const struct device *dev, const uint16_t x, const uint16_t y, const struct display_buffer_descriptor *desc, void *buf)

Read data from display.

**Parameters**

• `dev` – Pointer to device structure
• `x` – x Coordinate of the upper left corner where to read from
• `y` – y Coordinate of the upper left corner where to read from
• `desc` – Pointer to a structure describing the buffer layout
• `buf` – Pointer to buffer array

**Return values**

• 0 – on success else negative errno code.
• -ENOSYS – if not implemented.

static inline void *display_get_framebuffer(const struct device *dev)

Get pointer to framebuffer for direct access.

**Parameters**

• `dev` – Pointer to device structure

**Return values**

Pointer – to frame buffer or NULL if direct framebuffer access is not supported

static inline int display_blanking_on(const struct device *dev)

Turn display blanking on.

This function blanks the complete display. The content of the frame buffer will be retained while blanking is enabled and the frame buffer will be accessible for read and write operations.

In case backlight control is supported by the driver the backlight is turned off. The backlight configuration is retained and accessible for configuration.

In case the driver supports display blanking the initial state of the driver would be the same as if this function was called.

**Parameters**

• `dev` – Pointer to device structure

**Return values**

• 0 – on success else negative errno code.
• -ENOSYS – if not implemented.

static inline int display_blanking_off(const struct device *dev)

Turn display blanking off.

Restore the frame buffer content to the display. In case backlight control is supported by the driver the backlight configuration is restored.

**Parameters**

• `dev` – Pointer to device structure
Return values

- 0 – on success else negative errno code.
- -ENOSYS – if not implemented.

static inline int display_set_brightness(const struct device *dev, uint8_t brightness)
Set the brightness of the display.
Set the brightness of the display in steps of 1/256, where 255 is full brightness and 0 is minimal.

Parameters

- dev – Pointer to device structure
- brightness – Brightness in steps of 1/256

Return values

- 0 – on success else negative errno code.
- -ENOSYS – if not implemented.

static inline int display_set_contrast(const struct device *dev, uint8_t contrast)
Set the contrast of the display.
Set the contrast of the display in steps of 1/256, where 255 is maximum difference and 0 is minimal.

Parameters

- dev – Pointer to device structure
- contrast – Contrast in steps of 1/256

Return values

- 0 – on success else negative errno code.
- -ENOSYS – if not implemented.

static inline void display_get_capabilities(const struct device *dev, struct display_capabilities *capabilities)
Get display capabilities.

Parameters

- dev – Pointer to device structure
- capabilities – Pointer to capabilities structure to populate

static inline int display_set_pixel_format(const struct device *dev, const enum display_pixel_format pixel_format)
Set pixel format used by the display.

Parameters

- dev – Pointer to device structure
- pixel_format – Pixel format to be used by display

Return values

- 0 – on success else negative errno code.
- -ENOSYS – if not implemented.
static inline int display_set_orientation(const struct device *dev, const enum display_orientation orientation)

Set display orientation.

**Parameters**

- `dev` – Pointer to device structure
- `orientation` – Orientation to be used by display

**Return values**

- 0 – on success else negative errno code.
- -ENOSYS – if not implemented.

```c
#include <display.h>
```

Structure holding display capabilities.

**Public Members**

```c
uint16_t x_resolution
    Display resolution in the X direction.

uint16_t y_resolution
    Display resolution in the Y direction.

uint32_t supported_pixel_formats
    Bitwise or of pixel formats supported by the display.

uint32_t screen_info
    Information about display panel.

enum display_pixel_format current_pixel_format
    Currently active pixel format for the display.

enum display_orientation current_orientation
    Current display orientation.
```

```c
#include <display.h>
```

Structure to describe display data buffer layout.

**Public Members**

```c
uint32_t buf_size
    Data buffer size in bytes.

uint16_t width
    Data buffer row width in pixels.

uint16_t height
    Data buffer column height in pixels.
```
Number of pixels between consecutive rows in the data buffer.

\begin{verbatim}
#include <display.h>  
\end{verbatim}

Display driver API API which a display driver should expose.

\textbf{Grove LCD Display}  
\textbf{Related code samples}

\textbf{Grove LCD}

Display an incrementing counter and change the backlight color.

\textbf{group} grove_display

Grove display APIs.

\textbf{Defines}

- GLCD_DS_DISPLAY_ON
- GLCD_DS_DISPLAY_OFF
- GLCD_DS_CURSOR_ON
- GLCD_DS_CURSOR_OFF
- GLCD_DS_BLINK_ON
- GLCD_DS_BLINK_OFF
- GLCD_IS_SHIFT_INCREMENT
- GLCD_IS_SHIFT_DECREMENT
- GLCD_IS_ENTRY_LEFT
- GLCD_IS_ENTRY_RIGHT
- GLCD_FS_8BIT_MODE
- GLCD_FS_ROWS_2
- GLCD_FS_ROWS_1
- GLCD_FS_DOT_SIZE_BIG
Functions

void glcd_print(const struct device *dev, char *data, uint32_t size)
    Send text to the screen.

    Parameters
        • dev – Pointer to device structure for driver instance.
        • data – the ASCII text to display
        • size – the length of the text in bytes

void glcd_cursor_pos_set(const struct device *dev, uint8_t col, uint8_t row)
    Set text cursor position for next additions.

    Parameters
        • dev – Pointer to device structure for driver instance.
        • col – the column for the cursor to be moved to (0-15)
        • row – the row it should be moved to (0 or 1)

void glcd_clear(const struct device *dev)
    Clear the current display.

    Parameters
        • dev – Pointer to device structure for driver instance.

void glcd_display_state_set(const struct device *dev, uint8_t opt)
    Function to change the display state.

    This function provides the user the ability to change the state of the display as per
    needed. Controlling things like powering on or off the screen, the option to display the
    cursor or not, and the ability to blink the cursor.

    Parameters
        • dev – Pointer to device structure for driver instance.
        • opt – An 8bit bitmask of GLCD_DS_* options.

uint8_t glcd_display_state_get(const struct device *dev)
    return the display feature set associated with the device

    Parameters
        • dev – the Grove LCD to get the display features set

    Returns
        the display feature set associated with the device.
void glcd_input_state_set(const struct device *dev, uint8_t opt)
    Function to change the input state.
    This function provides the user the ability to change the state of the text input. Controlling things like text entry from the left or right side, and how far to increment on new text

    Parameters
    • dev – Pointer to device structure for driver instance.
    • opt – A bitmask of GLCD_IS_* options

uint8_t glcd_input_state_get(const struct device *dev)
    return the input set associated with the device

    Parameters
    • dev – the Grove LCD to get the input features set

Returns
    the input set associated with the device.

void glcd_function_set(const struct device *dev, uint8_t opt)
    Function to set the functional state of the display.
    This function provides the user the ability to change the state of the display as per needed. Controlling things like the number of rows, dot size, and text display quality.

    Parameters
    • dev – Pointer to device structure for driver instance.
    • opt – A bitmask of GLCD_FS_* options

uint8_t glcd_function_get(const struct device *dev)
    return the function set associated with the device

    Parameters
    • dev – the Grove LCD to get the functions set

Returns
    the function features set associated with the device.

void glcd_color_select(const struct device *dev, uint8_t color)
    Set LCD background to a predefined color.

    Parameters
    • dev – Pointer to device structure for driver instance.
    • color – One of the predefined color options

void glcd_color_set(const struct device *dev, uint8_t r, uint8_t g, uint8_t b)
    Set LCD background to custom RGB color value.

    Parameters
    • dev – Pointer to device structure for driver instance.
    • r – A numeric value for the red color (max is 255)
    • g – A numeric value for the green color (max is 255)
    • b – A numeric value for the blue color (max is 255)
BBC micro:bit Display

\textit{group \texttt{mb_display}}

BBC micro:bit display APIs.

\textbf{Defines}

\texttt{MB_\texttt{IMAGE}(...)}

Generate an image object from a given array rows/columns.

This helper takes an array of 5 rows, each consisting of 5 0/1 values which correspond to the columns of that row. The value 0 means the pixel is disabled whereas a 1 means the pixel is enabled.

The pixels go from left to right and top to bottom, i.e. top-left corner is the first row’s first value, top-right is the first row’s last value, and bottom-right corner is the last value of the last (5th) row. As an example, the following would create a smiley face image:

\textbf{Parameters}

- \texttt{\_rows} – Each of the 5 rows represented as a 5-value column array.

\textbf{Returns}

Image bitmap that can be passed e.g. to \texttt{mb_display_image()}.

\textbf{ Enums }

\texttt{enum \texttt{mb_display\_mode}}

Display mode.

First 16 bits are reserved for modes, last 16 for flags.

\textit{Values:}

\begin{itemize}
  \item \texttt{MB\_DISPLAY\_MODE\_DEFAULT} - Default mode (“single” for images, “scroll” for text).
  \item \texttt{MB\_DISPLAY\_MODE\_SINGLE} - Display images sequentially, one at a time.
  \item \texttt{MB\_DISPLAY\_MODE\_SCROLL} - Display images by scrolling.
  \item \texttt{MB\_DISPLAY\_FLAG\_LOOP = BIT(16)} - Loop back to the beginning when reaching the last image.
\end{itemize}

\textbf{Functions}

\texttt{struct mb\_display *mb\_display\_get(void)}

Get a pointer to the BBC micro:bit display object.

\textbf{Returns}

Pointer to display object.
void mb_display_image(struct mb_display *disp, uint32_t mode, int32_t duration, const struct mb_image *img, uint8_t img_count)

Display one or more images on the BBC micro:bit LED display.

This function takes an array of one or more images and renders them sequentially on the micro:bit display. The call is asynchronous, i.e. the processing of the display happens in the background. If there is another image being displayed it will be canceled and the new one takes over.

**Parameters**

- **disp** – Display object.
- **mode** – One of the MB_DISPLAY_MODE_* options.
- **duration** – Duration how long to show each image (in milliseconds), or SYS_FOREVER_MS.
- **img** – Array of image bitmaps (struct mb_image objects).
- **img_count** – Number of images in ‘img’ array.

void mb_display_print(struct mb_display *disp, uint32_t mode, int32_t duration, const char *fmt, ...)

Print a string of characters on the BBC micro:bit LED display.

This function takes a printf-style format string and outputs it in a scrolling fashion to the display.

The call is asynchronous, i.e. the processing of the display happens in the background. If there is another image or string being displayed it will be canceled and the new one takes over.

**Parameters**

- **disp** – Display object.
- **mode** – One of the MB_DISPLAY_MODE_* options.
- **duration** – Duration how long to show each character (in milliseconds), or SYS_FOREVER_MS.
- **fmt** – printf-style format string
- **...** – Optional list of format arguments.

void mb_display_stop(struct mb_display *disp)

Stop the ongoing display of an image.

**Parameters**

- **disp** – Display object.

struct mb_image

#include <mb_display.h> Representation of a BBC micro:bit display image.

This struct should normally not be used directly, rather created using the MB_IMAGE() macro.

---

**Monochrome Character Framebuffer**

**Related code samples**

**Character Framebuffer shell module**

Use the CFB shell module to interact with a monochrome display.

**Character frame buffer**

Display character strings using the Character Frame Buffer (CFB).
**Custom fonts**
Generate and use a custom font.

```c
#define FONT_ENTRY_DEFINE(_name, _width, _height, _caps, _data, _fc, _lc)
```

Macro for creating a font entry.

**Parameters**
- `name` – Name of the font entry.
- `width` – Width of the font in pixels
- `height` – Height of the font in pixels.
- `caps` – Font capabilities.
- `data` – Raw data of the font.
- `fc` – Character mapped to first font element.
- `lc` – Character mapped to last font element.

**Enums**

```c
eenum cfb_display_param

enumerator CFB_DISPLAY_HEIGH = 0
enumerator CFB_DISPLAY_WIDTH
enumerator CFB_DISPLAY_PPT
enumerator CFB_DISPLAY_ROWS
enumerator CFB_DISPLAY_COLS
```

```c
eenum cfb_font_caps

enumerator CFB_FONT_MONO_VPACKED = BIT(0)
enumerator CFB_FONT_MONO_HPACKED = BIT(1)
enumerator CFB_FONT_MSB_FIRST = BIT(2)
```
Functions

int cfb_print(const struct device *dev, const char *const str, uint16_t x, uint16_t y)
Print a string into the framebuffer.

Parameters
• dev – Pointer to device structure for driver instance
• str – String to print
• x – Position in X direction of the beginning of the string
• y – Position in Y direction of the beginning of the string

Returns
0 on success, negative value otherwise

int cfb_draw_text(const struct device *dev, const char *const str, int16_t x, int16_t y)
Print a string into the framebuffer.
For compare to cfb_print, cfb_draw_text accept non tile-aligned coords and not line wrapping.

Parameters
• dev – Pointer to device structure for driver instance
• str – String to print
• x – Position in X direction of the beginning of the string
• y – Position in Y direction of the beginning of the string

Returns
0 on success, negative value otherwise

int cfb_draw_point(const struct device *dev, const struct cfb_position *pos)
Draw a point.

Parameters
• dev – Pointer to device structure for driver instance
• pos – position of the point

Returns
0 on success, negative value otherwise

int cfb_draw_line(const struct device *dev, const struct cfb_position *start, const struct cfb_position *end)
Draw a line.

Parameters
• dev – Pointer to device structure for driver instance
• start – start position of the line
• end – end position of the line

Returns
0 on success, negative value otherwise

int cfb_draw_rect(const struct device *dev, const struct cfb_position *start, const struct cfb_position *end)
Draw a rectangle.

Parameters
• dev – Pointer to device structure for driver instance
- **start** – Top-Left position of the rectangle
- **end** – Bottom-Right position of the rectangle

**Returns**
0 on success, negative value otherwise

```c
int cfb_framebuffer_clear(const struct device *dev, bool clear_display)
```
Clear framebuffer.

**Parameters**
- **dev** – Pointer to device structure for driver instance
- **clear_display** – Clear the display as well

**Returns**
0 on success, negative value otherwise

```c
int cfb_framebuffer_invert(const struct device *dev)
```
Invert Pixels.

**Parameters**
- **dev** – Pointer to device structure for driver instance

**Returns**
0 on success, negative value otherwise

```c
int cfb_invert_area(const struct device * dev, uint16_t x, uint16_t y, uint16_t width, uint16_t height)
```
Invert Pixels in selected area.

**Parameters**
- **dev** – Pointer to device structure for driver instance
- **x** – Position in X direction of the beginning of area
- **y** – Position in Y direction of the beginning of area
- **width** – Width of area in pixels
- **height** – Height of area in pixels

**Returns**
0 on success, negative value otherwise

```c
int cfb_framebuffer_finalize(const struct device *dev)
```
Finalize framebuffer and write it to display RAM, invert or reorder pixels if necessary.

**Parameters**
- **dev** – Pointer to device structure for driver instance

**Returns**
0 on success, negative value otherwise

```c
int cfb_get_display_parameter(const struct device *dev, enum cfb_display_param)
```
Get display parameter.

**Parameters**
- **dev** – Pointer to device structure for driver instance
- **cfb_display_param** – One of the display parameters

**Returns**
Display parameter value
int cfb_framebuffer_set_font(const struct device *dev, uint8_t idx)
Set font.

Parameters
• dev – Pointer to device structure for driver instance
• idx – Font index

Returns
0 on success, negative value otherwise

int cfb_set_kerning(const struct device *dev, int8_t kerning)
Set font kerning (spacing between individual letters).

Parameters
• dev – Pointer to device structure for driver instance
• kerning – Font kerning

Returns
0 on success, negative value otherwise

int cfb_get_font_size(const struct device *dev, uint8_t idx, uint8_t *width, uint8_t *height)
Get font size.

Parameters
• dev – Pointer to device structure for driver instance
• idx – Font index
• width – Pointers to the variable where the font width will be stored.
• height – Pointers to the variable where the font height will be stored.

Returns
0 on success, negative value otherwise

int cfb_get_numof_fonts(const struct device *dev)
Get number of fonts.

Parameters
• dev – Pointer to device structure for driver instance

Returns
number of fonts

int cfb_framebuffer_init(const struct device *dev)
Initialize Character Framebuffer.

Parameters
• dev – Pointer to device structure for driver instance

Returns
0 on success, negative value otherwise

struct cfb_font
#include <cfb.h>

struct cfb_position
#include <cfb.h>
7.6.15 Electrically Erasable Programmable Read-Only Memory (EEPROM)

Overview

The EEPROM API provides read and write access to Electrically Erasable Programmable Read-Only Memory (EEPROM) devices.

EEPROMs have an erase block size of 1 byte, a long lifetime, and allow overwriting data on byte-by-byte access.

Configuration Options

Related configuration options:

- CONFIG_EEPROM

API Reference

Related code samples

**EEPROM**

Store a boot count value in EEPROM.

```c
const struct device *dev, off_t offset, void *data, size_t len
```

Read data from EEPROM.

**Parameters**

- `dev` – EEPROM device
- `offset` – Address offset to read from.
- `data` – Buffer to store read data.
- `len` – Number of bytes to read.

**Returns**

0 on success, negative errno code on failure.

```c
const struct device *dev, off_t offset, const void *data, size_t len
```

Write data to EEPROM.

**Parameters**

- `dev` – EEPROM device
- `offset` – Address offset to write data to.
- `data` – Buffer with data to write.
- `len` – Number of bytes to write.

**Returns**

0 on success, negative errno code on failure.
size_t eeprom_get_size(const struct device *dev)
Get the size of the EEPROM in bytes.

Parameters
• dev – EEPROM device.

Returns
EEPROM size in bytes.

7.6.16 Enhanced Serial Peripheral Interface (eSPI) Bus

Overview
The eSPI (enhanced serial peripheral interface) is a serial bus that is based on SPI. It also features a four-wire interface (receive, transmit, clock and slave select) and three configurations: single IO, dual IO and quad IO.

The technical advancements include lower voltage signal levels (1.8V vs. 3.3V), lower pin count, and the frequency is twice as fast (66MHz vs. 33MHz) Because of its enhancements, the eSPI is used to replace the LPC (lower pin count) interface, SPI, SMBus and sideband signals.

See eSPI interface specification for additional details.

API Reference

Related code samples
Enhanced Serial Peripheral Interface (eSPI)
Use eSPI to connect to a slave device and exchange virtual wire packets.

group espi_interface
eSPI Driver APIs
eSPI SAF Driver APIs

Defines
ESPI_VWIRE_SIGNAL_OCB_0
ESPI_VWIRE_SIGNAL_OCB_1
ESPI_VWIRE_SIGNAL_OCB_2
ESPI_VWIRE_SIGNAL_OCB_3
HOST_KBC_EVT_IBF
HOST_KBC_EVT_OBE
Typedefs

typedef void (*espi_callback_handler_t)(const struct device *dev, struct espi_callback *cb, struct espi_event espi_evt)

Define the application callback handler function signature.

**Param dev**
Device struct for the eSPI device.

**Param cb**
Original struct espi_callback owning this handler.

**Param espi_evt**
event details that trigger the callback handler.

Enums

define espi_io_mode
eSPI I/O mode capabilities

*Values:*

enumerator ESPI_IO_MODE_SINGLE_LINE = BIT(0)
enumerator ESPI_IO_MODE_DUAL_LINES = BIT(1)
enumerator ESPI_IO_MODE_QUAD_LINES = BIT(2)

define espi_channel
eSPI channel.
Identifies each eSPI logical channel supported by eSPI controller. Each channel allows independent traffic, but the assignment of channel type to channel number is fixed.

Note that generic commands are not associated with any channel, so traffic over eSPI can occur if all channels are disabled or not ready.

**Values:**

- enumerator `ESPI_CHANNEL_PERIPHERAL` = `BIT(0)`
- enumerator `ESPI_CHANNEL_VWIRE` = `BIT(1)`
- enumerator `ESPI_CHANNEL_OOB` = `BIT(2)`
- enumerator `ESPI_CHANNEL_FLASH` = `BIT(3)`

**enum espi_bus_event**

- eSPI bus event.
- eSPI bus event to indicate events for which user can register callbacks

**Values:**

- enumerator `ESPI_BUS_RESET` = `BIT(0)`
- enumerator `ESPI_BUS_EVENT_CHANNEL_READY` = `BIT(1)`
- enumerator `ESPI_BUS_EVENT_VWIRE_RECEIVED` = `BIT(2)`
- enumerator `ESPI_BUS_EVENT_OOB_RECEIVED` = `BIT(3)`
- enumerator `ESPI_BUS_PERIPHERAL_NOTIFICATION` = `BIT(4)`
enumerator ESPI_BUS_SAF_NOTIFICATION = BIT(5)

enum espi_pc_event
    eSPI peripheral channel events.
    eSPI peripheral channel event types to indicate users.
    Values:

    enumerator ESPI_PC_EVT_BUS_CHANNEL_READY = BIT(0)

    enumerator ESPI_PC_EVT_BUS_MASTER_ENABLE = BIT(1)

enum espi_virtual_peripheral
    eSPI peripheral notification type.
    eSPI peripheral notification event details to indicate which peripheral trigger the eSPI callback
    Values:

    enumerator ESPI_PERIPHERAL_UART

    enumerator ESPI_PERIPHERAL_8042_KBC

    enumerator ESPI_PERIPHERAL_HOST_IO

    enumerator ESPI_PERIPHERAL_DEBUG_PORT80

    enumerator ESPI_PERIPHERAL_HOST_IO_PVT

enum espi_cycle_type
    eSPI cycle types supported over eSPI peripheral channel
    Values:

    enumerator ESPI_CYCLE_MEMORY_READ32

    enumerator ESPI_CYCLE_MEMORY_READ64

    enumerator ESPI_CYCLE_MEMORY_WRITE32

    enumerator ESPI_CYCLE_MEMORY_WRITE64

    enumerator ESPI_CYCLE_MESSAGE_NODATA

    enumerator ESPI_CYCLE_MESSAGE_DATA

    enumerator ESPI_CYCLE_OK_COMPLETION_NODATA
enumerator ESPI_CYCLE_OK_COMPLETION_DATA
enumerator ESPI_CYCLE_NOK_COMPLETION_NODATA

enum espi_vwire_signal
  eSPI system platform signals that can be send or receive through virtual wire channel
  Values:
  enumerator ESPI_VWIRE_SIGNAL_SLP_S3
  enumerator ESPI_VWIRE_SIGNAL_SLP_S4
  enumerator ESPI_VWIRE_SIGNAL_SLP_S5
  enumerator ESPI_VWIRE_SIGNAL_OOB_RST_WARN
  enumerator ESPI_VWIRE_SIGNAL_PLTRST
  enumerator ESPI_VWIRE_SIGNAL_SUS_STAT
  enumerator ESPI_VWIRE_SIGNAL_NMIOUT
  enumerator ESPI_VWIRE_SIGNAL_SMIOUT
  enumerator ESPI_VWIRE_SIGNAL_HOST_RST_WARN
  enumerator ESPI_VWIRE_SIGNAL_SLP_A
  enumerator ESPI_VWIRE_SIGNAL_SUS_PWRDN_ACK
  enumerator ESPI_VWIRE_SIGNAL_SUS_WARN
  enumerator ESPI_VWIRE_SIGNAL_SLP_WLAN
  enumerator ESPI_VWIRE_SIGNAL_SLP_LAN
  enumerator ESPI_VWIRE_SIGNAL_HOST_C10
  enumerator ESPI_VWIRE_SIGNAL_DNX_WARN
  enumerator ESPI_VWIRE_SIGNAL_PME
  enumerator ESPI_VWIRE_SIGNAL_WAKE
  enumerator ESPI_VWIRE_SIGNAL_OOB_RST_ACK
enumerator ESPI_VWIRE_SIGNAL_SLV_BOOT_STS
enumerator ESPI_VWIRE_SIGNAL_ERR_NON_FATAL
enumerator ESPI_VWIRE_SIGNAL_ERR_FATAL
enumerator ESPI_VWIRE_SIGNAL_SLV_BOOT_DONE
enumerator ESPI_VWIRE_SIGNAL_HOST_RST_ACK
enumerator ESPI_VWIRE_SIGNAL_RST_CPU_INIT
enumerator ESPI_VWIRE_SIGNAL_SMI
enumerator ESPI_VWIRE_SIGNAL_SCI
enumerator ESPI_VWIRE_SIGNAL_DNX_ACK
enumerator ESPI_VWIRE_SIGNAL_SUS_ACK
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_0
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_1
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_2
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_3
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_4
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_5
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_6
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_7
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_8
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_9
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_10
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_11
enumerator ESPI_VWIRE_SIGNAL_COUNT

7.6. Peripherals
enum lpc_peripheral_opcode

Values:

enumerator E8042_OBF_HAS_CHAR = 0x50
enumerator E8042_IBF_HAS_CHAR
enumerator E8042_WRITE_KB_CHAR
enumerator E8042_WRITE_MB_CHAR
enumerator E8042_RESUME_IRQ
enumerator E8042_PAUSE_IRQ
enumerator E8042_CLEAR_OBF
enumerator E8042_READ_KB_STS
enumerator E8042_SET_FLAG
enumerator E8042_CLEAR_FLAG
enumerator EACPI_OBF_HAS_CHAR = EACPI_START_OPCODE
enumerator EACPI_IBF_HAS_CHAR
enumerator EACPI_WRITE_CHAR
enumerator EACPI_READ_STS
enumerator EACPI_WRITE_STS

Functions

int espi_config(const struct device *dev, struct espi_cfg *cfg)

Configure operation of a eSPI controller.

This routine provides a generic interface to override eSPI controller capabilities.

If this eSPI controller is acting as slave, the values set here will be discovered as part through the GET_CONFIGURATION command issued by the eSPI master during initialization.

If this eSPI controller is acting as master, the values set here will be used by eSPI master to determine minimum common capabilities with eSPI slave then send via SET_CONFIGURATION command.
Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `cfg` – the device runtime configuration for the eSPI controller.

Return values

- 0 – If successful.
- -EIO – General input / output error, failed to configure device.
- -EINVAL – invalid capabilities, failed to configure device.
- -ENOTSUP – capability not supported by eSPI slave.

bool `espi_get_channel_status`(const struct device *dev, enum espi_channel ch)

Query to see if it a channel is ready.

This routine allows to check if logical channel is ready before use. Note that queries for channels not supported will always return false.

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `ch` – the eSPI channel for which status is to be retrieved.

Return values

- true – If eSPI channel is ready.
- false – otherwise.

int `espi_read_request`(const struct device *dev, struct espi_request_packet *req)

Sends memory, I/O or message read request over eSPI.

This routines provides a generic interface to send a read request packet.

Parameters

- `dev` – Pointer to the device structure for the driver instance.
• req – Address of structure representing a memory, I/O or message read request.

Return values
• 0 – If successful.
• -ENOTSUP – if eSPI controller doesn’t support raw packets and instead low memory transactions are handled by controller hardware directly.
• -EIO – General input / output error, failed to send over the bus.

int espi_write_request(const struct device *dev, struct espi_request_packet *req)
Sends memory, I/O or message write request over eSPI.
This routines provides a generic interface to send a write request packet.

Parameters
• dev – Pointer to the device structure for the driver instance.
• req – Address of structure representing a memory, I/O or message write request.

Return values
• 0 – If successful.
• -ENOTSUP – if eSPI controller doesn’t support raw packets and instead low memory transactions are handled by controller hardware directly.
• -EINVAL – General input / output error, failed to send over the bus.

int espi_read_lpc_request(const struct device *dev, enum lpc_peripheral_opcode op, uint32_t *data)
Reads SOC data from a LPC peripheral with information updated over eSPI.
This routine provides a generic interface to read a block whose information was updated by an eSPI transaction. Reading may trigger a transaction. The eSPI packet is assembled by the HW block.

Parameters
• dev – Pointer to the device structure for the driver instance.
• op – Enum representing opcode for peripheral type and read request.
• data – Parameter to be read from to the LPC peripheral.

Return values
• 0 – If successful.
• -ENOTSUP – if eSPI peripheral is off or not supported.
• -EINVAL – for unimplemented lpc opcode, but in range.

int espi_write_lpc_request(const struct device *dev, enum lpc_peripheral_opcode op, uint32_t *data)
Writes data to a LPC peripheral which generates an eSPI transaction.
This routine provides a generic interface to write data to a block which triggers an eSPI transaction. The eSPI packet is assembled by the HW block.

Parameters
• dev – Pointer to the device structure for the driver instance.
• op – Enum representing an opcode for peripheral type and write request.
• data – Represents the parameter passed to the LPC peripheral.
Return values

- 0 – If successful.
- -ENOTSUP – if eSPI peripheral is off or not supported.
- -EINVAL – for unimplemented lpc opcode, but in range.

```c
int espi_send_vwire(const struct device *dev, enum espivwire_signal signal, uint8_t level)
```

Sends system/platform signal as a virtual wire packet.

This routines provides a generic interface to send a virtual wire packet from slave to master.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `signal` – The signal to be send to eSPI master.
- `level` – The level of signal requested LOW or HIGH.

**Return values**

- 0 – If successful.
- -EIO – General input / output error, failed to send over the bus.

```c
int espi_receive_vwire(const struct device *dev, enum espivwire_signal signal, uint8_t *level)
```

Retrieves level status for a signal encapsulated in a virtual wire.

This routines provides a generic interface to request a virtual wire packet from eSPI master and retrieve the signal level.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `signal` – the signal to be requested from eSPI master.
- `level` – the level of signal requested 0b LOW, 1b HIGH.

**Return values**

- -EIO – General input / output error, failed request to master.

```c
int espi_send_oob(const struct device *dev, struct espioob_packet *pckt)
```

Sends SMBus transaction (out-of-band) packet over eSPI bus.

This routines provides an interface to encapsulate a SMBus transaction and send into packet over eSPI bus

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `pckt` – Address of the packet representation of SMBus transaction.

**Return values**

- -EIO – General input / output error, failed request to master.

```c
int espi_receive_oob(const struct device *dev, struct espioob_packet *pckt)
```

Receives SMBus transaction (out-of-band) packet from eSPI bus.

This routines provides an interface to receive and decoded a SMBus transaction from eSPI bus

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
• \texttt{pckt} – Address of the packet representation of SMBus transaction.

\textbf{Return values}

- \texttt{-EIO} – General input / output error, failed request to master.

\begin{verbatim}
int espi_read_flash(const struct device *dev, struct espi_flash_packet *pckt)
\end{verbatim}

Sends a read request packet for shared flash.

This routines provides an interface to send a request to read the flash component shared between the eSPI master and eSPI slaves.

\textbf{Parameters}

• \texttt{dev} – Pointer to the device structure for the driver instance.

• \texttt{pckt} – Address of the representation of read flash transaction.

\textbf{Return values}

- \texttt{-ENOTSUP} – eSPI flash logical channel transactions not supported.

- \texttt{-EBUSY} – eSPI flash channel is not ready or disabled by master.

- \texttt{-EIO} – General input / output error, failed request to master.

\begin{verbatim}
int espi_write_flash(const struct device *dev, struct espi_flash_packet *pckt)
\end{verbatim}

Sends a write request packet for shared flash.

This routines provides an interface to send a request to write to the flash components shared between the eSPI master and eSPI slaves.

\textbf{Parameters}

• \texttt{dev} – Pointer to the device structure for the driver instance.

• \texttt{pckt} – Address of the representation of write flash transaction.

\textbf{Return values}

- \texttt{-ENOTSUP} – eSPI flash logical channel transactions not supported.

- \texttt{-EBUSY} – eSPI flash channel is not ready or disabled by master.

- \texttt{-EIO} – General input / output error, failed request to master.

\begin{verbatim}
int espi_flash_erase(const struct device *dev, struct espi_flash_packet *pckt)
\end{verbatim}

Sends a write request packet for shared flash.

This routines provides an interface to send a request to write to the flash components shared between the eSPI master and eSPI slaves.

\textbf{Parameters}

• \texttt{dev} – Pointer to the device structure for the driver instance.

• \texttt{pckt} – Address of the representation of write flash transaction.

\textbf{Return values}

- \texttt{-ENOTSUP} – eSPI flash logical channel transactions not supported.

- \texttt{-EBUSY} – eSPI flash channel is not ready or disabled by master.

- \texttt{-EIO} – General input / output error, failed request to master.

\begin{verbatim}
static inline void espi_init_callback(struct espi_callback *callback, espi_callback_handler_t handler, enum espi_bus_event evt_type)
\end{verbatim}

Callback model.
Helper to initialize a struct `espi_callback` properly.

**Parameters**

- `callback` – A valid Application’s callback structure pointer.
- `handler` – A valid handler function pointer.

---

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• **evt_type** – indicates the eSPI event relevant for the handler. for VWIRE_RECEIVED event the data will indicate the new level asserted

```c
static inline int espi_add_callback(const struct device *dev, struct espi_callback *callback)
```

Add an application callback.

Note: enables to add as many callback as needed on the same device.

---

**Note:** Callbacks may be added to the device from within a callback handler invocation, but whether they are invoked for the current eSPI event is not specified.

---

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
- **callback** – A valid Application’s callback structure pointer.

**Returns**

0 if successful, negative errno code on failure.

```c
static inline int espi_remove_callback(const struct device *dev, struct espi_callback *callback)
```

Remove an application callback.

Note: enables to remove as many callbacks as added through `espi_add_callback()`.

---

**Warning:** It is explicitly permitted, within a callback handler, to remove the registration for the callback that is running, i.e. `callback`. Attempts to remove other registrations on the same device may result in undefined behavior, including failure to invoke callbacks that remain registered and unintended invocation of removed callbacks.

---

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
- **callback** – A valid application’s callback structure pointer.

**Returns**

0 if successful, negative errno code on failure.

```c
int espi_saf_config(const struct device *dev, const struct espi_saf_cfg *cfg)
```

Configure operation of a eSPI controller.

This routine provides a generic interface to override eSPI controller capabilities.

If this eSPI controller is acting as slave, the values set here will be discovered as part through the GET_CONFIGURATION command issued by the eSPI master during initialization.

If this eSPI controller is acting as master, the values set here will be used by eSPI master to determine minimum common capabilities with eSPI slave then send via SET_CONFIGURATION command.
Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `cfg` – the device runtime configuration for the eSPI controller.

Return values

- 0 – If successful.
- -EIO – General input / output error, failed to configure device.
- -EINVAL – invalid capabilities, failed to configure device.
- -ENOTSUP – capability not supported by eSPI slave.

```
int espi_saf_set_protection_regions(const struct device *dev, const struct espi_saf_protection *pr)
```

Set one or more SAF protection regions.

This routine provides an interface to override the default flash protection regions of the SAF controller.

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `pr` – Pointer to the SAF protection region structure.

Return values

- 0 – If successful.
- -EIO – General input / output error, failed to configure device.
- -EINVAL – invalid capabilities, failed to configure device.
- -ENOTSUP – capability not supported by eSPI slave.

```
int espi_saf_activate(const struct device *dev)
```

Activate SAF block.

This routine activates the SAF block and should only be called after SAF has been configured and the eSPI Master has enabled the Flash Channel.
Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – If successful
• -EINVAL – if failed to activate SAF.

```c
bool espi_saf_get_channel_status(const struct device *dev)
```

Query to see if SAF is ready.
This routine allows to check if SAF is ready before use.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• true – If eSPI SAF is ready.
• false – otherwise.

```c
int espi_saf_flash_read(const struct device *dev, struct espi_saf_packet *pckt)
```

Sends a read request packet for slave attached flash.
This routine provides an interface to send a request to read the flash component shared between the eSPI master and eSPI slaves.

Parameters
• dev – Pointer to the device structure for the driver instance.
• pckt – Address of the representation of read flash transaction.

Return values
• -ENOTSUP – eSPI flash logical channel transactions not supported.
• -EBUSY – eSPI flash channel is not ready or disabled by master.
• -EIO – General input / output error, failed request to master.

```c
int espi_saf_flash_write(const struct device *dev, struct espi_saf_packet *pckt)
```

Sends a write request packet for slave attached flash.
This routine provides an interface to send a request to write to the flash components shared between the eSPI master and eSPI slaves.

Parameters
• dev – Pointer to the device structure for the driver instance.
• pckt – Address of the representation of write flash transaction.

Return values
• -ENOTSUP – eSPI flash logical channel transactions not supported.
• -EBUSY – eSPI flash channel is not ready or disabled by master.
• -EIO – General input / output error, failed request to master.

```c
int espi_saf_flash_erase(const struct device *dev, struct espi_saf_packet *pckt)
```

Sends a write request packet for slave attached flash.
This routine provides an interface to send a request to write to the flash components shared between the eSPI master and eSPI slaves.

Parameters
• dev – Pointer to the device structure for the driver instance.
- `pckt` – Address of the representation of erase flash transaction.

**Return values**
- `-ENOTSUP` – eSPI flash logical channel transactions not supported.
- `-EBUSY` – eSPI flash channel is not ready or disabled by master.
- `-EIO` – General input / output error, failed request to master.

```c
int espi_saf_flash_unsuccess(const struct device *dev, struct espi_saf_packet *pckt)
```

Response unsuccessful completion for slave attached flash.

This routines provides an interface to response that transaction is invalid and return unsuccessful completion from target to controller.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.
- `pckt` – Address of the representation of flash transaction.

**Return values**
- `-ENOTSUP` – eSPI flash logical channel transactions not supported.
- `-EBUSY` – eSPI flash channel is not ready or disabled by master.
- `-EIO` – General input / output error, failed request to master.

```c
static inline void espi_saf_init_callback(struct espi_callback *callback,
                                        espi_callback_handler_t handler,
                                        enum espi_bus_event evt_type)
```

Callback model.

```
| App | | eSPI driver | | HW | |eSPI Host| |
+-----+ +-------+-----+ +---+--+ +----+----+
| espi_init_callback |
| espi_add_callback |
```

```plaintext
(continues on next page)
```

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Helper to initialize a struct espi_callback properly.

**Parameters**
- **callback** – A valid Application’s callback structure pointer.
- **handler** – A valid handler function pointer.
- **evt_type** – indicates the eSPI event relevant for the handler. For VWIRE_RECEIVED event the data will indicate the new level asserted.

```c
static inline int espi_saf_add_callback(const struct device *dev, struct espi_callback *callback)
```

Add an application callback.

Note: enables to add as many callback as needed on the same device.

**Note:** Callbacks may be added to the device from within a callback handler invocation, but whether they are invoked for the current eSPI event is not specified.

**Parameters**
- **dev** – Pointer to the device structure for the driver instance.
- **callback** – A valid Application’s callback structure pointer.

**Returns**
0 if successful, negative errno code on failure.

```c
static inline int espi_saf_remove_callback(const struct device *dev, struct espi_callback *callback)
```

Remove an application callback.

Note: enables to remove as many callbacks as added through `espi_add_callback()`.
Warning: It is explicitly permitted, within a callback handler, to remove the registration for the callback that is running, i.e. callback. Attempts to remove other registrations on the same device may result in undefined behavior, including failure to invoke callbacks that remain registered and unintended invocation of removed callbacks.

Parameters

- dev – Pointer to the device structure for the driver instance.
- callback – A valid application’s callback structure pointer.

Returns

0 if successful, negative errno code on failure.

```c
struct espi_evt_data_kbc
#include <espi.h> Bit field definition of evt_data in struct espi_event for KBC.

struct espi_evt_data_acpi
#include <espi.h> Bit field definition of evt_data in struct espi_event for ACPI.

struct espi_event
#include <espi.h> eSPI event
```

Public Members

```c
enum espi_bus_event evt_type
Event type.

uint32_t evt_details
Additional details for bus event type.

uint32_t evt_data
Data associated to the event.
```

```c
struct espi_cfg
#include <espi.h> eSPI bus configuration parameters
```

Public Members

```c
enum espi_io_mode io_caps
Supported I/O mode.

enum espi_channel channel_caps
Supported channels.

uint8_t max_freq
Maximum supported frequency in MHz.
```
struct espi_request_packet
    #include <espi.h> eSPI peripheral request packet format

struct espi_oob_packet
    #include <espi.h> eSPI out-of-band transaction packet format

struct espi_flash_packet
    #include <espi.h> eSPI flash transactions packet format

struct espi_saf_cfg
    #include <espi_saf.h> eSPI SAF configuration parameters

struct espi_saf_packet
    #include <espi_saf.h> eSPI SAF transaction packet format

### 7.6.17 Entropy

#### Overview

The entropy API provides functions to retrieve entropy values from entropy hardware present on the platform. The entropy APIs are provided for use by the random subsystem and cryptographic services. They are not suitable to be used as random number generation functions.

#### API Reference

**group entropy_interface**

Entropy Interface.

**Defines**

**ENTROPY_BUSYWAIT**

Driver is allowed to busy-wait for random data to be ready.

**Typedefs**

typedef int (*entropy_get_entropy_t)(const struct device *dev, uint8_t *buffer, uint16_t length)

Callback API to get entropy.

See `entropy_get_entropy()` for argument description

**Note:** This call has to be thread safe to satisfy requirements of the random subsystem.
typedef int (*entropy_get_entropy_isr_t)(const struct device *dev, uint8_t *buffer, uint16_t length, uint32_t flags)

Callback API to get entropy from an ISR.
See `entropy_get_entropy_isr()` for argument description.

**Functions**

`int entropy_get_entropy(const struct device *dev, uint8_t *buffer, uint16_t length)`

Fills a buffer with entropy.
Blocks if required in order to generate the necessary random data.

**Parameters**
- `dev` – Pointer to the entropy device.
- `buffer` – Buffer to fill with entropy.
- `length` – Buffer length.

**Return values**
- `0` – on success.
- `-ERRNO` – errno code on error.

`static inline int entropy_get_entropy_isr(const struct device *dev, uint8_t *buffer, uint16_t length, uint32_t flags)`

Fills a buffer with entropy in a non-blocking or busy-wait manner.
Callable from ISRs.

**Parameters**
- `dev` – Pointer to the device structure.
- `buffer` – Buffer to fill with entropy.
- `length` – Buffer length.
- `flags` – Flags to modify the behavior of the call.

**Return values**
- `number` – number of bytes filled with entropy or -error.

`struct entropy_driver_api`  
`#include <entropy.h>` Entropy driver API structure.
This is the mandatory API any Entropy driver needs to expose.

**7.6.18 Error Detection And Correction (EDAC)**

Error Detection And Correction is a mechanism used to detect and correct errors while storing or reading data.

**In Band Error Correction Code (IBECC)**

**Overview** The mechanism initially found in Intel Elkhart Lake SOCs and later boards is an integrated memory controller with IBECC.
The In-Band Error Correction Code (IBECC) improves reliability by providing error detection and correction. IBECC can work for all or for specific regions of physical memory space. The IBECC is useful for memory technologies that do not support the out-of-band ECC.

IBECC adds memory overhead of 1/32 of the memory. This memory is not accessible and used to store ECC syndrome data. IBECC converts read / write transactions to two separate transactions: one for actual data and another for cache line containing ECC value.

There is a debug feature IBECC Error Injection which helps to debug and verify IBECC functionality. ECC errors are injected on the write path and cause ECC errors on the read path.

**IBECC Configuration**  There are three IBECC operation modes which can be selected by Bootloader. They are listed below:

- OPERATION_MODE = 0x0 sets functional mode to protect requests based on address range
- OPERATION_MODE = 0x1 sets functional mode to all requests not be protected and to ignore range checks
- OPERATION_MODE = 0x2 sets functional mode to protect all requests and ignore range checks

IBECC operational mode is configured through BIOS or Bootloader. For operation mode 0 there are more BIOS configuration options such as memory regions.

Due to high security risk Error Injection capability should not be enabled for production. Error Injection is only enabled for tests.

**IBECC Logging**  IBECC logs the following fields:

- Error Address
- Error Syndrome
- Error Type
  - Correctable Error (CE) - error is detected and corrected by IBECC module.
  - Uncorrectable Error (UE) - error is detected by IBECC module and not automatically corrected.

The IBECC driver provides error type for the higher-level application to implement desired policy with respect for handling those memory errors. Error syndrome is not used in the IBECC driver but provided to higher-level application.

**Usage notes**  Exceptional care needs to be taken with Non Maskable Interrupt (NMI). NMI will arrive at any time, even if the local CPU has disabled interrupts. That means that no locking mechanism can protect code against an NMI happening. Zephyr’s IPC mechanisms universally use local IRQ locking as the base layer for all higher-level synchronization primitives. So, you cannot share anything that is “protected” by a lock with an NMI, because the protection does not work. The only tool you have available for synchronization in the Zephyr API that works against an NMI is the atomic layer. This also applies to callback function which is called by NMI handler.

**Configuration option**  Related configuration option:

- CONFIG_EDAC_IBECC
**Configuration option**

Related configuration option:
- CONFIG_EDAC

**API Reference**

**Related code samples**

**EDAC shell**
Test error detection and correction (EDAC) using shell commands.

```plaintext
group edac
```

**Optional interfaces**

EDAC Optional Interfaces

static inline int edac_inject_set_param1(const struct device *dev, uint64_t value)
Set injection parameter param1.

**Parameters**
- `dev` – Pointer to the device structure
- `value` – First injection parameter

**Return values**
- `-ENOSYS` – if the optional interface is not implemented
- `0` – on success, other error code otherwise

static inline int edac_inject_get_param1(const struct device *dev, uint64_t *value)
Get injection parameter param1.

Get first error injection parameter value.

**Parameters**
- `dev` – Pointer to the device structure
- `value` – Pointer to the first injection parameter

**Return values**
- `-ENOSYS` – if the optional interface is not implemented
- `0` – on success, error code otherwise

static inline int edac_inject_set_param2(const struct device *dev, uint64_t value)
Set injection parameter param2.

Set second error injection parameter value.

**Parameters**
- `dev` – Pointer to the device structure
- `value` – Second injection parameter
Return values

- ENOSYS – if the optional interface is not implemented
- 0 – on success, error code otherwise

static inline int edac_inject_get_param2(const struct device *dev, uint64_t *value)

Get injection parameter param2.

Parameters

- dev – Pointer to the device structure
- value – Pointer to the second injection parameter

Return values

- ENOSYS – if the optional interface is not implemented
- 0 – on success, error code otherwise

static inline int edac_inject_set_error_type(const struct device *dev, uint32_t error_type)

Set error type value.

Set the value of error type to be injected

Parameters

- dev – Pointer to the device structure
- error_type – Error type value

Return values

- ENOSYS – if the optional interface is not implemented
- 0 – on success, error code otherwise

static inline int edac_inject_get_error_type(const struct device *dev, uint32_t *error_type)

Get error type value.

Get the value of error type to be injected

Parameters

- dev – Pointer to the device structure
- error_type – Pointer to error type value

Return values

- ENOSYS – if the optional interface is not implemented
- 0 – on success, error code otherwise

static inline int edac_inject_error_trigger(const struct device *dev)

Set injection control.

Trigger error injection.

Parameters

- dev – Pointer to the device structure

Return values

- ENOSYS – if the optional interface is not implemented
- 0 – on success, error code otherwise
Mandatory interfaces

EDAC Mandatory Interfaces

static inline int edac_ecc_error_log_get(const struct device *dev, uint64_t *value)
Get ECC Error Log.
Read value of ECC Error Log.

Parameters
- dev – Pointer to the device structure
- value – Pointer to the ECC Error Log value

Return values
- 0 – on success, error code otherwise
- -ENOSYS – if the mandatory interface is not implemented

static inline int edac_ecc_error_log_clear(const struct device *dev)
Clear ECC Error Log.
Clear value of ECC Error Log.

Parameters
- dev – Pointer to the device structure

Return values
- 0 – on success, error code otherwise
- -ENOSYS – if the mandatory interface is not implemented

static inline int edac_parity_error_log_get(const struct device *dev, uint64_t *value)
Get Parity Error Log.
Read value of Parity Error Log.

Parameters
- dev – Pointer to the device structure
- value – Pointer to the parity Error Log value

Return values
- 0 – on success, error code otherwise
- -ENOSYS – if the mandatory interface is not implemented

static inline int edac_parity_error_log_clear(const struct device *dev)
Clear Parity Error Log.
Clear value of Parity Error Log.

Parameters
- dev – Pointer to the device structure

Return values
- 0 – on success, error code otherwise
- -ENOSYS – if the mandatory interface is not implemented

static inline int edac_errors_cor_get(const struct device *dev)
Get number of correctable errors.

Parameters
• dev – Pointer to the device structure

**Return values**

• num – Number of correctable errors
• -ENOSYS – if the mandatory interface is not implemented

static inline int edac_errors_uc_get(const struct device *dev)
Get number of uncorrectable errors.

**Parameters**

• dev – Pointer to the device structure

**Return values**

• num – Number of uncorrectable errors
• -ENOSYS – if the mandatory interface is not implemented

static inline int edac_notify_callback_set(const struct device *dev,
edac_notify_callback_f cb)
Register callback function for memory error exception.
This callback runs in interrupt context

**Parameters**

• dev – EDAC driver device to install callback
• cb – Callback function pointer

**Return values**

• 0 – on success, error code otherwise
• -ENOSYS – if the mandatory interface is not implemented

**Enums**

def edac_error_type
    EDAC error type.
    
    **Values:**
    
    • enumerator EDAC_ERROR_TYPE_DRAM_COR = BIT(0)
    Correctable error type.

    • enumerator EDAC_ERROR_TYPE_DRAM_UC = BIT(1)
    Uncorrectable error type.

**7.6.19 Flash**

**Overview**

**Flash offset concept**

Offsets used by the user API are expressed in relation to the flash memory beginning address. This rule shall be applied to all flash controller regular memory that layout is accessible via API for retrieving the layout of pages (see CONFIG_FLASH_PAGE_LAYOUT).
An exception from the rule may be applied to a vendor-specific flash dedicated-purpose region (such a region obviously can’t be covered under API for retrieving the layout of pages).

**User API Reference**

**Related code samples**

**AT45 DataFlash driver**
Use the AT45 family DataFlash driver to interact with the flash memory over SPI.

**ESP32 Flash Memory-Mapped**
Write data into scratch area and read it using flash API and memory-mapped pointer.

**Flash shell**
Explore a flash device using shell commands.

**JEDEC SPI-NOR flash**
Use the flash API to interact with an SPI NOR serial flash memory device.

**JESD216 flash**
Use the JESD216 flash API to extract information from a compatible serial memory device.

**nRF SoC flash**
Use the flash API to interact with the SoC flash.

```c
#include <zephyr/kernel.h>

#define FLASH_EX_OP_VENDOR_BASE
#define FLASH_EX_OP_IS_VENDOR(c)

typedef bool (*flash_page_cb)(const struct flash_pages_info *info, void *data)

callback type for iterating over flash pages present on a device.

The callback should return true to continue iterating, and false to halt.

See also:

flash_page_foreach()
```

**Param info**
Information for current page

**Param data**
Private data for callback

**Return**
True to continue iteration, false to halt iteration.
Enums

enum flash_ex_op_types
    Enumeration for extra flash operations.
    Values:

    enumerator FLASH_EX_OP_RESET = 0

Functions

int flash_read(const struct device *dev, off_t offset, void *data, size_t len)
    Read data from flash.
    All flash drivers support reads without alignment restrictions on the read offset, the
    read size, or the destination address.
    Parameters
        • dev – : flash dev
        • offset – : Offset (byte aligned) to read
        • data – : Buffer to store read data
        • len – : Number of bytes to read.
    Returns
        0 on success, negative errno code on fail.

int flash_write(const struct device *dev, off_t offset, const void *data, size_t len)
    Write buffer into flash memory.
    All flash drivers support a source buffer located either in RAM or SoC flash, without
    alignment restrictions on the source address. Write size and offset must be multiples
    of the minimum write block size supported by the driver.
    Any necessary write protection management is performed by the driver write imple-
    mentation itself.
    Parameters
        • dev – : flash device
        • offset – : starting offset for the write
        • data – : data to write
        • len – : Number of bytes to write
    Returns
        0 on success, negative errno code on fail.

int flash_erase(const struct device *dev, off_t offset, size_t size)
    Erase part or all of a flash memory.
    Acceptable values of erase size and offset are subject to hardware-specific multiples of
    page size and offset. Please check the API implemented by the underlying sub driver,
    for example by using flash_get_page_info_by_offs() if that is supported by your flash
    driver.
    Any necessary erase protection management is performed by the driver erase imple-
    mentation itself.
See also:
flash_get_page_info_by_offs()
See also:
flash_get_page_info_by_idx()

Parameters
- **dev** – flash device
- **offset** – erase area starting offset
- **size** – size of area to be erased

Returns
0 on success, negative errno code on fail.

```c
int flash_get_page_info_by_offs(const struct device *dev, off_t offset, struct flash_pages_info *info)
```

Get the size and start offset of flash page at certain flash offset.

Parameters
- **dev** – flash device
- **offset** – Offset within the page
- **info** – Page Info structure to be filled

Returns
0 on success, -EINVAL if page of the offset doesn’t exist.

```c
int flash_get_page_info_by_idx(const struct device *dev, uint32_t page_index, struct flash_pages_info *info)
```

Get the size and start offset of flash page of certain index.

Parameters
- **dev** – flash device
- **page_index** – Index of the page. Index are counted from 0.
- **info** – Page Info structure to be filled

Returns
0 on success, -EINVAL if page of the index doesn’t exist.

```c
size_t flash_get_page_count(const struct device *dev)
```

Get the total number of flash pages.

Parameters
- **dev** – flash device

Returns
Number of flash pages.

```c
void flash_page_foreach(const struct device *dev, flash_page_cb cb, void *data)
```

Iterate over all flash pages on a device.

This routine iterates over all flash pages on the given device, ordered by increasing start offset. For each page, it invokes the given callback, passing it the page’s information and a private data object.

Parameters
- **dev** – Device whose pages to iterate over
int flash_sfdp_read(const struct device *dev, off_t offset, void *data, size_t len)

Read data from Serial Flash Discoverable Parameters.

This routine reads data from a serial flash device compatible with the JEDEC JESD216 standard for encoding flash memory characteristics.

Availability of this API is conditional on selecting CONFIG_FLASH_JESD216_API and support of that functionality in the driver underlying dev.

Parameters
- dev – device from which parameters will be read
- offset – address within the SFDP region containing data of interest
- data – where the data to be read will be placed
- len – the number of bytes of data to be read

Return values
- 0 – on success
- -ENOTSUP – if the flash driver does not support SFDP access
- negative – values for other errors.

int flash_read_jedec_id(const struct device *dev, uint8_t *id)

Read the JEDEC ID from a compatible flash device.

Parameters
- dev – device from which id will be read
- id – pointer to a buffer of at least 3 bytes into which id will be stored

Return values
- 0 – on successful store of 3-byte JEDEC id
- -ENOTSUP – if flash driver doesn’t support this function
- negative – values for other errors

size_t flash_get_write_block_size(const struct device *dev)

Get the minimum write block size supported by the driver.

The write block size supported by the driver might differ from the write block size of memory used because the driver might implements write-modify algorithm.

Parameters
- dev – flash device

Returns
write block size in bytes.

const struct flash_parameters *flash_get_parameters(const struct device *dev)

Get pointer to flash_parameters structure.

Returned pointer points to a structure that should be considered constant through a runtime, regardless if it is defined in RAM or Flash. Developer is free to cache the structure pointer or copy its contents.

Returns
pointer to flash_parameters structure characteristic for the device.
Execute flash extended operation on given device.

Besides of standard flash operations like write or erase, flash controllers also support additional features like write protection or readout protection. These features are not available in every flash controller, what's more controllers can implement it in a different way.

It doesn't make sense to add a separate flash API function for every flash controller feature, because it could be unique (supported on small number of flash controllers) or the API won't be able to represent the same feature on every flash controller.

**Parameters**

- **dev** – Flash device
- **code** – Operation which will be executed on the device.
- **in** – Pointer to input data used by operation. If operation doesn't need any input data it could be NULL.
- **out** – Pointer to operation output data. If operation doesn't produce any output it could be NULL.

**Return values**

- 0 – on success.
- -ENOTSUP – if given device doesn't support extended operation.
- -ENOSYS – if support for extended operations is not enabled in Kconfig
- negative – value on extended operation errors.

```
struct flash_parameters

#include <flash.h> Flash memory parameters.

Contents of this structure suppose to be filled in during flash device initialization and stay constant through a runtime.

struct flash_pages_info

#include <flash.h>
```

**Implementation interface API Reference**

```
group flash_internal_interface

FLASH internal Interface.

**Typedefs**

typedef int (*flash_api_read)(const struct device *dev, off_t offset, void *data, size_t len)

typedef int (*flash_api_write)(const struct device *dev, off_t offset, const void *data, size_t len)

Flash write implementation handler type.
```
Note: Any necessary write protection management must be performed by the driver, with the driver responsible for ensuring the “write-protect” after the operation completes (successfully or not) matches the write-protect state when the operation was started.

typedef int (*flash_api_erase)(const struct device *dev, off_t offset, size_t size)

Flash erase implementation handler type.

Note: Any necessary erase protection management must be performed by the driver, with the driver responsible for ensuring the “erase-protect” after the operation completes (successfully or not) matches the erase-protect state when the operation was started.

typedef const struct flash_parameters *(*flash_api_get_parameters)(const struct device *dev)

typedef void (*flash_api_pages_layout)(const struct device *dev, const struct flash_pages_layout **layout, size_t *layout_size)

Retrieve a flash device's layout.

A flash device layout is a run-length encoded description of the pages on the device. (Here, “page” means the smallest erasable area on the flash device.)

For flash memories which have uniform page sizes, this routine returns an array of length 1, which specifies the page size and number of pages in the memory.

Layouts for flash memories with nonuniform page sizes will be returned as an array with multiple elements, each of which describes a group of pages that all have the same size. In this case, the sequence of array elements specifies the order in which these groups occur on the device.

**Param dev**
Flash device whose layout to retrieve.

**Param layout**
The flash layout will be returned in this argument.

**Param layout_size**
The number of elements in the returned layout.

typedef int (*flash_api_sfdp_read)(const struct device *dev, off_t offset, void *data, size_t len)

typedef int (*flash_api_read_jedec_id)(const struct device *dev, uint8_t *id)

typedef int (*flash_api_ex_op)(const struct device *dev, uint16_t code, const uintptr_t in, void *out)

struct flash_pages_layout
    #include <flash.h>

struct flash_driver_api
    #include <flash.h>
7.6.20 Fuel Gauge

The fuel gauge subsystem exposes an API to uniformly access battery fuel gauge devices. Currently, only reading data is supported.

Note: This API is currently experimental and this doc will be significantly changed as new features are added to the API.

Basic Operation

Properties Fundamentally, a property is a quantity that a fuel gauge device can measure. Fuel gauges typically support multiple properties, such as temperature readings of the battery-pack or present-time current/voltage.

Properties are fetched by the client one at a time using `fuel_gauge_get_prop()`, or fetched in a batch using `fuel_gauge_get_props()`.

Properties are set by the client one at a time using `fuel_gauge_set_prop()`, or set in a batch using `fuel_gauge_set_props()`.

Battery Cutoff Many fuel gauges embedded within battery packs expose a register address that when written to with a specific payload will do a battery cutoff. This battery cutoff is often referred to as ship, shelf, or sleep mode due to its utility in reducing battery drain while devices are stored or shipped.

The fuel gauge API exposes battery cutoff with the `fuel_gauge_battery_cutoff()` function.

Caching The Fuel Gauge API explicitly provides no caching for its clients.

API Reference

group fuel_gauge_interface

Fuel Gauge Interface.

Defines

SBS_GAUGE_MANUFACTURER_NAME_MAX_SIZE

Data structures for reading SBS buffer properties.

SBS_GAUGE_DEVICE_NAME_MAX_SIZE

SBS_GAUGE_DEVICE_CHEMISTRY_MAX_SIZE

Typedefs

typedef uint16_t fuel_gauge_prop_t
typedef int (*fuel_gauge_get_property_t)(const struct device *dev, fuel_gauge_prop_t prop, union fuel_gauge_prop_val *val)
    Callback API for getting a fuel_gauge property.
    See fuel_gauge_get_property() for argument description

typedef int (*fuel_gauge_set_property_t)(const struct device *dev, fuel_gauge_prop_t prop, union fuel_gauge_prop_val val)
    Callback API for setting a fuel_gauge property.
    See fuel_gauge_set_property() for argument description

typedef int (*fuel_gauge_get_buffer_property_t)(const struct device *dev, fuel_gauge_prop_t prop_type, void *dst, size_t dst_len)
    Callback API for getting a fuel_gauge buffer property.
    See fuel_gauge_get_buffer_property() for argument description

typedef int (*fuel_gauge_battery_cutoff_t)(const struct device *dev)
    Callback API for doing a battery cutoff.
    See fuel_gauge_battery_cutoff() for argument description

Enums

enum fuel_gauge_prop_type
    Values:

    enumerator FUEL_GAUGE_AVG_CURRENT = 0
        Runtime Dynamic Battery Parameters.
        Provide a 1 minute average of the current on the battery. Does not check for
        flags or whether those values are bad readings. See driver instance header for
        details on implementation and how the average is calculated. Units in uA nega-
        tive=discharging

    enumerator FUEL_GAUGE_BATTERY_CUTOFF
        Used to cutoff the battery from the system - useful for storage/shipping of devices.

    enumerator FUEL_GAUGE_CURRENT
        Battery current (uA); negative=discharging.

    enumerator FUEL_GAUGE_CHARGE_CUTOFF
        Whether the battery underlying the fuel-gauge is cut off from charge.

    enumerator FUEL_GAUGE_CYCLE_COUNT
        Cycle count in 1/100ths (number of charge/discharge cycles)

    enumerator FUEL_GAUGE_CONNECT_STATE
        Connect state of battery.
enumerator FUEL_GAUGE_FLAGS
    General Error/Runtime Flags.

enumerator FUEL_GAUGE_FULL_CHARGE_CAPACITY
    Full Charge Capacity in uAh (might change in some implementations to determine wear)

enumerator FUEL_GAUGE_PRESENT_STATE
    Is the battery physically present.

enumerator FUEL_GAUGE_REMAINING_CAPACITY
    Remaining capacity in uAh.

enumerator FUEL_GAUGE_RUNTIME_TOEMPTY
    Remaining battery life time in minutes.

enumerator FUEL_GAUGE_RUNTIME_TOFULL
    Remaining time in minutes until battery reaches full charge.

enumerator FUEL_GAUGE_SBS_MFR_ACCESS
    Retrieve word from SBS1.1 ManufacturerAccess.

enumerator FUEL_GAUGE_ABSOLUTE_STATE_OF_CHARGE
    Absolute state of charge (percent, 0-100) - expressed as % of design capacity.

enumerator FUEL_GAUGE_RELATIVE_STATE_OF_CHARGE
    Relative state of charge (percent, 0-100) - expressed as % of full charge capacity.

enumerator FUEL_GAUGE_TEMPERATURE
    Temperature in 0.1 K.

enumerator FUEL_GAUGE_VOLTAGE
    Battery voltage (uV)

enumerator FUEL_GAUGE_SBS_MODE
    Battery Mode (flags)

enumerator FUEL_GAUGE_CHARGE_CURRENT
    Battery desired Max Charging Current (uA)

enumerator FUEL_GAUGE_CHARGE_VOLTAGE
    Battery desired Max Charging Voltage (uV)

enumerator FUEL_GAUGE_STATUS
    Alarm, Status and Error codes (flags)

enumerator FUEL_GAUGE_DESIGN_CAPACITY
    Design Capacity (mAh or 10mWh)
enumerator FUEL_GAUGE_DESIGN_VOLTAGE
    Design Voltage (mV)

enumerator FUEL_GAUGE_SBS_ATRATE
    AtRate (mA or 10 mW)

counter FUEL_GAUGE_SBS_ATRATE_TIME_TO_FULL
    AtRateTimeToFull (minutes)

counter FUEL_GAUGE_SBS_ATRATE_TIME_TO_EMPTY
    AtRateTimeToEmpty (minutes)

counter FUEL_GAUGE_SBS_ATRATE_OK
    AtRateOK (boolean)

counter FUEL_GAUGE_SBS_REMAINING_CAPACITY_ALARM
    Remaining Capacity Alarm (mAh or 10mWh)

counter FUEL_GAUGE_SBS_REMAINING_TIME_ALARM
    Remaining Time Alarm (minutes)

counter FUEL_GAUGE_MANUFACTURER_NAME
    Manufacturer of pack (1 byte length + 20 bytes data)

counter FUEL_GAUGE_DEVICE_NAME
    Name of pack (1 byte length + 20 bytes data)

counter FUEL_GAUGE_DEVICE_CHEMISTRY
    Chemistry (1 byte length + 4 bytes data)

counter FUEL_GAUGE_COMMON_COUNT
    Reserved to demark end of common fuel gauge properties.

counter FUEL_GAUGE_CUSTOM_BEGIN
    Reserved to demark downstream custom properties - use this value as the actual value may change over future versions of this API.

counter FUEL_GAUGE_PROP_MAX = UINT16_MAX
    Reserved to demark end of valid enum properties.

Functions

int fuel_gauge_get_prop(const struct device *dev, fuel_gauge_prop_t prop, union fuel_gauge_prop_val *val)

Fetch a battery fuel-gauge property.

Parameters

- dev – Pointer to the battery fuel-gauge device
- prop – Type of property to be fetched from device
• val – pointer to a union `fuel_gauge_prop_val` where the property is read into from the fuel gauge device.

**Returns**

0 if successful, negative errno code if failure.

```c
int fuel_gauge_get_props(const struct device *dev, fuel_gauge_prop_t *props, union fuel_gauge_prop_val *vals, size_t len)
```

Fetch multiple battery fuel-gauge properties.

The default implementation is the same as calling `fuel_gauge_get_prop()` multiple times. A driver may implement the get_properties field of the fuel gauge driver APIs struct to override this implementation.

**Parameters**

- dev – Pointer to the battery fuel-gauge device
- props – Array of the type of property to be fetched from device, each index corresponds to the same index of the vals input array.
- vals – Pointer to array of union `fuel_gauge_prop_val` where the property is read into from the fuel gauge device. The vals array is not permuted.
- len – number of properties in props & vals array

**Returns**

0 if successful, negative errno code of first failing property

```c
int fuel_gauge_set_prop(const struct device *dev, fuel_gauge_prop_t prop, union fuel_gauge_prop_val val)
```

Set a battery fuel-gauge property.

**Parameters**

- dev – Pointer to the battery fuel-gauge device
- prop – Type of property that’s being set
- val – Value to set associated prop property.

**Returns**

0 if successful, negative errno code of first failing property

```c
int fuel_gauge_set_props(const struct device *dev, fuel_gauge_prop_t *props, union fuel_gauge_prop_val *vals, size_t len)
```

Set a battery fuel-gauge property.

**Parameters**

- dev – Pointer to the battery fuel-gauge device
- props – Array of the type of property to be set, each index corresponds to the same index of the vals input array.
- vals – Pointer to array of union `fuel_gauge_prop_val` where the property is written the fuel gauge device. The vals array is not permuted.
- len – number of properties in props array

**Returns**

`return=0` if successful. Otherwise, return array index of failing property.

```c
int fuel_gauge_get_buffer_prop(const struct device *dev, fuel_gauge_prop_t prop_type, void *dst, size_t dst_len)
```

Fetch a battery fuel-gauge buffer property.

**Parameters**
• dev – Pointer to the battery fuel-gauge device
• prop_type – Type of property to be fetched from device
• dst – byte array or struct that will hold the buffer data that is read from
  the fuel gauge
• dst_len – the length of the destination array in bytes

Returns
return=0 if successful, return < 0 if getting property failed, return 0 on suc-
cess

int fuel_gauge_battery_cutoff(const struct device *dev)
Have fuel gauge cutoff its associated battery.

Parameters
• dev – Pointer to the battery fuel-gauge device

Returns
return=0 if successful and battery cutoff is now in process, return < 0 if
failed to do battery cutoff.

union fuel_gauge_prop_val
#include <fuel_gauge.h> Property field to value/type union.

Public Members

int avg_current
    FUEL_GAUGE_AVG_CURRENT.

bool cutoff
    FUEL_GAUGE_CHARGE_CUTOFF.

int current
    FUEL_GAUGE_CURRENT.

uint32_t cycle_count
    FUEL_GAUGE_CYCLE_COUNT.

uint32_t flags
    FUEL_GAUGE_FLAGS.

uint32_t full_charge_capacity
    FUEL_GAUGE_FULL_CHARGE_CAPACITY.

uint32_t remaining_capacity
    FUEL_GAUGE_REMAINING_CAPACITY.

uint32_t runtime_to_empty
    FUEL_GAUGE_RUNTIME_TO_EMPTY.

uint32_t runtime_to_full
    FUEL_GAUGE_RUNTIME_TO_FULL.
uint16_t sbs_mfr_access_word
    FUEL_GAUGE_SBS_MFR_ACCESS.

uint8_t absolute_state_of_charge
    FUEL_GAUGE_ABSOLUTE_STATE_OF_CHARGE.

uint8_t relative_state_of_charge
    FUEL_GAUGE_RELATIVE_STATE_OF_CHARGE.

uint16_t temperature
    FUEL_GAUGE_TEMPERATURE.

int voltage
    FUEL_GAUGE_VOLTAGE.

uint16_t sbs_mode
    FUEL_GAUGE_SBS_MODE.

uint32_t chg_current
    FUEL_GAUGE_CHARGE_CURRENT.

uint32_t chg_voltage
    FUEL_GAUGE_CHARGE_VOLTAGE.

uint16_t fg_status
    FUEL_GAUGE_STATUS.

uint16_t design_cap
    FUEL_GAUGE_DESIGN_CAPACITY.

uint16_t design_volt
    FUEL_GAUGE_DESIGN_VOLTAGE.

int16_t sbs_at_rate
    FUEL_GAUGE_SBS_ATRATE.

uint16_t sbs_at_rate_time_to_full
    FUEL_GAUGE_SBS_ATRATE_TIME_TO_FULL.

uint16_t sbs_at_rate_time_to_empty
    FUEL_GAUGE_SBS_ATRATE_TIME_TO_EMPTY

bool sbs_at_rate_ok
    FUEL_GAUGE_SBS_ATRATE_OK.

uint16_t sbs_remaining_capacity_alarm
    FUEL_GAUGE_SBS_REMAINING_CAPACITY_ALARM.
uint16_t sbs_remaining_time_alarm
    FUEL_GAUGE_SBS_REMAINING_TIME_ALARM.

struct sbs_gauge_manufacturer_name
    #include <fuel_gauge.h>

struct sbs_gauge_device_name
    #include <fuel_gauge.h>

struct sbs_gauge_device_chemistry
    #include <fuel_gauge.h>

struct fuel_gauge_driver_api
    #include <fuel_gauge.h>

Public Members

fuel_gauge_get_property_t get_property
    Note: Historically this API allowed drivers to implement a custom multi-get/set property function, this was added so drivers could potentially optimize batch read with their specific chip.

    However, it was removed because of no existing concrete case upstream. If this need is demonstrated, we can add this back in as an API field.

Functions

int emul_fuel_gauge_set_battery_charging(const struct emul *target, uint32_t uV, int uA)
    Set charging for fuel gauge associated battery.

    Set how much the battery associated with a fuel gauge IC is charging or discharging. Where voltage is always positive and a positive or negative current denotes charging or discharging, respectively.

    Parameters
    • target – Pointer to the emulator structure for the fuel gauge emulator instance.
    • uV – Microvolts describing the battery voltage.
    • uA – Microamps describing the battery current where negative is discharging.

    Return values
    • 0 – If successful.
    • -EINVAL – if mV or mA are 0.
int emul_fuel_gauge_is_battery_cutoff(const struct emul *target, bool *cutoff)
Check if the battery has been cut off.

Parameters
• target – Pointer to the emulator structure for the fuel gauge emulator instance.
• cutoff – Pointer to bool storing variable.

Return values
• 0 – If successful.
• -ENOTSUP – if not supported by emulator.

7.6.21 GNSS (Global Navigation Satellite System)

Overview

GNSS is a general term which covers satellite systems used for navigation, like GPS (Global Positioning System). GNSS services are usually accessed through GNSS modems which receive and process GNSS signals to determine their position, or more specifically, their antennas position. They usually additionally provide a precise time synchronization mechanism, commonly named PPS (Pulse-Per-Second).

Subsystem support

The GNSS subsystem is based on the Modem modules. The GNSS subsystem covers everything from sending and receiving commands to and from the modem, to parsing, creating and processing NMEA0183 messages.

Adding support for additional NMEA0183 based GNSS modems requires little more than implementing power management and configuration for the specific GNSS modem.

Adding support for GNSS modems which use other protocols and/or busses than the usual NMEA0183 over UART is possible, but will require a bit more work from the driver developer.

Configuration Options

Related configuration options:
• CONFIG_GNSS
• CONFIG_GNSS_SATELLITES
• CONFIG_GNSS_DUMP_TO_LOG

Navigation Reference

Related code samples
GNSS
Connect to a GNSS device to obtain time, navigation data, and satellite information.

group navigation
Navigation utilities.
Functions

```c
int navigation_distance(uint64_t *distance, const struct navigation_data *p1, const struct navigation_data *p2)
```

Calculate the distance between two navigation points along the surface of the sphere they are relative to.

**Parameters**
- `distance` – Destination for calculated distance in millimeters
- `p1` – First navigation point
- `p2` – Second navigation point

**Returns**
- 0 if successful
- -EINVAL if either navigation point is invalid

```c
int navigation_bearing(uint32_t *bearing, const struct navigation_data *from, const struct navigation_data *to)
```

Calculate the bearing from one navigation point to another.

**Parameters**
- `bearing` – Destination for calculated bearing angle in millidegrees
- `from` – First navigation point
- `to` – Second navigation point

**Returns**
- 0 if successful
- -EINVAL if either navigation point is invalid

```c
struct navigation_data

#include <navigation.h> Navigation data structure.
```

The structure describes the momentary navigation details of a point relative to a sphere (commonly Earth)

**Public Members**

```c
int64_t latitude
    Latitudal position in nanodegrees (0 to +-180E9)
```

```c
int64_t longitude
    Longitudal position in nanodegrees (0 to +-180E9)
```

```c
uint32_t bearing
    Bearing angle in millidegrees (0 to 360E3)
```

```c
uint32_t speed
    Speed in millimeters per second.
```
int32_t altitude
Altitude in millimeters.

GNSS API Reference

Related code samples

GNSS
Connect to a GNSS device to obtain time, navigation data, and satellite information.

> **group** gnss_interface
GNSS Interface.

**Defines**

GNSS_DATA_CALLBACK_DEFINE(_dev, _callback)
Register a callback structure for GNSS data published.

**Parameters**

- _dev – Device pointer
- _callback – The callback function

GNSS_SATELLITES_CALLBACK_DEFINE(_dev, _callback)
Register a callback structure for GNSS satellites published.

**Parameters**

- _dev – Device pointer
- _callback – The callback function

**Typedefs**

typedef int (*gnss_set_fix_rate_t)(const struct device *dev, uint32_t fix_interval_ms)
API for setting fix rate.

typedef int (*gnss_get_fix_rate_t)(const struct device *dev, uint32_t *fix_interval_ms)
API for getting fix rate.

typedef int (*gnss_set_periodic_config_t)(const struct device *dev, const struct gnss_periodic_config *periodic_config)
API for setting periodic tracking configuration.

typedef int (*gnss_get_periodic_config_t)(const struct device *dev, struct gnss_periodic_config *periodic_config)
API for setting periodic tracking configuration.

typedef int (*gnss_set_navigation_mode_t)(const struct device *dev, enum gnss_navigation_mode mode)
API for setting navigation mode.
typedef int (*gnss_get_navigation_mode_t)(const struct device *dev, enum gnss_navigation_mode *mode)
    API for getting navigation mode.

typedef uint32_t gnss_systems_t
    Type storing bitmask of GNSS systems.

typedef int (*gnss_set_enabled_systems_t)(const struct device *dev, gnss_systems_t systems)
    API for enabling systems.

typedef int (*gnss_get_enabled_systems_t)(const struct device *dev, gnss_systems_t *systems)
    API for getting enabled systems.

typedef int (*gnss_get_supported_systems_t)(const struct device *dev, gnss_systems_t *systems)
    API for getting enabled systems.

typedef void (*gnss_data_callback_t)(const struct device *dev, const struct gnss_data *data)
    Template for GNSS data callback.

typedef void (*gnss_satellites_callback_t)(const struct device *dev, const struct gnss_satellite *satellites, uint16_t size)
    Template for GNSS satellites callback.

Enums

enum gnss_pps_mode
    GNSS PPS modes.
    Values:
    
    enumerator GNSS_PPS_MODE_DISABLED = 0
        PPS output disabled.

    enumerator GNSS_PPS_MODE_ENABLED = 1
        PPS output always enabled.

    enumerator GNSS_PPS_MODE_ENABLED_AFTER_LOCK = 2
        PPS output enabled from first lock.

    enumerator GNSS_PPS_MODE_ENABLED_WHILE_LOCKED = 3
        PPS output enabled while locked.

enum gnss_navigation_mode
    GNSS navigation modes.
    Values:
enumerator GNSS_NAVIGATION_MODE_ZERO_DYNAMICS = 0
Dynamics have no impact on tracking.

denumerator GNSS_NAVIGATION_MODE_LOW_DYNAMICS = 1
Low dynamics have higher impact on tracking.

denumerator GNSS_NAVIGATION_MODE_BALANCED_DYNAMICS = 2
Low and high dynamics have equal impact on tracking.

denumerator GNSS_NAVIGATION_MODE_HIGH_DYNAMICS = 3
High dynamics have higher impact on tracking.

enum gnss_system
Systems contained in gnss_systems_t.
Values:

denumerator GNSS_SYSTEM_GPS = BIT(0)
Global Positioning System (GPS)

denumerator GNSS_SYSTEM_GLONASS = BIT(1)
GLObal NAvigation Satellite System (GLONASS)

denumerator GNSS_SYSTEM_GALILEO = BIT(2)
Galileo.

denumerator GNSS_SYSTEM_BEIDOU = BIT(3)
BeiDou Navigation Satellite System.

denumerator GNSS_SYSTEM_QZSS = BIT(4)
Quasi-Zenith Satellite System (QZSS)

denumerator GNSS_SYSTEM_IRNSS = BIT(5)
Indian Regional Navigation Satellite System (IRNSS)

denumerator GNSS_SYSTEM_SBAS = BIT(6)
Satellite-Based Augmentation System (SBAS)

denumerator GNSS_SYSTEM_IMES = BIT(7)
Indoor Messaging System (IMES)

enum gnss_fix_status
GNSS fix status.
Values:

denumerator GNSS_FIX_STATUS_NO_FIX = 0
No GNSS fix acquired.
enumerator GNSS_FIX_STATUS_GNSS_FIX = 1
    GNSS fix acquired.

enumerator GNSS_FIX_STATUS_DGNSS_FIX = 2
    Differential GNSS fix acquired.

enumerator GNSS_FIX_STATUS_ESTIMATED_FIX = 3
    Estimated fix acquired.

enum gnss_fix_quality
    GNSS fix quality.
    Values:

    enumerator GNSS_FIX_QUALITY_INVALID = 0
        Invalid fix.

    enumerator GNSS_FIX_QUALITY_GNSS_SPS = 1
        Standard positioning service.

    enumerator GNSS_FIX_QUALITY_DGNSS = 2
        Differential GNSS.

    enumerator GNSS_FIX_QUALITY_GNSS_PPS = 3
        Precise positioning service.

    enumerator GNSS_FIX_QUALITY_RTK = 4
        Real-time kinematic.

    enumerator GNSS_FIX_QUALITY_FLOAT_RTK = 5
        Floating real-time kinematic.

    enumerator GNSS_FIX_QUALITY_ESTIMATED = 6
        Estimated fix.

Functions

int gnss_set_fix_rate(const struct device *dev, uint32_t fix_interval_ms)
    Set the GNSS fix rate.

Parameters
    • dev – Device instance
    • fix_interval_ms – Fix interval to set in milliseconds

Returns
    0 if successful

Returns
    -errno negative errno code on failure
int gnss_get_fix_rate(const struct device *dev, uint32_t *fix_interval_ms)
Get the GNSS fix rate.

Parameters
• dev – Device instance
• fix_interval_ms – Destination for fix interval in milliseconds

Returns
0 if successful

Returns
-errno negative errno code on failure

int gnss_set_periodic_config(const struct device *dev, const struct gnss_periodic_config *config)
Set the GNSS periodic tracking configuration.

Parameters
• dev – Device instance
• config – Periodic tracking configuration to set

Returns
0 if successful

Returns
-errno negative errno code on failure

int gnss_get_periodic_config(const struct device *dev, struct gnss_periodic_config *config)
Get the GNSS periodic tracking configuration.

Parameters
• dev – Device instance
• config – Destination for periodic tracking configuration

Returns
0 if successful

Returns
-errno negative errno code on failure

int gnss_set_navigation_mode(const struct device *dev, enum gnss_navigation_mode mode)
Set the GNSS navigation mode.

Parameters
• dev – Device instance
• mode – Navigation mode to set

Returns
0 if successful

Returns
-errno negative errno code on failure

int gnss_get_navigation_mode(const struct device *dev, enum gnss_navigation_mode *mode)
Get the GNSS navigation mode.

Parameters
• dev – Device instance
int gnss_set_enabled_systems(const struct device *dev, gnss_systems_t systems)
Set enabled GNSS systems.
Parameters
• dev – Device instance
• systems – Systems to enable
Returns
0 if successful
-errno negative errno code on failure

int gnss_get_enabled_systems(const struct device *dev, gnss_systems_t *systems)
Get enabled GNSS systems.
Parameters
• dev – Device instance
• systems – Destination for enabled systems
Returns
0 if successful
-errno negative errno code on failure

int gnss_get_supported_systems(const struct device *dev, gnss_systems_t *systems)
Get supported GNSS systems.
Parameters
• dev – Device instance
• systems – Destination for supported systems
Returns
0 if successful
-errno negative errno code on failure

struct gnss_periodic_config
#include <gnss.h> GNSS periodic tracking configuration.

Note: Setting either active_time or inactive_time to 0 will disable periodic function.

Public Members

double active_time_ms
The time the GNSS will spend in the active state in ms.
uint32_t inactive_time_ms
   The time the GNSS will spend in the inactive state in ms.

struct gnss_info
   #include <gnss.h> GNSS info data structure.

   Public Members

   uint16_t satellites_cnt
      Number of satellites being tracked.

   uint16_t hdop
      Horizontal dilution of precision in 1/1000.

enum gnss_fix_status fix_status
   The fix status.

enum gnss_fix_quality fix_quality
   The fix quality.

struct gnss_time
   #include <gnss.h> GNSS time data structure.

   Public Members

   uint8_t hour
      Hour [0, 23].

   uint8_t minute
      Minute [0, 59].

   uint16_t millisecond
      Millisecond [0, 59999].

   uint8_t month_day
      Day of month [1, 31].

   uint8_t month
      Month [1, 12].

   uint8_t century_year
      Year [0, 99].

struct gnss_driver_api
   #include <gnss.h> GNSS API structure.

struct gnss_data
   #include <gnss.h> GNSS data structure.

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Public Members

struct navigation_data nav_data
    Navigation data acquired.

struct gnss_info info
    GNSS info when navigation data was acquired.

struct gnss_time utc
    UTC time when data was acquired.

struct gnss_data_callback
    #include <gnss.h> GNSS callback structure.

Public Members

const struct device *dev
    Filter callback to GNSS data from this device if not NULL.

gnss_data_callback_t callback
    Callback called when GNSS data is published.

struct gnss_satellite
    #include <gnss.h> GNSS satellite structure.

Public Members

uint8_t prn
    Pseudo-random noise sequence.

uint8_t snr
    Signal-to-noise ratio in dB.

uint8_t elevation
    Elevation in degrees [0, 90].

uint16_t azimuth
    Azimuth relative to True North in degrees [0, 359].

dui8_t is_tracked
    True if satellite is being tracked.

struct gnss_satellites_callback
    #include <gnss.h> GNSS callback structure.
Public Members

const struct device *dev
    Filter callback to GNSS data from this device if not NULL.

gnss_satellites_callback_t callback
    Callback called when GNSS satellites is published.

7.6.22 General-Purpose Input/Output (GPIO)

Overview

Configuration Options

Related configuration options:

- CONFIG_GPIO

API Reference

Related code samples

Basic thread manipulation
    Spawn multiple threads that blink LEDs and print information to the console.

Blinky
    Blink an LED forever using the GPIO API.

Button
    Handle GPIO inputs with interrupts.

GPIO with custom Devicetree binding
    Use custom Devicetree binding to control a GPIO.

HD44780 LCD controller
    Control an HD44780-based LCD display using GPIO pins.

X-NUCLEO-53L0A1 shield
    Interact with the 7-segment display and VL53L0X ranging sensor of an X-NUCLEO-53L0A1 shield.

# group gpio_interface
    GPIO Driver APIs.

    GPIO input/output configuration flags

    GPIO_INPUT
        Enables pin as input.

    GPIO_OUTPUT
        Enables pin as output, no change to the output state.
GPIO_DISCONNECTED
Disables pin for both input and output.

GPIO_OUTPUT_LOW
Configures GPIO pin as output and initializes it to a low state.

GPIO_OUTPUT_HIGH
Configures GPIO pin as output and initializes it to a high state.

GPIO_OUTPUT_INACTIVE
Configures GPIO pin as output and initializes it to a logic 0.

GPIO_OUTPUT_ACTIVE
Configures GPIO pin as output and initializes it to a logic 1.

**GPIO interrupt configuration flags**

The GPIO_INT_* flags are used to specify how input GPIO pins will trigger interrupts. The interrupts can be sensitive to pin physical or logical level. Interrupts sensitive to pin logical level take into account GPIO_ACTIVE_LOW flag. If a pin was configured as Active Low, physical level low will be considered as logical level 1 (an active state), physical level high will be considered as logical level 0 (an inactive state). The GPIO controller should reset the interrupt status, such as clearing the pending bit, etc, when configuring the interrupt triggering properties. Applications should use the GPIO_INT_MODE_ENABLE_ONLY and GPIO_INT_MODE_DISABLE_ONLY flags to enable and disable interrupts on the pin without changing any GPIO settings.

GPIO_INT_DISABLE
Disables GPIO pin interrupt.

GPIO_INT_EDGE_RISING
Configures GPIO interrupt to be triggered on pin rising edge and enables it.

GPIO_INT_EDGE_FALLING
Configures GPIO interrupt to be triggered on pin falling edge and enables it.

GPIO_INT_EDGE_BOTH
Configures GPIO interrupt to be triggered on pin rising or falling edge and enables it.

GPIO_INT_LEVEL_LOW
Configures GPIO interrupt to be triggered on pin physical level low and enables it.

GPIO_INT_LEVEL_HIGH
Configures GPIO interrupt to be triggered on pin physical level high and enables it.

GPIO_INT_EDGE_TO_INACTIVE
Configures GPIO interrupt to be triggered on pin state change to logical level 0 and enables it.
GPIO_INT_EDGE_TO_ACTIVE
    Configures GPIO interrupt to be triggered on pin state change to logical level 1 and enables it.

GPIO_INT_LEVEL_INACTIVE
    Configures GPIO interrupt to be triggered on pin logical level 0 and enables it.

GPIO_INT_LEVEL_ACTIVE
    Configures GPIO interrupt to be triggered on pin logical level 1 and enables it.

GPIO pin active level flags

GPIO_ACTIVE_LOW
    GPIO pin is active (has logical value ‘1’) in low state.

GPIO_ACTIVE_HIGH
    GPIO pin is active (has logical value ‘1’) in high state.

GPIO pin drive flags

GPIO_OPEN_DRAIN
    Configures GPIO output in open drain mode (wired AND).

    Note: ‘Open Drain’ mode also known as ‘Open Collector’ is an output configuration which behaves like a switch that is either connected to ground or disconnected.

GPIO_OPEN_SOURCE
    Configures GPIO output in open source mode (wired OR).

    Note: ‘Open Source’ is a term used by software engineers to describe output mode opposite to ‘Open Drain’. It behaves like a switch that is either connected to power supply or disconnected. There exist no corresponding hardware schematic and the term is generally unknown to hardware engineers.

GPIO pin bias flags

GPIO_PULL_UP
    Enables GPIO pin pull-up.

GPIO_PULL_DOWN
    Enable GPIO pin pull-down.
**Defines**

`GPIO_DT_SPEC_GET_BY_IDX(node_id, prop, idx)`

Static initializer for a `gpio_dt_spec`.

This returns a static initializer for a `gpio_dt_spec` structure given a devicetree node identifier, a property specifying a GPIO and an index.

Example devicetree fragment:

```plaintext
n: node {
  foo-gpios = <&gpio0 1 GPIO_ACTIVE_LOW>,
    <&gpio1 2 GPIO_ACTIVE_LOW>;
}
```

Example usage:

```c
const struct gpio_dt_spec spec = GPIO_DT_SPEC_GET_BY_IDX(DT_NODELABEL(n),
  foo_gpios, 1);
// Initializes 'spec' to:
// {
//   .port = DEVICE_DT_GET(DT_NODELABEL(gpio1)),
//   .pin = 2,
//   .dt_flags = GPIO_ACTIVE_LOW
// }
```

The ‘gpio’ field must still be checked for readiness, e.g. using `device_is_ready()`. It is an error to use this macro unless the node exists, has the given property, and that property specifies a GPIO controller, pin number, and flags as shown above.

**Parameters**
- `node_id` – devicetree node identifier
- `prop` – lowercase-and-underscores property name
- `idx` – logical index into “prop”

**Returns**
static initializer for a struct `gpio_dt_spec` for the property

`GPIO_DT_SPEC_GET_BY_IDX_OR(node_id, prop, idx, default_value)`

Like `GPIO_DT_SPEC_GET_BY_IDX()`, with a fallback to a default value.

If the devicetree node identifier 'node_id' refers to a node with a property 'prop', this expands to `GPIO_DT_SPEC_GET_BY_IDX(node_id, prop, idx)`. The default_value parameter is not expanded in this case.

Otherwise, this expands to `default_value`.

**Parameters**
- `node_id` – devicetree node identifier
- `prop` – lowercase-and-underscores property name
- `idx` – logical index into “prop”
- `default_value` – fallback value to expand to

**Returns**
static initializer for a struct `gpio_dt_spec` for the property, or `default_value` if the node or property do not exist
**Zephyr Project Documentation, Release 3.6.0-rc3**

**GPIO_DT_SPEC_GET**(node_id, prop)
Equivalent to **GPIO_DT_SPEC_GET_BY_IDX**(node_id, prop, 0).

**See also:**
**GPIO_DT_SPEC_GET_BY_IDX()**

**Parameters**
- node_id – devicetree node identifier
- prop – lowercase-and-underscores property name

**Returns**
static initializer for a struct gpio_dt_spec for the property

**GPIO_DT_SPEC_GET_OR**(node_id, prop, default_value)
Equivalent to **GPIO_DT_SPEC_GET_BY_IDX_OR**(node_id, prop, 0, default_value).

**See also:**
**GPIO_DT_SPEC_GET_BY_IDX_OR()**

**Parameters**
- node_id – devicetree node identifier
- prop – lowercase-and-underscores property name
- default_value – fallback value to expand to

**Returns**
static initializer for a struct gpio_dt_spec for the property

**GPIO_DT_SPEC_INST_GET_BY_IDX**(inst, prop, idx)
Static initializer for a gpio_dt_spec from a DT_DRV_COMPAT instance's GPIO property at an index.

**See also:**
**GPIO_DT_SPEC_GET_BY_IDX()**

**Parameters**
- inst – DT_DRV_COMPAT instance number
- prop – lowercase-and-underscores property name
- idx – logical index into “prop”

**Returns**
static initializer for a struct gpio_dt_spec for the property

**GPIO_DT_SPEC_INST_GET_BY_IDX_OR**(inst, prop, idx, default_value)
Static initializer for a gpio_dt_spec from a DT_DRV_COMPAT instance's GPIO property at an index, with fallback.

**See also:**
**GPIO_DT_SPEC_GET_BY_IDX()**

7.6. Peripherals
Parameters

- inst – DT_DRV_COMPAT instance number
- prop – lowercase-and-underscores property name
- idx – logical index into “prop”
- default_value – fallback value to expand to

Returns

static initializer for a struct gpio_dt_spec for the property

`GPIO_DT_SPEC_INST_GET` (inst, prop)

Equivalent to `GPIO_DT_SPEC_INST_GET_BY_IDX(inst, prop, 0)`.

See also:

`GPIO_DT_SPEC_INST_GET_BY_IDX()`

Parameters

- inst – DT_DRV_COMPAT instance number
- prop – lowercase-and-underscores property name

Returns

static initializer for a struct gpio_dt_spec for the property

`GPIO_DT_SPEC_INST_GET_OR` (inst, prop, default_value)

Equivalent to `GPIO_DT_SPEC_INST_GET_BY_IDX_OR(inst, prop, 0, default_value)`.

See also:

`GPIO_DT_SPEC_INST_GET_BY_IDX()`

Parameters

- inst – DT_DRV_COMPAT instance number
- prop – lowercase-and-underscores property name
- default_value – fallback value to expand to

Returns

static initializer for a struct gpio_dt_spec for the property

`GPIO_DT_RESERVED_RANGES_NGPIOS` (node_id, ngpios)

Makes a bitmask of reserved GPIOs from DT "gpio-reserved-ranges" property and "ngpios" argument.

This macro returns the value as a bitmask of the "gpio-reserved-ranges" property. This property defines the disabled (or 'reserved') GPIOs in the range 0…ngpios-1 and is specified as an array of value’s pairs that define the start offset and size of the reserved ranges.

For example, setting “gpio-reserved-ranges = <3 2>, <10 1>;" means that GPIO offsets 3, 4 and 10 cannot be used even if ngpios = <18>.

The implementation constraint is inherited from common DT limitations: a maximum of 64 pairs can be used (with result limited to bitsize of gpio_port_pins_t type).

NB: Due to the nature of C macros, some incorrect tuple definitions (for example, overlapping or out of range) will produce undefined results.
Also be aware that if `ngpios` is less than 32 (bit size of DT int type), then all unused MSBs outside the range defined by `ngpios` will be marked as reserved too.

Example devicetree fragment:

```
Example devicetree fragment:

a {
    compatible = "some,gpio-controller";
    ngpios = <32>;
    gpio-reserved-ranges = <0 4>, <5 3>, <9 5>, <11 2>, <15 2>,
                        <18 2>, <21 1>, <23 1>, <25 4>, <30 2>;
};

b {
    compatible = "some,gpio-controller";
    ngpios = <18>;
    gpio-reserved-ranges = <3 2>, <10 1>;
};
```

Example usage:

```
Example usage:

struct some_config {
    uint32_t ngpios;
    uint32_t gpios_reserved;
};

static const struct some_config dev_cfg_a = {
    .ngpios = DT_PROP_OR(DT_LABEL(a), ngpios, 0),
    .gpios_reserved = GPIO_DT_RESERVED_RANGES_NGPIOS(DT_LABEL(a),
                                                      DT_PROP(DT_LABEL(a), ngpios)),
};

static const struct some_config dev_cfg_b = {
    .ngpios = DT_PROP_OR(DT_LABEL(b), ngpios, 0),
    .gpios_reserved = GPIO_DT_RESERVED_RANGES_NGPIOS(DT_LABEL(b),
                                                      DT_PROP(DT_LABEL(b), ngpios)),
};
```

This expands to:

```
This expands to:

struct some_config {
    uint32_t ngpios;
    uint32_t gpios_reserved;
};

static const struct some_config dev_cfg_a = {
    .ngpios = 32,
    .gpios_reserved = 0xdeadbeef,
    // 0b1101 1110 1010 1101 1011 1110 1110 1111
};

static const struct some_config dev_cfg_b = {
    .ngpios = 18,
    .gpios_reserved = 0xfffc0418,
    // 0b1111 1111 1111 1100 0000 0100 0001 1000
    // unused MSBs were marked as reserved too
};
```

**Parameters**

- `node_id` – GPIO controller node identifier.
- `ngpios` – number of GPIOs.

**Returns**

the bitmask of reserved gpios
GPIO_DT_RESERVED_RANGES(node_id)
Makes a bitmask of reserved GPIOs from the "gpio-reserved-ranges" and "ngpios" DT properties values.

Parameters
  - node_id – GPIO controller node identifier.

Returns
the bitmask of reserved gpios

GPIO_DT_INST_RESERVED_RANGES_NGPIOS(inst, ngpios)
Makes a bitmask of reserved GPIOs from a DT_DRV_COMPAT instance's "gpio-reserved-ranges" property and "ngpios" argument.

See also:
GPIO_DT_RESERVED_RANGES()

Parameters
  - inst – DT_DRV_COMPAT instance number
  - ngpios – number of GPIOs

Returns
the bitmask of reserved gpios

GPIO_DT_INST_RESERVED_RANGES(inst)
Make a bitmask of reserved GPIOs from a DT_DRV_COMPAT instance's GPIO "gpio-reserved-ranges" and "ngpios" properties.

See also:
GPIO_DT_RESERVED_RANGES()

Parameters
  - inst – DT_DRV_COMPAT instance number

Returns
the bitmask of reserved gpios

GPIO_DT_PORT_PIN_MASK_NGPIOS_EXC(node_id, ngpios)
Makes a bitmask of allowed GPIOs from DT "gpio-reserved-ranges" property and "ngpios" argument.

This macro is paired with GPIO_DT_RESERVED_RANGES_NGPIOS(), however unlike the latter, it returns a bitmask of ALLOWED gpios.

Example devicetree fragment:

```
a {
    compatible = "some,gpio-controller";
    ngpios = <32>;
    gpio-reserved-ranges = <0 8>, <9 5>, <15 16>;
};
```

Example usage:
This expands to:

```c
struct some_config {
    uint32_t port_pin_mask;
};

static const struct some_config dev_cfg = {
    .port_pin_mask = 0x80004100,
};
```

Parameters
- `node_id` – GPIO controller node identifier.
- `ngpios` – number of GPIOs

Returns
the bitmask of allowed gpios

`GPIO_DT_INST_PORT_PIN_MASK_NGPIOS_EXC(inst, ngpios)`

Makes a bitmask of allowed GPIOs from a DT_DRV_COMPAT instance's "gpio-reserved-ranges" property and "ngpios" argument.

See also:
`GPIO_DT_NGPIOS_PORT_PIN_MASK_EXC()`

Parameters
- `inst` – DT_DRV_COMPAT instance number
- `ngpios` – number of GPIOs

Returns
the bitmask of allowed gpios

`GPIO_MAX_PINS_PER_PORT`

Maximum number of pins that are supported by `gpio_port_pins_t`.

`GPIO_DT_FLAGS_MASK`

Mask for DT GPIO flags.

Typedefs

```c
typedef uint32_t gpio_port_pins_t
```

Identifies a set of pins associated with a port.
The pin with index n is present in the set if and only if the bit identified by \((1U \ll n)\) is set.

typedef uint32_t gpio_port_value_t
Provides values for a set of pins associated with a port.
The value for a pin with index n is high (physical mode) or active (logical mode) if and only if the bit identified by \((1U \ll n)\) is set. Otherwise the value for the pin is low (physical mode) or inactive (logical mode).
Values of this type are often paired with a gpio_port_pins_t value that specifies which encoded pin values are valid for the operation.

typedef uint8_t gpio_pin_t
Provides a type to hold a GPIO pin index.
This reduced-size type is sufficient to record a pin number, e.g. from a devicetree GPIOS property.

typedef uint16_t gpio_dt_flags_t
Provides a type to hold GPIO devicetree flags.
All GPIO flags that can be expressed in devicetree fit in the low 16 bits of the full flags field, so use a reduced-size type to record that part of a GPIOS property.
The lower 8 bits are used for standard flags. The upper 8 bits are reserved for SoC specific flags.

typedef uint32_t gpio_flags_t
Provides a type to hold GPIO configuration flags.
This type is sufficient to hold all flags used to control GPIO configuration, whether pin or interrupt.

typedef void (*gpio_callback_handler_t)(const struct device *port, struct gpio_callback *cb, gpio_port_pins_t pins)
Define the application callback handler function signature.

Note: cb pointer can be used to retrieve private data through CONTAINER_OF() if original struct gpio_callback is stored in another private structure.

**Param port**
Device struct for the GPIO device.

**Param cb**
Original struct gpio_callback owning this handler

**Param pins**
Mask of pins that triggers the callback handler

**Functions**

static inline bool gpio_is_ready_dt(const struct gpio_dt_spec *spec)
Validate that GPIO port is ready.

**Parameters**
- spec – GPIO specification from devicetree
Return values

- `true` – if the GPIO spec is ready for use.
- `false` – if the GPIO spec is not ready for use.

```c
int gpio_pin_interrupt_configure(const struct device *port, gpio_pin_t pin, gpio_flags_t flags)
```

Configure pin interrupt.

**Note:** This function can also be used to configure interrupts on pins not controlled directly by the GPIO module. That is, pins which are routed to other modules such as I2C, SPI, UART.

**Parameters**

- `port` – Pointer to device structure for the driver instance.
- `pin` – Pin number.
- `flags` – Interrupt configuration flags as defined by GPIO_INT_*.

**Return values**

- `0` – If successful.
- `-ENOSYS` – If the operation is not implemented by the driver.
- `-ENOTSUP` – If any of the configuration options is not supported (unless otherwise directed by flag documentation).
- `-EINVAL` – Invalid argument.
- `-EBUSY` – Interrupt line required to configure pin interrupt is already in use.
- `-EIO` – I/O error when accessing an external GPIO chip.
- `-EWOULDBLOCK` – if operation would block.

```c
static inline int gpio_pin_interrupt_configure_dt(const struct gpio_dt_spec *spec, gpio_flags_t flags)
```

Configure pin interrupts from a `gpio_dt_spec`.

This is equivalent to:

```c
gpio_pin_interrupt_configure(spec->port, spec->pin, flags);
```

The `spec->dt_flags` value is not used.

**Parameters**

- `spec` – GPIO specification from devicetree
- `flags` – interrupt configuration flags

**Returns**

a value from `gpio_pin_interrupt_configure()`

```c
int gpio_pin_configure(const struct device *port, gpio_pin_t pin, gpio_flags_t flags)
```

Configure a single pin.

**Parameters**

- `port` – Pointer to device structure for the driver instance.
- `pin` – Pin number to configure.
• **flags** – Flags for pin configuration: ‘GPIO input/output configuration flags’, ‘GPIO pin drive flags’, ‘GPIO pin bias flags’.

**Return values**

• **0** – If successful.
• **-ENOTSUP** – if any of the configuration options is not supported (unless otherwise directed by flag documentation).
• **-EINVAL** – Invalid argument.
• **-EIO** – I/O error when accessing an external GPIO chip.
• **-EWOULDBLOCK** – if operation would block.

static inline int gpio_pin_configure_dt(const struct gpio_dt_spec *spec, gpio_flags_t extra_flags)

Configure a single pin from a `gpio_dt_spec` and some extra flags.

This is equivalent to:

```
gpio_pin_configure(spec->port, spec->pin, spec->dt_flags | extra_flags);
```

**Parameters**

• `spec` – GPIO specification from devicetree
• `extra_flags` – additional flags

**Returns**

a value from `gpio_pin_configure()`

int gpio_port_get_direction(const struct device *port, gpio_port_pins_t map, gpio_port_pins_t *inputs, gpio_port_pins_t *outputs)

Get direction of select pins in a port.

Retrieve direction of each pin specified in `map`.

If `inputs` or `outputs` is NULL, then this function does not get the respective input or output direction information.

**Parameters**

• `port` – Pointer to the device structure for the driver instance.
• `map` – Bitmap of pin directions to query.
• `inputs` – Pointer to a variable where input directions will be stored.
• `outputs` – Pointer to a variable where output directions will be stored.

**Return values**

• **0** – If successful.
• **-ENOSYS** – if the underlying driver does not support this call.
• **-EIO** – I/O error when accessing an external GPIO chip.
• **-EWOULDBLOCK** – if operation would block.

static inline int gpio_pin_is_input(const struct device *port, gpio_pin_t pin)

Check if pin is configured for input.

**Parameters**

• `port` – Pointer to device structure for the driver instance.
• `pin` – Pin number to query the direction of
Return values

• 1 – if pin is configured as \texttt{GPIO\_INPUT}.
• 0 – if pin is not configured as \texttt{GPIO\_INPUT}.
• -ENOSYS – if the underlying driver does not support this call.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_is_input_dt(const struct gpio_dt_spec *spec)
Check if a single pin from \texttt{gpio_dt_spec} is configured for input.
This is equivalent to:
\begin{verbatim}
gpio_pin_is_input(spec->port, spec->pin);
\end{verbatim}

Parameters

• spec – GPIO specification from devicetree.

Returns

A value from \texttt{gpio_pin_is_input()}. 

static inline int gpio_pin_is_output(const struct device *port, gpio_pin_t pin)
Check if pin is configured for output.

Parameters

• port – Pointer to device structure for the driver instance.
• pin – Pin number to query the direction of

Return values

• 1 – if pin is configured as \texttt{GPIO\_OUTPUT}.
• 0 – if pin is not configured as \texttt{GPIO\_OUTPUT}.
• -ENOSYS – if the underlying driver does not support this call.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_is_output_dt(const struct gpio_dt_spec *spec)
Check if a single pin from \texttt{gpio_dt_spec} is configured for output.
This is equivalent to:
\begin{verbatim}
gpio_pin_is_output(spec->port, spec->pin);
\end{verbatim}

Parameters

• spec – GPIO specification from devicetree.

Returns

A value from \texttt{gpio_pin_is_output()}. 

int gpio_pin_get_config(const struct device *port, gpio_pin_t pin, gpio_flags_t *flags)
Get a configuration of a single pin.

Parameters

• port – Pointer to device structure for the driver instance.
• pin – Pin number which configuration is get.
• flags – Pointer to variable in which the current configuration will be stored if function is successful.

Return values
• 0 – If successful.
• -ENOSYS – if getting current pin configuration is not implemented by the driver.
• -EINVAL – Invalid argument.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_get_config_dt(const struct gpio_dt_spec *spec, gpio_flags_t *flags)

Get a configuration of a single pin from a gpio_dt_spec.
This is equivalent to:

gpio_pin_get_config(spec->port, spec->pin, flags);

Parameters
• spec – GPIO specification from devicetree
• flags – Pointer to variable in which the current configuration will be stored if function is successful.

Returns
a value from gpio_pin_configure()

int gpio_port_get_raw(const struct device *port, gpio_port_value_t *value)
Get physical level of all input pins in a port.
A low physical level on the pin will be interpreted as value 0. A high physical level will be interpreted as value 1. This function ignores GPIO_ACTIVE_LOW flag.
Value of a pin with index n will be represented by bit n in the returned port value.

Parameters
• port – Pointer to the device structure for the driver instance.
• value – Pointer to a variable where pin values will be stored.

Return values
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_port_get(const struct device *port, gpio_port_value_t *value)
Get logical level of all input pins in a port.
Get logical level of an input pin taking into account GPIO_ACTIVE_LOW flag. If pin is configured as Active High, a low physical level will be interpreted as logical value 0. If pin is configured as Active Low, a low physical level will be interpreted as logical value 1.
Value of a pin with index n will be represented by bit n in the returned port value.

Parameters
• port – Pointer to the device structure for the driver instance.
• **value** – Pointer to a variable where pin values will be stored.

**Return values**
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

```c
int gpio_port_set_masked_raw(const struct device *port, gpio_port_pins_t mask,
                            gpio_port_value_t value)
```

Set physical level of output pins in a port.

Writing value 0 to the pin will set it to a low physical level. Writing value 1 will set it to a high physical level. This function ignores GPIO_ACTIVE_LOW flag.

Pin with index n is represented by bit n in mask and value parameter.

**Parameters**
• **port** – Pointer to the device structure for the driver instance.
• **mask** – Mask indicating which pins will be modified.
• **value** – Value assigned to the output pins.

**Return values**
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

```c
static inline int gpio_port_set_masked(const struct device *port,
                                        gpio_port_pins_t mask,
                                        gpio_port_value_t value)
```

Set logical level of output pins in a port.

Set logical level of an output pin taking into account GPIO_ACTIVE_LOW flag. Value 0 sets the pin in logical 0 / inactive state. Value 1 sets the pin in logical 1 / active state.

If pin is configured as Active High, the default, setting it in inactive state will force the pin to a low physical level. If pin is configured as Active Low, setting it in inactive state will force the pin to a high physical level.

Pin with index n is represented by bit n in mask and value parameter.

**Parameters**
• **port** – Pointer to the device structure for the driver instance.
• **mask** – Mask indicating which pins will be modified.
• **value** – Value assigned to the output pins.

**Return values**
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

```c
int gpio_port_set_bits_raw(const struct device *port,
                           gpio_port_pins_t pins)
```

Set physical level of selected output pins to high.

**Parameters**
• **port** – Pointer to the device structure for the driver instance.
• **pins** – Value indicating which pins will be modified.

**Return values**
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_port_set_bits(const struct device *port, gpio_port_pins_t pins)
Set logical level of selected output pins to active.

Parameters
• port – Pointer to the device structure for the driver instance.
• pins – Value indicating which pins will be modified.

Return values
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

int gpio_port_clear_bits_raw(const struct device *port, gpio_port_pins_t pins)
Set physical level of selected output pins to low.

Parameters
• port – Pointer to the device structure for the driver instance.
• pins – Value indicating which pins will be modified.

Return values
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_port_clear_bits(const struct device *port, gpio_port_pins_t pins)
Set logical level of selected output pins to inactive.

Parameters
• port – Pointer to the device structure for the driver instance.
• pins – Value indicating which pins will be modified.

Return values
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

int gpio_port_toggle_bits(const struct device *port, gpio_port_pins_t pins)
Toggle level of selected output pins.

Parameters
• port – Pointer to the device structure for the driver instance.
• pins – Value indicating which pins will be modified.

Return values
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.
static inline int gpio_port_set_clr_bits_raw(const struct device *port, gpio_port_pins_t set_pins, gpio_port_pins_t clear_pins)

Set physical level of selected output pins.

Parameters

- port – Pointer to the device structure for the driver instance.
- set_pins – Value indicating which pins will be set to high.
- clear_pins – Value indicating which pins will be set to low.

Return values

- 0 – If successful.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

static inline int gpio_port_set_clr_bits(const struct device *port, gpio_port_pins_t set_pins, gpio_port_pins_t clear_pins)

Set logical level of selected output pins.

Parameters

- port – Pointer to the device structure for the driver instance.
- set_pins – Value indicating which pins will be set to active.
- clear_pins – Value indicating which pins will be set to inactive.

Return values

- 0 – If successful.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_get_raw(const struct device *port, gpio_pin_t pin)

Get physical level of an input pin.

A low physical level on the pin will be interpreted as value 0. A high physical level will be interpreted as value 1. This function ignores GPIO_ACTIVE_LOW flag.

Parameters

- port – Pointer to the device structure for the driver instance.
- pin – Pin number.

Return values

- 1 – If pin physical level is high.
- 0 – If pin physical level is low.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_get(const struct device *port, gpio_pin_t pin)

Get logical level of an input pin.

Get logical level of an input pin taking into account GPIO_ACTIVE_LOW flag. If pin is configured as Active High, a low physical level will be interpreted as logical value 0. If pin is configured as Active Low, a low physical level will be interpreted as logical value 1.

Note: If pin is configured as Active High, the default, gpio_pin_get() function is equivalent to gpio_pin_get_raw().
Parameters
• **port** – Pointer to the device structure for the driver instance.
• **pin** – Pin number.

Return values
• 1 – If pin logical value is 1 / active.
• 0 – If pin logical value is 0 / inactive.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_get_dt(const struct gpio_dt_spec *spec)
Get logical level of an input pin from a gpio_dt_spec.
This is equivalent to:
```
gpio_pin_get(spec->port, spec->pin);
```

Parameters
• **spec** – GPIO specification from devicetree

Returns
a value from gpio_pin_get()

static inline int gpio_pin_set_raw(const struct device *port, gpio_pin_t pin, int value)
Set physical level of an output pin.
Writing value 0 to the pin will set it to a low physical level. Writing any value other than 0 will set it to a high physical level. This function ignores GPIO_ACTIVE_LOW flag.

Parameters
• **port** – Pointer to the device structure for the driver instance.
• **pin** – Pin number.
• **value** – Value assigned to the pin.

Return values
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_set(const struct device *port, gpio_pin_t pin, int value)
Set logical level of an output pin.
Set logical level of an output pin taking into account GPIO_ACTIVE_LOW flag. Value 0 sets the pin in logical 0 / inactive state. Any value other than 0 sets the pin in logical 1 / active state. If pin is configured as Active High, the default, setting it in inactive state will force the pin to a low physical level. If pin is configured as Active Low, setting it in inactive state will force the pin to a high physical level.

Note: If pin is configured as Active High, gpio_pin_set() function is equivalent to gpio_pin_set_raw().

Parameters
• **port** – Pointer to the device structure for the driver instance.
• **pin** – Pin number.
• **value** – Value assigned to the pin.
**Return values**

- **0** – If successful.
- **-EIO** – I/O error when accessing an external GPIO chip.
- **-EWOULDBLOCK** – if operation would block.

```c
static inline int gpio_pin_set_dt(const struct gpio_dt_spec *spec, int value);
```

Set logical level of a output pin from a `gpio_dt_spec`.

This is equivalent to:

```
gpio_pin_set(spec->port, spec->pin, value);
```

**Parameters**

- **spec** – GPIO specification from devicetree
- **value** – Value assigned to the pin.

**Returns**

A value from `gpio_pin_set()`

```c
static inline int gpio_pin_toggle(const struct device *port, gpio_pin_t pin);
```

Toggle pin level.

**Parameters**

- **port** – Pointer to the device structure for the driver instance.
- **pin** – Pin number.

**Return values**

- **0** – If successful.
- **-EIO** – I/O error when accessing an external GPIO chip.
- **-EWOULDBLOCK** – if operation would block.

```c
static inline int gpio_pin_toggle_dt(const struct gpio_dt_spec *spec);
```

Toggle pin level from a `gpio_dt_spec`.

This is equivalent to:

```
gpio_pin_toggle(spec->port, spec->pin);
```

**Parameters**

- **spec** – GPIO specification from devicetree

**Returns**

A value from `gpio_pin_toggle()`

```c
static inline void gpio_init_callback(struct gpio_callback *callback,
                                       gpio_callback_handler_t handler,
                                       gpio_port_pins_t pin_mask);
```

Helper to initialize a struct `gpio_callback` properly.

**Parameters**

- **callback** – A valid Application's callback structure pointer.
- **handler** – A valid handler function pointer.
- **pin_mask** – A bit mask of relevant pins for the handler
static inline int gpio_add_callback(const struct device *port, struct gpio_callback *callback)

Add an application callback.

Note: enables to add as many callback as needed on the same port.

Note: Callbacks may be added to the device from within a callback handler invocation, but whether they are invoked for the current GPIO event is not specified.

Parameters

- port – Pointer to the device structure for the driver instance.
- callback – A valid Application's callback structure pointer.

Return values

- 0 – If successful
- -ENOSYS – If driver does not implement the operation
- -errno – Other negative errno code on failure.

static inline int gpio_add_callback_dt(const struct gpio_dt_spec *spec, struct gpio_callback *callback)

Add an application callback.

This is equivalent to:

gpio_add_callback(spec->port, callback);

Parameters

- spec – GPIO specification from devicetree.
- callback – A valid application's callback structure pointer.

Returns

a value from gpio_add_callback().

static inline int gpio_remove_callback(const struct device *port, struct gpio_callback *callback)

Remove an application callback.

Note: enables to remove as many callbacks as added through gpio_add_callback().

Warning: It is explicitly permitted, within a callback handler, to remove the registration for the callback that is running, i.e. callback. Attempts to remove other registrations on the same device may result in undefined behavior, including failure to invoke callbacks that remain registered and unintended invocation of removed callbacks.

Parameters

- port – Pointer to the device structure for the driver instance.
- callback – A valid application's callback structure pointer.

Return values
- If successful
- -ENOSYS – If driver does not implement the operation
- -errno – Other negative errno code on failure.

static inline int gpio_remove_callback_dt(const struct gpio_dt_spec *spec, struct gpio_callback *callback)
Remove an application callback.
This is equivalent to:

```c
gpio_remove_callback(spec->port, callback);
```

Parameters
• spec – GPIO specification from devicetree.
• callback – A valid application’s callback structure pointer.

Returns
a value from gpio_remove_callback().

int gpio_get_pending_int(const struct device *dev)
Function to get pending interrupts.
The purpose of this function is to return the interrupt status register for the device.
This is especially useful when waking up from low power states to check the wake up source.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• status – != 0 if at least one gpio interrupt is pending.
• 0 – if no gpio interrupt is pending.
• -ENOSYS – If driver does not implement the operation

See also:

GPIO_DT_SPEC_GET_BY_IDX
See also:

GPIO_DT_SPEC_GET_BY_IDX_OR
See also:

GPIO_DT_SPEC_GET
See also:

GPIO_DT_SPEC_GET_OR

7.6. Peripherals
Public Members

const struct device *port
   GPIO device controlling the pin.

gpio_pin_t pin
   The pin's number on the device.

gpio_dt_flags_t dt_flags
   The pin's configuration flags as specified in devicetree.

struct gpio_driver_config
   #include <gpio.h> This structure is common to all GPIO drivers and is expected to be
   the first element in the object pointed to by the config field in the device structure.

Public Members

gpio_port_pins_t port_pin_mask
   Mask identifying pins supported by the controller.
   Initialization of this mask is the responsibility of device instance generation in the
   driver.

struct gpio_driver_data
   #include <gpio.h> This structure is common to all GPIO drivers and is expected to be
   the first element in the driver's struct driver_data declaration.

Public Members

gpio_port_pins_t invert
   Mask identifying pins that are configured as active low.
   Management of this mask is the responsibility of the wrapper functions in this
   header.

struct gpio_callback
   #include <gpio.h> GPIO callback structure.
   Used to register a callback in the driver instance callback list. As many callbacks
   as needed can be added as long as each of them are unique pointers of struct
   gpio_callback. Beware such structure should not be allocated on stack.
   Note: To help setting it, see gpio_init_callback() below

Public Members

sys_snode_t node
   This is meant to be used in the driver and the user should not mess with it (see
   drivers/gpio/gpio_utils.h)
\texttt{gpio\_callback\_handler\_t} \texttt{handler}

Actual callback function being called when relevant.

\texttt{gpio\_port\_pins\_t} \texttt{pin\_mask}

A mask of pins the callback is interested in, if 0 the callback will never be called.

Such \texttt{pin\_mask} can be modified whenever necessary by the owner, and thus will affect the handler being called or not. The selected pins must be configured to trigger an interrupt.

### 7.6.23 Hardware Information

#### Overview

The HW Info API provides access to hardware information such as device identifiers and reset cause flags.

Reset cause flags can be used to determine why the device was reset; for example due to a watchdog timeout or due to power cycling. Different devices support different subset of flags. Use \texttt{hwinfo\_get\_supported\_reset\_cause()} to retrieve the flags that are supported by that device.

#### Configuration Options

Related configuration options:

- \texttt{CONFIG\_HWINFO}

#### API Reference

\textit{group} \texttt{hwinfo\_interface}

Hardware Information Interface.

#### Reset cause flags

- \texttt{RESET\_PIN}

  External pin.

- \texttt{RESET\_SOFTWARE}

  Software reset.

- \texttt{RESET\_BROWNOUT}

  Brownout (drop in voltage)

- \texttt{RESET\_POR}

  Power-on reset (POR)
RESET_WATCHDOG
Watchdog timer expiration.

RESET_DEBUG
Debug event.

RESET_SECURITY
Security violation.

RESET_LOW_POWER_WAKE
Waking up from low power mode.

RESET_CPU_LOCKUP
CPU lock-up detected.

RESET_PARITY
Parity error.

RESET_PLL
PLL error.

RESET_CLOCK
Clock error.

RESET_HARDWARE
Hardware reset.

RESET_USER
User reset.

RESET_TEMPERATURE
Temperature reset.

Functions

ssize_t hwinfo_get_device_id(uint8_t *buffer, size_t length)
Copy the device id to a buffer.

This routine copies “length” number of bytes of the device ID to the buffer. If the device ID is smaller then length, the rest of the buffer is left unchanged. The ID depends on the hardware and is not guaranteed unique.

Drivers are responsible for ensuring that the ID data structure is a sequence of bytes. The returned ID value is not supposed to be interpreted based on vendor-specific assumptions of byte order. It should express the identifier as a raw byte sequence, doing any endian conversion necessary so that a hex representation of the bytes produces the intended serial number.

Parameters

• buffer – Buffer to write the ID to.
• length – Max length of the buffer.
Return values

- **size** – of the device ID copied.
- **-ENOSYS** – if there is no implementation for the particular device.
- **any** – negative value on driver specific errors.

```c
int hwinfo_get_reset_cause(uint32_t *cause)
```

Retrieve cause of device reset.

This routine retrieves the flags that indicate why the device was reset.

On some platforms the reset cause flags accumulate between successive resets and this routine may return multiple flags indicating all reset causes since the device was powered on. If you need to retrieve the cause only for the most recent reset call `hwinfo_clear_reset_cause` after calling this routine to clear the hardware flags before the next reset event.

Successive calls to this routine will return the same value, unless `hwinfo_clear_reset_cause` has been called.

**Parameters**

- **cause** – OR'd `reset cause` flags

**Return values**

- **zero** – if successful.
- **-ENOSYS** – if there is no implementation for the particular device.
- **any** – negative value on driver specific errors.

```c
int hwinfo_clear_reset_cause(void)
```

Clear cause of device reset.

Clears reset cause flags.

**Return values**

- **zero** – if successful.
- **-ENOSYS** – if there is no implementation for the particular device.
- **any** – negative value on driver specific errors.

```c
int hwinfo_get_supported_reset_cause(uint32_t *supported)
```

Get supported reset cause flags.

Retrieves all `reset_cause` flags that are supported by this device.

**Parameters**

- **supported** – OR'd `reset cause` flags that are supported

**Return values**

- **zero** – if successful.
- **-ENOSYS** – if there is no implementation for the particular device.
- **any** – negative value on driver specific errors.
7.6.24 I2C EEPROM Target

Overview

API Reference

group i2c_eeprom_target_api

I2C EEPROM Target Driver API.

Functions

int eeprom_target_program(const struct device *dev, const uint8_t *eeprom_data, unsigned int length)

Program memory of the virtual EEPROM.

Parameters

• dev – Pointer to the device structure for the driver instance.
• eeprom_data – Pointer of data to program into the virtual eeprom memory
• length – Length of data to program into the virtual eeprom memory

Return values

• 0 – If successful.
• -EINVAL – Invalid data size

int eeprom_target_read(const struct device *dev, uint8_t *eeprom_data, unsigned int offset)

Read single byte of virtual EEPROM memory.

Parameters

• dev – Pointer to the device structure for the driver instance.
• eeprom_data – Pointer of byte where to store the virtual eeprom memory
• offset – Offset into EEPROM memory where to read the byte

Return values

• 0 – If successful.
• -EINVAL – Invalid data pointer or offset

int eeprom_target_set_addr(const struct device *dev, uint8_t addr)

Change the address of eeprom taget at runtime.

Parameters

• dev – Pointer to the device structure for the driver instance.
• addr – New address to assign to the eeprom target devide

Return values

• 0 – Is successful
• -EINVAL – If parameters are invalid
• -EIO – General input / output error during i2c_taget_register
• -ENOSYS – If target mode is not implemented
7.6.25 Improved Inter-Integrated Circuit (I3C) Bus

I3C (Improved Inter-Integrated Circuit) is a two-signal shared peripheral interface bus. Devices on the bus can operate in two roles: as a “controller” that initiates transactions and controls the clock, or as a “target” that responds to transaction commands.

Currently, the API is based on the I3C Specification version 1.1.1.

- **I3C Controller API**
  - In-Band Interrupt (IBI)
  - Device Tree
  - Device Drivers for I3C Devices
  - I2C Devices under I3C Bus
- **Configuration Options**
- **API Reference**

**I3C Controller API**

Zephyr's I3C controller API is used when an I3C controller controls the bus, in particular the start and stop conditions and the clock. This is the most common mode, used to interact with I3C target devices such as sensors.

Due to the nature of the I3C, there are devices on the bus where they may not have addresses when powered on. Therefore, an additional dynamic address assignment needs to be carried out by the I3C controller. Because of this, the controller needs to maintain separate structures to keep track of device status. This can be done at build time, for example, by creating arrays of device descriptors for both I3C and I2C devices:

```c
static struct i3c_device_desc i3c_device_array[] = I3C_DEVICE_ARRAY_DT_INST(inst);
static struct i3c_i2c_device_desc i2c_device_array[] = I3C_I2C_DEVICE_ARRAY_DT_INST(inst);
```

The macros `I3CDEVICE_ARRAY_DT_INST` and `I3CI2CDEVICE_ARRAY_DT_INST` are helper macros to aid in create arrays of device descriptors corresponding to the devicetree nodes under the I3C controller.

Here is a list of generic steps for initializing the I3C controller and the I3C bus inside the device driver initialization function:

1. Initialize the data structure of the I3C controller device driver instance. The usual device defining macros such as `DEVICE_DT_INST_DEFINE` can be used, and the initialization function provided as a parameter to the macro.

   - The `i3c_addrSlots` and `i3c_dev_list` are structures to aid in address assignments and device list management. If this is being used, this struct needs to be initialized by calling `i3c_addrSlotsInit()`. These two structures can also be used with various helper functions.

   - Initialize the device descriptors if needed by the controller driver.

2. Initialize the hardware, including but not limited to:

   - Setup pin mux and directions.
   - Setup the clock for the controller.
   - Power on the hardware.
   - Configure the hardware (e.g. SCL clock frequency).
3. Perform bus initialization. There is a generic helper function, \texttt{i3c\_bus\_init()}, which performs the following steps. This function can be used if the controller does not require any special handling during bus initialization.

1. Do \texttt{RSTDAA} to reset dynamic addresses of connected devices. If any connected devices have already been assigned an address, the bookkeeping data structures do not have records of these, for example, at power-on. So it is a good idea to reset and assign them new addresses.

2. Do \texttt{DISEC} to disable any events from devices.

3. Do \texttt{SETDASA} to use static addresses as dynamic address if so desired.
   - \texttt{SETAASA} may not be supported for all connected devices to assign static addresses as dynamic addresses.
   - BCR and DCR need to be obtained separately to populate the relevant fields in the I3C target device descriptor struct.

4. Do \texttt{ENTDAA} to start dynamic address assignment, if there are still devices without addresses.
   - If there is a device waiting for address, it will send its Provisioned ID, BCR, and DCR back. Match the received Provisioned ID to the list of registered I3C devices.
     - If there is a match, assign an address (either from the stated static address if \texttt{SETDASA} has not been done, or use a free address).
       - Also, set the BCR and DCR fields in the device descriptor struct.
     - If there is no match, depending on policy, it can be assigned a free address, or the device driver can stop the assignment process and errors out.
       - Note that the I3C API requires device descriptor to function. A device without a device descriptor cannot be accessed through the API.
     - This step can be skipped if there is no connected devices requiring DAA.

5. These are optional but highly recommended:
   - Do \texttt{GETMRL} and \texttt{GETMWL} to get maximum read/write length.
   - Do \texttt{GETMXDS} to get maximum read/write speed and maximum read turnaround time.
   - The helper function, \texttt{i3c\_bus\_init()}, would retrieve basic device information such as BCR, DCR, MRL and MWL.

6. Do \texttt{ENEC} to re-enable events from devices.
   - The helper function, \texttt{i3c\_bus\_init()}, only re-enables hot-join events. IBI event should only be enabled when enabling IBI of a device.

\textbf{In-Band Interrupt (IBI)}

If a target device can generate In-Band Interrupt (IBI), the controller needs to be made aware of it.

- \texttt{i3c\_ibi\_enable()} to enable IBI of a target device.
  - Some controller hardware have IBI slots which need to be programmed so that the controller can recognize incoming IBIs from a particular target device.
    - If the hardware has IBI slots, \texttt{i3c\_ibi\_enable()} needs to program those IBI slots.
    - Note that there are usually limited IBI slots on the controller so this operation may fail.
  - The implementation in driver should also send the \texttt{ENEC} command to enable interrupt of this target device.
• `i3c_ibi_disable()` to disable IBI of a target device.
  
  – If controller hardware makes use of IBI slots, this will remove description of the target device from the slots.
  
  – The implementation in driver should also send the DISEC command to disable interrupt of this target device.

**Device Tree**  
Here is an example for defining an I3C controller in device tree:

```plaintext
i3c0: i3c@10000 {
    compatible = "vendor,i3c";

    #address-cells = <0x3>;
    #size-cells = <0x0>;

    reg = <0x1000 0x1000>;
    interrupts = <0x1F 0x0>;

    pinctrl-0 = <&pinmux-i3c>;
    pinctrl-names = "default";

    i2c-scl-hz = <400000>;
    i3c-scl-hz = <1200000>;

    status = "okay";
}

i3c-dev0: i3c-dev0@420000ABCD12345678 {
    compatible = "vendor,i3c-dev";

    reg = <0x42 0xABCD 0x12345678>;

    status = "okay";
};

i2c-dev0: i2c-dev0@380000000000000050 {
    compatible = "vendor-i2c-dev";

    reg = <0x38 0x0 0x50>;

    status = "okay";
};

**I3C Devices**  
For I3C devices, the `reg` property has 3 elements:

• The first one is the static address of the device.
  
  – Can be zero if static address is not used. Address will be assigned during DAA (Dynamic Address Assignment).
  
  – If non-zero and property `assigned-address` is not set, this will be the address of the device after SETDASA (Set Dynamic Address from Static Address) is issued.

• Second element is the upper 16-bit of the Provisioned ID (PID) which contains the manufacturer ID left-shifted by 1. This is the bits 33-47 (zero-based) of the 48-bit Provisioned ID.

• Third element contains the lower 32-bit of the Provisioned ID which is a combination of the part ID (left-shifted by 16, bits 16-31 of the PID) and the instance ID (left-shifted by 12, bits 12-15 of the PID).
Note that the unit-address (the part after @) must match the reg property fully where each element is treated as 32-bit integer, combining to form a 96-bit integer. This is required for properly generating device tree macros.

**I2C Devices** For I2C devices where the device driver has support for working under I3C bus, the device node can be described as a child of the I3C controller. If the device driver is written to only work with I2C controllers, define the node under the I2C virtual controller as described below. Otherwise, the reg property, similar to I3C devices, has 3 elements:

- The first one is the static address of the device. This must be a valid address as I2C devices do not support dynamic address assignment.
- Second element is always zero.
  - This is used by various helper macros to determine whether the device tree entry corresponds to a I2C device.
- Third element is the LVR (Legacy Virtual Register):
  - bit[31:8] are unused.
  - bit[7:5] are the I2C device index:
    - Index 0
      - I3C device has a 50 ns spike filter where it is not affected by high frequency on SCL.
    - Index 1
      - I2C device does not have a 50 ns spike filter but can work with high frequency on SCL.
    - Index 2
      - I3C device does not have a 50 ns spike filter and cannot work with high frequency on SCL.
  - bit[4] is the I2C mode indicator:
    - 0 is FM+ mode.
    - 1 is FM mode.

Similar to I3C devices, the unit-address must match the reg property fully where each element is treated as 32-bit integer, combining to form a 96-bit integer.

**Device Drivers for I3C Devices** All of the transfer functions of I3C controller API require the use of device descriptors, `i3c_device_desc`. This struct contains runtime information about an I3C device, such as, its dynamic address, BCR, DCR, MRL and MWL. Therefore, the device driver of an I3C device should grab a pointer to this device descriptor from the controller using `i3c_device_find()`. This function takes an ID parameter of type `i3c_device_id` for matching. The returned pointer can then be used in subsequent API calls to the controller.

**I2C Devices under I3C Bus** Since I3C is backward compatible with I2C, the I3C controller API can accommodate I2C API calls without modifications if the controller device driver implements the I2C API. This has the advantage of using existing I2C devices without any modifications to their device drivers. However, since the I3C controller API works on device descriptors, any calls to I2C API will need to look up the corresponding device descriptor from the I2C device address. This adds a bit of processing cost to any I2C API calls.

On the other hand, a device driver can be extended to utilize native I2C device support via the I3C controller API. During device initialization, `i3c_i2c_device_find()` needs to be called to retrieve the pointer to the device descriptor. This pointer can be used in subsequent API calls.
Note that, with either methods mentioned above, the devicetree node of the I2C device must be declared according to I3C standard:

The I2C virtual controller device driver provides a way to interface I2C devices on the I3C bus where the associated device drivers can be used as-is without modifications. This requires adding an intermediate node in the device tree:

```c
i3c0: i3c@00000 {
    <!-- I3C controller related properties -->
    <!-- Nodes of I3C devices, if any -->
    i2c-dev0: i2c-dev0@420000000000000050 {
        compatible = "vendor-i2c-dev";
        reg = <0x42 0x0 0x50 >;
        status = "okay";
    }
};
```

### Configuration Options

Related configuration options:

- `CONFIG_I3C`
- `CONFIG_I3C_USE_GROUP_ADDR`
- `CONFIG_I3C_USE_IBI`
- `CONFIG_I3C_IBI_MAX_PAYLOAD_SIZE`
- `CONFIG_I3C_CONTROLLER_INIT_PRIORITY`

### API Reference

`group i3c_interface`

I3C Interface.

#### Bus Characteristic Register (BCR)

- BCR[7:6]: Device Role
  - 0: I3C Target
  - 1: I3C Controller capable
  - 2: Reserved
  - 3: Reserved
- BCR[5]: Advanced Capabilities
  - 0: Does not support optional advanced capabilities.
  - 1: Supports optional advanced capabilities which can be viewed via GETCAPS CCC.
- BCR[4]: Virtual Target Support
  - 0: Is not a virtual target.
– 1: Is a virtual target.

• BCR[3]: Offline Capable
  – 0: Will always response to I3C commands.
  – 1: Will not always response to I3C commands.

• BCR[2]: IBI Payload
  – 0: No data bytes following the accepted IBI.
  – 1: One data byte (MDB, Mandatory Data Byte) follows the accepted IBI. Additional data bytes may also follows.

• BCR[1]: IBI Request Capable
  – 0: Not capable
  – 1: Capable

• BCR[0]: Max Data Speed Limitation
  – 0: No Limitation
  – 1: Limitation obtained via GETMXDS CCC.

\texttt{I3C\_BCR\_MAX\_DATA\_SPEED\_LIMIT}

Max Data Speed Limitation bit.
0 - No Limitation. 1 - Limitation obtained via GETMXDS CCC.

\texttt{I3C\_BCR\_IBI\_REQUEST\_CAPABLE}

IBI Request Capable bit.

\texttt{I3C\_BCR\_IBI\_PAYLOAD\_HAS\_DATA\_BYTE}

IBI Payload bit.

0 - No data bytes following the accepted IBI. 1 - One data byte (MDB, Mandatory Data Byte) follows the accepted IBI. Additional data bytes may also follows.

\texttt{I3C\_BCR\_OFFLINE\_CAPABLE}

Offline Capable bit.

0 - Will always respond to I3C commands. 1 - Will not always respond to I3C commands.

\texttt{I3C\_BCR\_VIRTUAL\_TARGET}

Virtual Target Support bit.

0 - Is not a virtual target. 1 - Is a virtual target.

\texttt{I3C\_BCR\_ADV\_CAPABILITIES}

Advanced Capabilities bit.

0 - Does not support optional advanced capabilities. 1 - Supports optional advanced capabilities which can be viewed via GETCAPS CCC.

\texttt{I3C\_BCR\_DEVICE\_ROLE\_I3C\_TARGET}

Device Role - I3C Target.

\texttt{I3C\_BCR\_DEVICE\_ROLE\_I3C\_CONTROLLER\_CAPABLE}

Device Role - I3C Controller Capable.
I3C_BCR_DEVICE_ROLE_SHIFT
   Device Role bit shift value.

I3C_BCR_DEVICE_ROLE_MASK
   Device Role bit shift mask.

I3C_BCR_DEVICE_ROLE(bcr)
   Device Role.
   Obtain Device Role value from the BCR value obtained via GETBCR.

   Parameters
   • bcr – BCR value

Legacy Virtual Register (LVR)

Legacy Virtual Register (LVR)

   • LVR[7:5]: I2C device index:
     – 0: I2C device has a 50 ns spike filter where it is not affected by high frequency on SCL.
     – 1: I2C device does not have a 50 ns spike filter but can work with high frequency on SCL.
     – 2: I2C device does not have a 50 ns spike filter and cannot work with high frequency on SCL.
   • LVR[4]: I2C mode indicator:
     – 0: FM+ mode
     – 1: FM mode
   • LVR[3:0]: Reserved.

I3C_LVR_I2C_FM_PLUS_MODE
   I2C FM+ Mode.

I3C_LVR_I2C_FM_MODE
   I2C FM Mode.

I3C_LVR_I2C_MODE_SHIFT
   I2C Mode Indicator bit shift value.

I3C_LVR_I2C_MODE_MASK
   I2C Mode Indicator bitmask.

I3C_LVR_I2C_MODE(lvr)
   I2C Mode.
   Obtain I2C Mode value from the LVR value.

   Parameters
   • lvr – LVR value
I3C_LVR_I2C_DEV_IDX_0
I2C Device Index 0.
I2C device has a 50 ns spike filter where it is not affected by high frequency on SCL.

I3C_LVR_I2C_DEV_IDX_1
I2C Device Index 1.
I2C device does not have a 50 ns spike filter but can work with high frequency on SCL.

I3C_LVR_I2C_DEV_IDX_2
I2C Device Index 2.
I2C device does not have a 50 ns spike filter and cannot work with high frequency on SCL.

I3C_LVR_I2C_DEV_IDX_SHIFT
I2C Device Index bit shift value.

I3C_LVR_I2C_DEV_IDX_MASK
I2C Device Index bitmask.

I3C_LVR_I2C_DEV_IDX(lvr)
I2C Device Index.
Obtain I2C Device Index value from the LVR value.

Parameters
• lvr – LVR value

Defines

I3C_DEVICE_ID(pid)
Structure initializer for i3c_device_id from PID.
This helper macro expands to a static initializer for a struct i3c_device_id by populating the PID (Provisioned ID) field.

Parameters
• pid – Provisioned ID.

Enums

enum i3c_bus_mode
I3C bus mode.
Values:

enumerator I3C_BUS_MODE_PUR
Only I3C devices are on the bus.
enumerator I3C_BUS_MODE_MIXED_FAST
    Both I3C and legacy I2C devices are on the bus.
    The I2C devices have 50ns spike filter on SCL.

enumerator I3C_BUS_MODE_MIXED_LIMITED
    Both I3C and legacy I2C devices are on the bus.
    The I2C devices do not have 50ns spike filter on SCL and can tolerate maximum SDR SCL clock frequency.

enumerator I3C_BUS_MODE_MIXED_SLOW
    Both I3C and legacy I2C devices are on the bus.
    The I2C devices do not have 50ns spike filter on SCL but cannot tolerate maximum SDR SCL clock frequency.

enumerator I3C_BUS_MODE_MAX = I3C_BUS_MODE_MIXED_SLOW

enumerator I3C_BUS_MODE_INVALID

eenum i3c_i2c_speed_type
    I2C bus speed under I3C bus.
    Only FM and FM+ modes are supported for I2C devices under I3C bus.
    Values:

    enumerator I3C_I2C_SPEED_FM
        I2C FM mode.

    enumerator I3C_I2C_SPEED_FMPLUS
        I2C FM+ mode.

    enumerator I3C_I2C_SPEED_MAX = I3C_I2C_SPEED_FMPLUS

    enumerator I3C_I2C_SPEED_INVALID

eenum i3c_data_rate
    I3C data rate.
    I3C data transfer rate defined by the I3C specification.
    Values:

    enumerator I3C_DATA_RATE_SDR
        Single Data Rate messaging.

    enumerator I3C_DATA_RATE_HDR_DDR
        High Data Rate - Double Data Rate messaging.

    enumerator I3C_DATA_RATE_HDR_TSL
        High Data Rate - Ternary Symbol Legacy-inclusive-Bus.

7.6. Peripherals
enumerator I3C_DATA_RATE_HDR_TSP
   High Data Rate - Ternary Symbol for Pure Bus.

enumerator I3C_DATA_RATE_HDR_BT
   High Data Rate - Bulk Transport.

enumerator I3C_DATA_RATE_MAX = I3C_DATA_RATE_HDR_BT

enumerator I3C_DATA_RATE_INVALID

enum i3c_sdr_controller_error_codes
I3C SDR Controller Error Codes.
These are error codes defined by the I3C specification.
I3C_ERROR_CE_UNKNOWN and I3C_ERROR_CE_NONE are not official error codes according to the specification. These are there simply to aid in error handling during interactions with the I3C drivers and subsystem.
Values:

enumerator I3C_ERROR_CE0
   Transaction after sending CCC.

enumerator I3C_ERROR_CE1
   Monitoring Error.

enumerator I3C_ERROR_CE2
   No response to broadcast address (0x7E)

enumerator I3C_ERROR_CE3
   Failed Controller Handoff.

enumerator I3C_ERROR_CE_UNKNOWN
   Unknown error (not official error code)

enumerator I3C_ERROR_CE_NONE
   No error (not official error code)

enumerator I3C_ERROR_CE_MAX = I3C_ERROR_CE_UNKNOWN

enumerator I3C_ERROR_CE_INVALID

enum i3c_sdr_target_error_codes
I3C SDR Target Error Codes.
These are error codes defined by the I3C specification.
I3C_ERROR_TE_UNKNOWN and I3C_ERROR_TE_NONE are not official error codes according to the specification. These are there simply to aid in error handling during interactions with the I3C drivers and subsystem.
Values:
enumerator I3C_ERROR_TE0
    Invalid Broadcast Address or Dynamic Address after DA assignment.

denumerator I3C_ERROR_TE1
    CCC Code.

denumerator I3C_ERROR_TE2
    Write Data.

denumerator I3C_ERROR_TE3
    Assigned Address during Dynamic Address Arbitration.

denumerator I3C_ERROR_TE4
    0x7E/R missing after RESTART during Dynamic Address Arbitration

denumerator I3C_ERROR_TE5
    Transaction after detecting CCC.

denumerator I3C_ERROR_TE6
    Monitoring Error.

denumerator I3C_ERROR_DBR
    Dead Bus Recovery.

denumerator I3C_ERROR_TE_UNKNOWN
    Unknown error (not official error code)

denumerator I3C_ERROR_TE_NONE
    No error (not official error code)

denumerator I3C_ERROR_TE_MAX = I3C_ERROR_TE_UNKNOWN

denumerator I3C_ERROR_TE_INVALID

denum i3c_config_type
    Type of configuration being passed to configure function. 
    Values:

    enumerator I3C_CONFIG_CONTROLLER

    enumerator I3C_CONFIG_TARGET

    enumerator I3C_CONFIG_CUSTOM

**Functions**
Find a I3C target device descriptor by ID.
This finds the I3C target device descriptor in the device list matching the provided ID.

Parameters
• dev_list – Pointer to the device list struct.
• id – Pointer to I3C device ID struct.

Returns
Pointer the the I3C target device descriptor, or NULL if none is found.

Find a I3C target device descriptor by dynamic address.
This finds the I3C target device descriptor in the attached device list matching the dynamic address (addr)

Parameters
• dev_list – Pointer to the device list struct.
• addr – Dynamic address to be matched.

Returns
Pointer the the I3C target device descriptor, or NULL if none is found.

Find a I2C target device descriptor by address.
This finds the I2C target device descriptor in the attached device list matching the address (addr)

Parameters
• dev_list – Pointer to the device list struct.
• addr – Address to be matched.

Returns
Pointer the the I2C target device descriptor, or NULL if none is found.

Helper function to find the default address an i3c device is attached with.
This is a helper function to find the default address the device will be loaded with. This could be either it’s static address, a requested dynamic address, or just a dynamic address that is available

Parameters
• target – [in] The pointer of the device descriptor
• addr – [out] Address to be assigned to target device.

Return values
• 0 – if successful.
• -EINVAL – if the expected default address is already in use
int i3c_dev_list_daa_addr_helper(struct i3c_addr_slots *addr_slots, const struct i3c_dev_list *dev_list, uint64_t pid, bool must_match, bool assigned_okay, struct i3c_device_desc **target, uint8_t *addr)

Helper function to find a usable address during ENTDAA.

This is a helper function to find a usable address during Dynamic Address Assignment. Given the PID (pid), it will search through the device list for the matching device descriptor. If the device descriptor indicates that there is a preferred address (i.e. assigned-address in device tree),

If must_match is true, the PID (pid) must match one of the device in the device list.

See also:

i3c_device_desc::init_dynamic_addr), this preferred address will be returned if this address is still available. If it is not available, another free address will be returned.

If must_match is false, this will return an arbitrary address. This is useful when not all devices are described in device tree. Or else, the DAA process cannot proceed since there is no address to be assigned.

If assigned_okay is true, it will return the same address already assigned to the device (that

If assigned_okay is false, the device cannot have an address assigned already (that

See also:

i3c_device_desc::dynamic_addr). If no address has been assigned, it behaves as if assigned_okay is false. This is useful for assigning the same address to the same device (for example, hot-join after device coming back from suspend).

See also:

i3c_device_desc::dynamic_addr is not zero). This is mainly used during the initial DAA.

Parameters

- addr_slots – [in] Pointer to address slots struct.
- dev_list – [in] Pointer to the device list struct.
- pid – [in] Provisioned ID of device to be assigned address.
- assigned_okay – [in] True if it is okay to return the address already assigned to the target matching the PID (pid).
- target – [out] Store the pointer of the device descriptor if it matches the incoming PID (pid).
- addr – [out] Address to be assigned to target device.

Return values

- 0 – if successful.
- -ENODEV – if no device matches the PID (pid) in the device list and must_match is true.
- -EINVAL – if the device matching PID (pid) already has an address assigned or invalid function arguments.
static inline int i3c_configure(const struct device *dev, enum i3c_config_type type, void *config)

Configure the I3C hardware.

Parameters

- dev – Pointer to controller device driver instance.
- type – Type of configuration parameters being passed in config.
- config – Pointer to the configuration parameters.

Return values

- 0 – If successful.
- EINVAL – If invalid configure parameters.
- EIO – General Input/Output errors.
- ENOSYS – If not implemented.

static inline int i3c_config_get(const struct device *dev, enum i3c_config_type type, void *config)

Get configuration of the I3C hardware.

This provides a way to get the current configuration of the I3C hardware.

This can return cached config or probed hardware parameters, but it has to be up to date with current configuration.

Note that if type is I3C_CONFIG_CUSTOM, config must contain the ID of the parameter to be retrieved.

Parameters

- dev – [in] Pointer to controller device driver instance.
- type – [in] Type of configuration parameters being passed in config.
- config – [inout] Pointer to the configuration parameters.

Return values

- 0 – If successful.
- EIO – General Input/Output errors.
- ENOSYS – If not implemented.

static inline int i3c_recover_bus(const struct device *dev)

Attempt bus recovery on the I3C bus.

This routine asks the controller to attempt bus recovery.

Return values

- 0 – If successful.
- EBUSY – If bus recovery fails.
- EIO – General input / output error.
- ENOSYS – Bus recovery is not supported by the controller driver.

int i3c_attach_i3c_device(struct i3c_device_desc *target)

Attach an I3C device.

Called to attach a I3C device to the addresses. This is typically called before a SETDASA or ENTDAA to reserve the addresses. This will also call the optional api to update any registers within the driver if implemented.
**Warning:** Use cases involving multiple writers to the i3c/i2c devices must prevent concurrent write operations, either by preventing all writers from being preempted or by using a mutex to govern writes to the i3c/i2c devices.

**Parameters**
- `target` – Pointer to the target device descriptor

**Return values**
- `0` – If successful.
- `-EINVAL` – If address is not available or if the device has already been attached before

```c
int i3c_reattach_i3c_device(struct i3c_device_desc *target, uint8_t old_dyn_addr)
```

Reattach I3C device. called after every time an I3C device has its address changed. It can be because the device has been powered down and has lost its address, or it can happen when a device had a static address and has been assigned a dynamic address with SETDASA or a dynamic address has been updated with SETNEWDA. This will also call the optional api to update any registers within the driver if implemented.

**Warning:** Use cases involving multiple writers to the i3c/i2c devices must prevent concurrent write operations, either by preventing all writers from being preempted or by using a mutex to govern writes to the i3c/i2c devices.

**Parameters**
- `target` – Pointer to the target device descriptor
- `old_dyn_addr` – The old dynamic address of target device, 0 if there was no old dynamic address

**Return values**
- `0` – If successful.
- `-EINVAL` – If address is not available

```c
int i3c_detach_i3c_device(struct i3c_device_desc *target)
```

Detach I3C Device. called to remove an I3C device and to free up the address that it used. If it's dynamic address was not set, then it assumed that SETDASA failed and will free it's static addr. This will also call the optional api to update any registers within the driver if implemented.

**Warning:** Use cases involving multiple writers to the i3c/i2c devices must prevent concurrent write operations, either by preventing all writers from being preempted or by using a mutex to govern writes to the i3c/i2c devices.

**Parameters**
- `target` – Pointer to the target device descriptor

**Return values**
- `0` – If successful.
- EINVAL – If device is already detached

int i3c_attach_i2c_device(struct i3c_i2c_device_desc *target)
Attach an I2C device.
Called to attach an I2C device to the addresses. This will also call the optional api to update any registers within the driver if implemented.

**Warning:** Use cases involving multiple writers to the i3c/i2c devices must prevent concurrent write operations, either by preventing all writers from being preempted or by using a mutex to govern writes to the i3c/i2c devices.

**Parameters**
- target – Pointer to the target device descriptor

**Return values**
- 0 – If successful.
- -EINVAL – If address is not available or if the device has already been attached before

int i3c_detach_i2c_device(struct i3c_i2c_device_desc *target)
Detach I2C Device.
called to remove an I2C device and to free up the address that it used. This will also call the optional api to update any registers within the driver if implemented.

**Warning:** Use cases involving multiple writers to the i3c/i2c devices must prevent concurrent write operations, either by preventing all writers from being preempted or by using a mutex to govern writes to the i3c/i2c devices.

**Parameters**
- target – Pointer to the target device descriptor

**Return values**
- 0 – If successful.
- -EINVAL – If device is already detached

static inline int i3c_do_daa(const struct device *dev)
Perform Dynamic Address Assignment on the I3C bus.
This routine asks the controller to perform dynamic address assignment where the controller belongs. Only the active controller of the bus should do this.

**Note:** For controller driver implementation, the controller should perform SETDASA to allow static addresses to be the dynamic addresses before actually doing ENTDAA.

**Parameters**
- dev – Pointer to the device structure for the controller driver instance.

**Return values**
- 0 – If successful.
• -EBUSY – Bus is busy.
• -EIO – General input / output error.
• -ENODEV – If a provisioned ID does not match to any target devices in the registered device list.
• -ENOSPC – No more free addresses can be assigned to target.
• -ENOSYS – Dynamic address assignment is not supported by the controller driver.

`int i3c_do_ccc(const struct device *dev, struct i3c_ccc_payload *payload)`
Send CCC to the bus.

**Parameters**
- `dev` – Pointer to the device structure for the controller driver instance.
- `payload` – Pointer to the structure describing the CCC payload.

**Return values**
- 0 – If successful.
- -EBUSY – Bus is busy.
- -EIO – General Input / output error.
- -EINVAL – Invalid valid set in the payload structure.
- -ENOSYS – Not implemented.

`static inline struct i3c_device_desc *i3c_device_find(const struct device *dev, const struct i3c_device_id *id)`
Find a registered I3C target device.
Controller only API.
This returns the I3C device descriptor of the I3C device matching the incoming `id`.

**Parameters**
- `dev` – Pointer to controller device driver instance.
- `id` – Pointer to I3C device ID.

**Returns**
Pointer to I3C device descriptor, or NULL if no I3C device found matching incoming `id`.

`int i3c_bus_init(const struct device *dev, const struct i3c_dev_list *i3c_dev_list)`
Generic helper function to perform bus initialization.

**Parameters**
- `dev` – Pointer to controller device driver instance.
- `i3c_dev_list` – Pointer to I3C device list.

**Return values**
- 0 – If successful.
- -EBUSY – Bus is busy.
- -EIO – General input / output error.
- -ENODEV – If a provisioned ID does not match to any target devices in the registered device list.
- -ENOSPC – No more free addresses can be assigned to target.
• -ENOSYS – Dynamic address assignment is not supported by the controller driver.

```c
int i3c_device_basic_info_get(struct i3c_device_desc *target)
```

Get basic information from device and update device descriptor.

This retrieves some basic information:

- Bus Characteristics Register (GETBCR)
- Device Characteristics Register (GETDCR)
- Max Read Length (GETMRL)
- Max Write Length (GETMWL) from the device and update the corresponding fields of the device descriptor.

This only updates the field(s) in device descriptor only if CCC operations succeed.

**Parameters**

- `target` – [inout] I3C target device descriptor.

**Return values**

- 0 – if successful.
- -EIO – General Input/Output error.

```c
struct i3c_config_controller
```

```c
#include <i3c.h>
```

Configuration parameters for I3C hardware to act as controller.

**Public Members**

```c
bool is_secondary
```

True if the controller is to be the secondary controller of the bus.

False to be the primary controller.

```c
uint32_t i3c
```

SCL frequency (in Hz) for I3C transfers.

```c
uint32_t i2c
```

SCL frequency (in Hz) for I2C transfers.

```c
uint8_t supported_hdr
```

Bit mask of supported HDR modes (0 - 7).

This can be used to enable or disable HDR mode supported by the hardware at runtime.

```c
struct i3c_config_custom
```

```c
#include <i3c.h>
```

Custom I3C configuration parameters.

This can be used to configure the I3C hardware on parameters not covered by

See also:

- `i3c_config_controller` or
See also:
i3c_config_target. Mostly used to configure vendor specific parameters of the I3C hardware.

Public Members

```c
uint32_t id
    ID of the configuration parameter.
```

```c
uintptr_t val
    Value of configuration parameter.
```

```c
void *ptr
    Pointer to configuration parameter.
    Mainly used to pointer to a struct that the device driver understands.
```

```c
struct i3c_device_id
    #include <i3c.h> Structure used for matching I3C devices.
```

Public Members

```c
const uint64_t pid
    Device Provisioned ID.
```

```c
struct i3c_device_desc
    #include <i3c.h> Structure describing a I3C target device.
```

Instances of this are passed to the I3C controller device APIs, for example:

- i3c_device_register() to tell the controller of a target device.
- i3c_transfers() to initiate data transfers between controller and target device.

Fields bus, pid and static_addr must be initialized by the module that implements the target device behavior prior to passing the object reference to I3C controller device APIs. static_addr can be zero if target device does not have static address.

Field node should not be initialized or modified manually.

Public Members

```c
const struct device *const bus
    Used to attach this node onto a linked list.
    I3C bus to which this target device is attached
```

```c
const struct device *const dev
    Device driver instance of the I3C device.
```
const uint64_t pid
    Device Provisioned ID.

const uint8_t static_addr
    Static address for this target device.

    0 if static address is not being used, and only dynamic address is used. This means that the target device must go through ENTDAA (Dynamic Address Assignment) to get a dynamic address before it can communicate with the controller. This means SETAASA and SETDASA CCC cannot be used to set dynamic address on the target device (as both are to tell target device to use static address as dynamic address).

const uint8_t init_dynamic_addr
    Initial dynamic address.

    This is specified in the device tree property “assigned-address” to indicate the desired dynamic address during address assignment (SETDASA and ENTDAA).

    0 if there is no preference.

uint8_t dynamic_addr
    Dynamic Address for this target device used for communication.

    This is to be set by the controller driver in one of the following situations:
    • During Dynamic Address Assignment (during ENTDAA)
    • Reset Dynamic Address Assignment (RSTDAA)
    • Set All Addresses to Static Addresses (SETAASA)
    • Set New Dynamic Address (SETNEWDA)
    • Set Dynamic Address from Static Address (SETDASA)

    0 if address has not been assigned.

uint8_t group_addr
    Group address for this target device.

    Set during:
    • Reset Group Address(es) (RSTGRPA)
    • Set Group Address (SETGRPA)

    0 if group address has not been assigned.

uint8_t bcr
    Bus Characteristic Register (BCR)

    • BCR[7:6]: Device Role
        – 0: I3C Target
        – 1: I3C Controller capable
        – 2: Reserved
        – 3: Reserved

    • BCR[5]: Advanced Capabilities
        – 0: Does not support optional advanced capabilities.
        – 1: Supports optional advanced capabilities which can be viewed via GETCAPS CCC.

    • BCR[4]: Virtual Target Support
        – 0: Is not a virtual target.
        – 1: Is a virtual target.

    • BCR[3]: Offline Capable
        – 0: Will always response to I3C commands.
        – 1: Will not always response to I3C commands.
• BCR[2]: IBI Payload
  – 0: No data bytes following the accepted IBI.
  – 1: One data byte (MDB, Mandatory Data Byte) follows the accepted IBI. Additional data bytes may also follow.
• BCR[1]: IBI Request Capable
  – 0: Not capable
  – 1: Capable
• BCR[0]: Max Data Speed Limitation
  – 0: No Limitation
  – 1: Limitation obtained via GETMXDS CCC.

```c
uint8_t dcr

Device Characteristic Register (DCR)

Describes the type of device. Refer to official documentation on what this number means.
```

```c
uint8_t maxrd

Maximum Read Speed.
```

```c
uint8_t maxwr

Maximum Write Speed.
```

```c
uint16_t max_read_turnaround

Maximum Read turnaround time in microseconds.
```

```c
uint16_t mrl

Maximum Read Length.
```

```c
uint16_t mwl

Maximum Write Length.
```

```c
uint8_t max_ibi

Maximum IBI Payload Size.

Valid only if BCR[2] is 1.
```

```c
i3c_target_ibi_cb_t ibi_cb

Private data by the controller to aid in transactions.

Do not modify. In-Band Interrupt (IBI) callback.
```

```c

```

```c
struct i3c_i2c_device_desc

#include <i3c.h> Structure describing a I2C device on I3C bus.

Instances of this are passed to the I3C controller device APIs, for example: () i3c_i2c_device_register() to tell the controller of an I2C device. () i3c_i2c_transfers() to initiate data transfers between controller and I2C device.

Fields other than node must be initialized by the module that implements the device behavior prior to passing the object reference to I3C controller device APIs.

Public Members

7.6. Peripherals
const struct device *bus
    Used to attach this node onto a linked list.
    I3C bus to which this I2C device is attached

const uint16_t addr
    Static address for this I2C device.

const uint8_t lvr
    Legacy Virtual Register (LVR)
    • LVR[7:5]: I2C device index:
        – 0: I2C device has a 50 ns spike filter where it is not affected by high frequency on SCL.
        – 1: I2C device does not have a 50 ns spike filter but can work with high frequency on SCL.
        – 2: I2C device does not have a 50 ns spike filter and cannot work with high frequency on SCL.
    • LVR[4]: I2C mode indicator:
        – 0: FM+ mode
        – 1: FM mode
    • LVR[3:0]: Reserved.

struct i3c_dev_attached_list
    #include <i3c.h> Structure for describing attached devices for a controller.
    This contains slists of attached I3C and I2C devices.
    This is a helper struct that can be used by controller device driver to aid in device management.

Public Members

struct i3c_addr_slots addr_slots
    Address slots:
    • Aid in dynamic address assignment.
    • Quick way to find out if a target address is a I3C or I2C device.

sys_slist_t i3c
    Linked list of attached I3C devices.

sys_slist_t i2c
    Linked list of attached I2C devices.

struct i3c_dev_list
    #include <i3c.h> Structure for describing known devices for a controller.
    This contains arrays of known I3C and I2C devices.
    This is a helper struct that can be used by controller device driver to aid in device management.
Public Members

struct i3c_device_desc *const i3c
    Pointer to array of known I3C devices.

struct i3c_i2c_device_desc *const i2c
    Pointer to array of known I2C devices.

const uint8_t num_i3c
    Number of I3C devices in array.

const uint8_t num_i2c
    Number of I2C devices in array.

struct i3c_driver_config
    #include <i3c.h> This structure is common to all I3C drivers and is expected to be the first element in the object pointed to by the config field in the device structure.

Public Members

struct i3c_dev_list dev_list
    I3C/I2C device list struct.

struct i3c_driver_data
    #include <i3c.h> This structure is common to all I3C drivers and is expected to be the first element in the driver's struct driver_data declaration.

Public Members

struct i3c_config_controller ctrl_config
    Controller Configuration.

struct i3c_dev_attached_list attached_dev
    Attached I3C/I2C devices and addresses.

group i3c_ccc
    I3C Common Command Codes.

Defines

I3C_CCC_BROADCAST_MAX_ID
    Maximum CCC ID for broadcast.

I3C_CCC_ENEC(broadcast)
    Enable Events Command.

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_DISEC(broadcast)
Disable Events Command.

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS(as, broadcast)
Enter Activity State.

Parameters
• as – Desired activity state
• broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS0(broadcast)
Enter Activity State 0.

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS1(broadcast)
Enter Activity State 1.

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS2(broadcast)
Enter Activity State 2.

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS3(broadcast)
Enter Activity State 3.

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_RSTDAA
Reset Dynamic Address Assignment (Broadcast)

I3C_CCC_ENTDA
Enter Dynamic Address Assignment (Broadcast)

I3C_CCC_DEFMTGS
Define List of Targets (Broadcast)

I3C_CCC_SETML_WL(broadcast)
Set Max Write Length (Broadcast or Direct)

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_SETML_RL(broadcast)
Set Max Read Length (Broadcast or Direct)

Parameters
- **broadcast** – True if broadcast, false if direct.

**I3C_CCC_ENTTM**
Enter Test Mode (Broadcast)

**I3C_CCC_SETBUSCON**
Set Bus Context (Broadcast)

**I3C_CCC_ENDXFER(broadcast)**
Data Transfer Ending Procedure Control.

**Parameters**
- **broadcast** – True if broadcast, false if direct.

**I3C_CCC_ENTHDR(x)**
Enter HDR Mode (HDR-DDR) (Broadcast)

**I3C_CCC_ENTHDR0**
Enter HDR Mode 0 (HDR-DDR) (Broadcast)

**I3C_CCC_ENTHDR1**
Enter HDR Mode 1 (HDR-TSP) (Broadcast)

**I3C_CCC_ENTHDR2**
Enter HDR Mode 2 (HDR-TSL) (Broadcast)

**I3C_CCC_ENTHDR3**
Enter HDR Mode 3 (HDR-BT) (Broadcast)

**I3C_CCC_ENTHDR4**
Enter HDR Mode 4 (Broadcast)

**I3C_CCC_ENTHDR5**
Enter HDR Mode 5 (Broadcast)

**I3C_CCC_ENTHDR6**
Enter HDR Mode 6 (Broadcast)

**I3C_CCC_ENTHDR7**
Enter HDR Mode 7 (Broadcast)

**I3C_CCC_SETXTIME(broadcast)**
Exchange Timing Information (Broadcast or Direct)

**Parameters**
- **broadcast** – True if broadcast, false if direct.

**I3C_CCC_SETAASA**
Set All Addresses to Static Addresses (Broadcast)

**I3C_CCC_RSTACT(broadcast)**
Target Reset Action.

**Parameters**

7.6. Peripherals
• broadcast – True if broadcast, false if direct.

I3C_CCC_DEFGRPA
   Define List of Group Address (Broadcast)

I3C_CCC_RSTGRPA(broadcast)
   Reset Group Address.

   Parameters
   • broadcast – True if broadcast, false if direct.

I3C_CCC_MLANE(broadcast)
   Multi-Lane Data Transfer Control (Broadcast)

I3C_CCC_VENDOR(broadcast, id)
   Vendor/Standard Extension.

   Parameters
   • broadcast – True if broadcast, false if direct.
   • id – Extension ID.

I3C_CCC_SETDASA
   Set Dynamic Address from Static Address (Direct)

I3C_CCC_SETNEWDA
   Set New Dynamic Address (Direct)

I3C_CCC_GETMWL
   Get Max Write Length (Direct)

I3C_CCC_GETMRL
   Get Max Read Length (Direct)

I3C_CCC_GETPID
   Get Provisioned ID (Direct)

I3C_CCC_GETBCR
   Get Bus Characteristics Register (Direct)

I3C_CCC_GETDCR
   Get Device Characteristics Register (Direct)

I3C_CCC_GETSTATUS
   Get Device Status (Direct)

I3C_CCC_GETACCCR
   Get Accept Controller Role (Direct)

I3C_CCC_SETBRGTGT
   Set Bridge Targets (Direct)
I3C_CCC_GETMXDS
   Get Max Data Speed (Direct)

I3C_CCC_GETCAPS
   Get Optional Feature Capabilities (Direct)

I3C_CCC_SETROUTE
   Set Route (Direct)

I3C_CCC_D2DXFER
   Device to Device(s) Tunneling Control (Direct)

I3C_CCC_GETXTIME
   Get Exchange Timing Information (Direct)

I3C_CCC_SETGRPDA
   Set Group Address (Direct)

I3C_CCC_ENEC.EVT_ENINTR
   Enable Events (ENEC) - Target Interrupt Requests.

I3C_CCC_ENEC.EVT_ENCR
   Enable Events (ENEC) - Controller Role Requests.

I3C_CCC_ENEC.EVT_ENHJ
   Enable Events (ENEC) - Hot-Join Event.

I3C_CCC_ENEC.EVT_ALL

I3C_CCC_DISEC.EVT_DISINTR
   Disable Events (DISEC) - Target Interrupt Requests.

I3C_CCC_DISEC.EVT_DISCR
   Disable Events (DISEC) - Controller Role Requests.

I3C_CCC_DISEC.EVT_DISHJ
   Disable Events (DISEC) - Hot-Join Event.

I3C_CCC_DISEC.EVT_ALL

I3C_CCC_EVT_INTR
   Events - Target Interrupt Requests.

I3C_CCC_EVT_CR
   Events - Controller Role Requests.

I3C_CCC_EVT_HJ
   Events - Hot-Join Event.
Zephyr Project Documentation, Release 3.6.0-rc3

I3C_CCC_EVT_ALL
   Bitmask for all events.

I3C_CCC_GETSTATUS_PROTOCOL_ERR
   GETSTATUS Format 1 - Protocol Error bit.

I3C_CCC_GETSTATUS_ACTIVITY_MODE_SHIFT
   GETSTATUS Format 1 - Activity Mode bit shift value.

I3C_CCC_GETSTATUS_ACTIVITY_MODE_MASK
   GETSTATUS Format 1 - Activity Mode bitmask.

I3C_CCC_GETSTATUS_ACTIVITY_MODE(status)
   GETSTATUS Format 1 - Activity Mode.
   Obtain Activity Mode from GETSTATUS Format 1 value obtained via GETSTATUS.

   Parameters
   • status – GETSTATUS Format 1 value

I3C_CCC_GETSTATUS_NUM_INT_SHIFT
   GETSTATUS Format 1 - Number of Pending Interrupts bit shift value.

I3C_CCC_GETSTATUS_NUM_INT_MASK
   GETSTATUS Format 1 - Number of Pending Interrupts bitmask.

I3C_CCC_GETSTATUS_NUM_INT(status)
   GETSTATUS Format 1 - Number of Pending Interrupts.
   Obtain Number of Pending Interrupts from GETSTATUS Format 1 value obtained via GETSTATUS.

   Parameters
   • status – GETSTATUS Format 1 value

I3C_CCC_GETSTATUS_PRECR_DEEP_SLEEP_DETECTED
   GETSTATUS Format 2 - PERCR - Deep Sleep Detected bit.

I3C_CCC_GETSTATUS_PRECR_HANDOFF_DELAY_NACK
   GETSTATUS Format 2 - PERCR - Handoff Delay NACK.

I3C_CCC_GETMXDS_MAX_SDR_FSCL_MAX
   Get Max Data Speed (GETMXDS) - Default Max Sustained Data Rate.

I3C_CCC_GETMXDS_MAX_SDR_FSCL_8MHZ
   Get Max Data Speed (GETMXDS) - 8MHz Max Sustained Data Rate.

I3C_CCC_GETMXDS_MAX_SDR_FSCL_6MHZ
   Get Max Data Speed (GETMXDS) - 6MHz Max Sustained Data Rate.

I3C_CCC_GETMXDS_MAX_SDR_FSCL_4MHZ
   Get Max Data Speed (GETMXDS) - 4MHz Max Sustained Data Rate.
I3C_CCC_GETMXDS_MAX_SDR_FSCL_2MHZ
Get Max Data Speed (GETMXDS) - 2MHz Max Sustained Data Rate.

I3C_CCC_GETMXDS_TSCO_8NS
Get Max Data Speed (GETMXDS) - Clock to Data Turnaround <= 8ns.

I3C_CCC_GETMXDS_TSCO_9NS
Get Max Data Speed (GETMXDS) - Clock to Data Turnaround <= 9ns.

I3C_CCC_GETMXDS_TSCO_10NS
Get Max Data Speed (GETMXDS) - Clock to Data Turnaround <= 10ns.

I3C_CCC_GETMXDS_TSCO_11NS
Get Max Data Speed (GETMXDS) - Clock to Data Turnaround <= 11ns.

I3C_CCC_GETMXDS_TSCO_12NS
Get Max Data Speed (GETMXDS) - Clock to Data Turnaround <= 12ns.

I3C_CCC_GETMXDS_TSCO_GT_12NS
Get Max Data Speed (GETMXDS) - Clock to Data Turnaround > 12ns.

I3C_CCC_GETMXDS_MAXWR_DEFINING_BYTE_SUPPORT
Get Max Data Speed (GETMXDS) - maxWr - Optional Defining Byte Support.

I3C_CCC_GETMXDS_MAXWR_MAX_SDR_FSCL_SHIFT
Get Max Data Speed (GETMXDS) - Max Sustained Data Rate bit shift value.

I3C_CCC_GETMXDS_MAXWR_MAX_SDR_FSCL_MASK
Get Max Data Speed (GETMXDS) - Max Sustained Data Rate bitmask.

I3C_CCC_GETMXDS_MAXRD_W2R_PERMITS_STOP_BETWEEN
Get Max Data Speed (GETMXDS) - maxRd - Write-to-Read Permits Stop Between.

I3C_CCC_GETMXDS_MAXRD_TSCO_SHIFT
Get Max Data Speed (GETMXDS) - maxRd - Clock to Data Turnaround bit shift value.

I3C_CCC_GETMXDS_MAXRD_TSCO_MASK
Get Max Data Speed (GETMXDS) - maxRd - Clock to Data Turnaround bitmask.

Parameters
- maxwr – GETMXDS maxWr value.

I3C_CCC_GETMXDS_MAXRD_W2R_PERMITS_STOP_BETWEEN
Get Max Data Speed (GETMXDS) - maxRd - Write-to-Read Permits Stop Between.

I3C_CCC_GETMXDS_MAXRD_TSCO_SHIFT
Get Max Data Speed (GETMXDS) - maxRd - Clock to Data Turnaround bit shift value.

I3C_CCC_GETMXDS_MAXRD_TSCO_MASK
Get Max Data Speed (GETMXDS) - maxRd - Clock to Data Turnaround bitmask.

Obtain Clock to Data Turnaround value from GETMXDS maxRd value obtained via GETMXDS.

7.6. Peripherals
Parameters

• `maxrd` – `GETMXDS` maxRd value.

**I3C_CCC_GETMXDS_MAXRD_MAX_SDR_FSCL_SHIFT**
Get Max Data Speed (`GETMXDS`) - maxRd - Max Sustained Data Rate bit shift value.

**I3C_CCC_GETMXDS_MAXRD_MAX_SDR_FSCL_MASK**
Get Max Data Speed (`GETMXDS`) - maxRd - Max Sustained Data Rate bitmask.

**I3C_CCC_GETMXDS_MAXRD_MAX_SDR_FSCL(maxrd)**
Get Max Data Speed (`GETMXDS`) - maxRd - Max Sustained Data Rate.

Obtain Max Sustained Data Rate value from `GETMXDS` maxRd value obtained via `GETMXDS`.

Parameters

• `maxrd` – `GETMXDS` maxRd value.

**I3C_CCC_GETMXDS_CRDHLY1_SET_BUS_ACT_STATE**
Get Max Data Speed (`GETMXDS`) - CRDHLY1 - Set Bus Activity State bit shift value.

**I3C_CCC_GETMXDS_CRDHLY1_CTRL_HANDOFF_ACT_STATE_SHIFT**
Get Max Data Speed (`GETMXDS`) - CRDHLY1 - Controller Handoff Activity State bit shift value.

**I3C_CCC_GETMXDS_CRDHLY1_CTRL_HANDOFF_ACT_STATE_MASK**
Get Max Data Speed (`GETMXDS`) - CRDHLY1 - Controller Handoff Activity State bitmask.

**I3C_CCC_GETMXDS_CRDHLY1_CTRL_HANDOFF_ACT_STATE(crhdly1)**
Get Max Data Speed (`GETMXDS`) - CRDHLY1 - Controller Handoff Activity State.

Obtain Controller Handoff Activity State value from `GETMXDS` value obtained via `GETMXDS`.

Parameters

• `crhdly1` – `GETMXDS` value.

**I3C_CCC_GETCAPS1_HDR_DDR**
Get Optional Feature Capabilities (`GETCAPS`) Format 1 - HDR-DDR mode bit.

**I3C_CCC_GETCAPS1_HDR_BT**
Get Optional Feature Capabilities (`GETCAPS`) Format 1 - HDR-BT mode bit.

**I3C_CCC_GETCAPS1_HDR_MODE(x)**
Get Optional Feature Capabilities (`GETCAPS`) - HDR Mode.

Get the bit corresponding to HDR mode.

Parameters

• `x` – HDR mode

**I3C_CCC_GETCAPS1_HDR_MODE0**
Get Optional Feature Capabilities (`GETCAPS`) Format 1 - HDR Mode 0.
I3C_CCC_GETCAPS1_HDR_MODE1
Get Optional Feature Capabilities (GETCAPS) Format 1 - HDR Mode 1.

I3C_CCC_GETCAPS1_HDR_MODE2
Get Optional Feature Capabilities (GETCAPS) Format 1 - HDR Mode 2.

I3C_CCC_GETCAPS1_HDR_MODE3
Get Optional Feature Capabilities (GETCAPS) Format 1 - HDR Mode 3.

I3C_CCC_GETCAPS1_HDR_MODE4
Get Optional Feature Capabilities (GETCAPS) Format 1 - HDR Mode 4.

I3C_CCC_GETCAPS1_HDR_MODE5
Get Optional Feature Capabilities (GETCAPS) Format 1 - HDR Mode 5.

I3C_CCC_GETCAPS1_HDR_MODE6
Get Optional Feature Capabilities (GETCAPS) Format 1 - HDR Mode 6.

I3C_CCC_GETCAPS1_HDR_MODE7
Get Optional Feature Capabilities (GETCAPS) Format 1 - HDR Mode 7.

I3C_CCC_GETCAPS2_HDRDDR_WRITE_ABORT
Get Optional Feature Capabilities (GETCAPS) Format 2 - HDR-DDR Write Abort bit.

I3C_CCC_GETCAPS2_HDRDDR_ABORT_CRC
Get Optional Feature Capabilities (GETCAPS) Format 2 - HDR-DDR Abort CRC bit.

I3C_CCC_GETCAPS2_GRPADDR_CAP_SHIFT
Get Optional Feature Capabilities (GETCAPS) Format 2 - Group Address Capabilities bit shift value.

I3C_CCC_GETCAPS2_GRPADDR_CAP_MASK
Get Optional Feature Capabilities (GETCAPS) Format 2 - Group Address Capabilities bitmask.

I3C_CCC_GETCAPS2_GRPADDR_CAP(getcaps2)
Get Optional Feature Capabilities (GETCAPS) Format 2 - Group Address Capabilities.
Obtain Group Address Capabilities value from GETCAPS Format 2 value obtained via GETCAPS.

Parameters
  • getcaps2 – GETCAPS2 value.

I3C_CCC_GETCAPS2_SPEC_VER_SHIFT
Get Optional Feature Capabilities (GETCAPS) Format 2 - I3C 1.x Specification Version bit shift value.

I3C_CCC_GETCAPS2_SPEC_VER_MASK
Get Optional Feature Capabilities (GETCAPS) Format 2 - I3C 1.x Specification Version bitmask.
I3C_CCC_GETCAPS2_SPEC_VER(getcaps2)
Get Optional Feature Capabilities (GETCAPS) Format 2 - I3C 1.x Specification Version.
Obtain I3C 1.x Specification Version value from GETCAPS Format 2 value obtained via
GETCAPS.

Parameters
- getcaps2 – GETCAPS2 value.

I3C_CCC_GETCAPS3_MLANE_SUPPORT
Get Optional Feature Capabilities (GETCAPS) Format 3 - Multi-Lane Data Transfer Support bit.

I3C_CCC_GETCAPS3_D2DXFER_SUPPORT
Get Optional Feature Capabilities (GETCAPS) Format 3 - Device to Device Transfer (D2DXFER) Support bit.

I3C_CCC_GETCAPS3_D2DXFER_IBI_CAPABLE
Get Optional Feature Capabilities (GETCAPS) Format 3 - Device to Device Transfer (D2DXFER) IBI Capable bit.

I3C_CCC_GETCAPS3_GETCAPS_DEFINING_BYTE_SUPPORT
Get Optional Feature Capabilities (GETCAPS) Format 3 - Defining Byte Support in GETCAPS bit.

I3C_CCC_GETCAPS3_GETSTATUS_DEFINING_BYTE_SUPPORT
Get Optional Feature Capabilities (GETCAPS) Format 3 - Defining Byte Support in GETSTATUS bit.

I3C_CCC_GETCAPS3_HDRBT_CRC32_SUPPORT

I3C_CCC_GETCAPS3_IBI_MDR_PENDING_READ_NOTIFICATION
Get Optional Feature Capabilities (GETCAPS) Format 3 - IBI MDB Support for Pending Read Notification bit.

Enums

enum i3c_ccc_getstatus_fmt
Indicate which format of GETSTATUS to use.

Values:

- enumerator GETSTATUS_FORMAT_1
  GETSTATUS Format 1.

- enumerator GETSTATUS_FORMAT_2
  GETSTATUS Format 2.

enum i3c_ccc_getstatus_defbyte
Defining byte values for GETSTATUS Format 2.

Values:
enumerator **GETSTATUS_FORMAT_2_TGTSTAT** = 0x00U
   Target status.

enumerator **GETSTATUS_FORMAT_2_PRECR** = 0x91U
   PRECR - Alternate status format describing Controller-capable device.

enumerator **GETSTATUS_FORMAT_2_INVALID** = 0x100U
   Invalid defining byte.

enum **i3c_ccc_rstact_defining_byte**
   Enum for I3C Reset Action (RSTACT) Defining Byte Values.
   
   **Values:**

   enumerator **I3C_CCC_RSTACT_NO_RESET** = 0x00U
      No Reset on Target Reset Pattern.

   enumerator **I3C_CCC_RSTACT_PERIPHERAL_ONLY** = 0x01U
      Reset the I3C Peripheral Only.

   enumerator **I3C_CCC_RSTACT_RESET_WHOLE_TARGET** = 0x02U
      Reset the Whole Target.

   enumerator **I3C_CCC_RSTACT_DEBUG_NETWORK_ADAPTER** = 0x03U
      Debug Network Adapter Reset.

   enumerator **I3C_CCC_RSTACT_VIRTUAL_TARGET_DETECT** = 0x04U
      Virtual Target Detect.

**Functions**

static inline bool **i3c_ccc_is_payload_broadcast**(const struct **i3c_ccc_payload** *payload)
   Test if I3C CCC payload is for broadcast.
   This tests if the CCC payload is for broadcast.

   **Parameters**
   
   • payload – [in] Pointer to the CCC payload.

   **Return values**
   
   • true – if payload target is broadcast
   • false – if payload target is direct

int **i3c_ccc_do_getbcr**(struct **i3c_device_desc** *target, struct **i3c_ccc_getbcr** *bcr)
   Get BCR from a target.
   Helper function to get BCR (Bus Characteristic Register) from target device.

   **See also:**

   **i3c_do_ccc**
Parameters

- **target** – [in] Pointer to the target device descriptor.
- **bcr** – [out] Pointer to the BCR payload structure.

Returns

```c
int i3c_ccc_do_getdcr(struct i3c_device_desc *target, struct i3c_ccc_getdcr *dcr)
```

Get DCR from a target.

Helper function to get DCR (Device Characteristic Register) from target device.

See also:

- `i3c_do_ccc`

Parameters

- **target** – [in] Pointer to the target device descriptor.
- **dcr** – [out] Pointer to the DCR payload structure.

Returns

```c
int i3c_ccc_do_getpid(struct i3c_device_desc *target, struct i3c_ccc_getpid *pid)
```

Get PID from a target.

Helper function to get PID (Provisioned ID) from target device.

See also:

- `i3c_do_ccc`

Parameters

- **target** – [in] Pointer to the target device descriptor.
- **pid** – [out] Pointer to the PID payload structure.

Returns

```c
int i3c_ccc_do_rstact_all(const struct device *controller, enum i3c_ccc_rstact_defining_byte action)
```

Broadcast RSTACT to reset I3C Peripheral.

Helper function to broadcast Target Reset Action (RSTACT) to all connected targets to Reset the I3C Peripheral Only (0x01).

See also:

- `i3c_do_ccc`

Parameters

- **controller** – [in] Pointer to the controller device driver instance.

Returns
int i3c_ccc_do_rstdaa all(const struct device *controller)
  Broadcast RSTDAA to reset dynamic addresses for all targets.
  Helper function to reset dynamic addresses of all connected targets.

See also:
i3c_do_ccc

Parameters
  • controller – [in] Pointer to the controller device driver instance.

Returns

int i3c_ccc_do_setdasa(const struct i3c_device_desc *target)
  Set Dynamic Address from Static Address for a target.
  Helper function to do SETDASA (Set Dynamic Address from Static Address) for a particular target.
  Note this does not update target with the new dynamic address.

See also:
i3c_do_ccc

Parameters
  • target – [in] Pointer to the target device descriptor where the device is configured with a static address.

Returns

int i3c_ccc_do_setnewda(const struct i3c_device_desc *target, struct i3c_ccc_address new_da)
  Set New Dynamic Address for a target.
  Helper function to do SETNEWDA(Set New Dynamic Address) for a particular target.
  Note this does not update target with the new dynamic address.

See also:
i3c_do_ccc

Parameters
  • target – [in] Pointer to the target device descriptor where the device is configured with a static address.

Returns

int i3c_ccc_do_events_all_set(const struct device *controller, bool enable, struct i3c_ccc_events *events)
  Broadcast ENEC/DISEC to enable/disable target events.
  Helper function to broadcast Target Events Command to enable or disable target events (ENEC/DISEC).
See also:

\texttt{i3c\_do\_ccc}

\textbf{Parameters}

- \texttt{controller} – \texttt{[in]} Pointer to the controller device driver instance.
- \texttt{enable} – \texttt{[in]} ENEC if true, DISEC if false.
- \texttt{events} – \texttt{[in]} Pointer to the event struct.

\textbf{Returns}

\texttt{int i3c\_ccc\_do\_events\_set(struct i3c\_device\_desc \*target, bool enable, struct i3c\_ccc\_events \*events)}

Direct CCC ENEC/DISEC to enable/disable target events.

Helper function to send Target Events Command to enable or disable target events (ENEC/DISEC) on a single target.

See also:

\texttt{i3c\_do\_ccc}

\textbf{Parameters}

- \texttt{target} – \texttt{[in]} Pointer to the target device descriptor.
- \texttt{enable} – \texttt{[in]} ENEC if true, DISEC if false.
- \texttt{events} – \texttt{[in]} Pointer to the event struct.

\textbf{Returns}

\texttt{int i3c\_ccc\_do\_setmwl\_all(const struct device \*controller, const struct i3c\_ccc\_mwl \*mwl)}

Broadcast SETMWL to Set Maximum Write Length.

Helper function to do SETMWL (Set Maximum Write Length) to all connected targets.

See also:

\texttt{i3c\_do\_ccc}

\textbf{Parameters}

- \texttt{controller} – \texttt{[in]} Pointer to the controller device driver instance.
- \texttt{mwl} – \texttt{[in]} Pointer to SETMWL payload.

\textbf{Returns}

\texttt{int i3c\_ccc\_do\_setmwl(const struct i3c\_device\_desc \*target, const struct i3c\_ccc\_mwl \*mwl)}

Single target SETMWL to Set Maximum Write Length.

Helper function to do SETMWL (Set Maximum Write Length) to one target.

See also:

\texttt{i3c\_do\_ccc}
Parameters
• target – [in] Pointer to the target device descriptor.
• mwl – [in] Pointer to SETMWL payload.

Returns
int i3c_ccc_do_getmwl(const struct i3c_device_desc *target, struct i3c_ccc_mwl *mwl)
Single target GETMWL to Get Maximum Write Length.
Helper function to do GETMWL (Get Maximum Write Length) of one target.

See also:
i3c_do_ccc

Parameters
• target – [in] Pointer to the target device descriptor.
• mwl – [out] Pointer to GETMWL payload.

Returns
int i3c_ccc_do_setmrl_all(const struct device *controller, const struct i3c_ccc_mrl *mrl, bool has_ibi_size)
Broadcast SETMRL to Set Maximum Read Length.
Helper function to do SETMRL (Set Maximum Read Length) to all connected targets.

See also:
i3c_do_ccc

Parameters
• controller – [in] Pointer to the controller device driver instance.
• mrl – [in] Pointer to SETMRL payload.
• has_ibi_size – [in] True if also sending the optional IBI payload size.
  False if not sending.

Returns
int i3c_ccc_do_setmrl(const struct i3c_device_desc *target, const struct i3c_ccc_mrl *mrl)
Single target SETMRL to Set Maximum Read Length.
Helper function to do SETMRL (Set Maximum Read Length) to one target.
Note this uses the BCR of the target to determine whether to send the optional IBI payload size.

See also:
i3c_do_ccc

Parameters
• target – [in] Pointer to the target device descriptor.
• mrl – [in] Pointer to SETMRL payload.
Returns

int i3c_ccc_do_getmrl(const struct i3c_device_desc *target, struct i3c_ccc_mrl *mrl)

Single target GETMRL to Get Maximum Read Length.
Helper function to do GETMRL (Get Maximum Read Length) of one target.
Note this uses the BCR of the target to determine whether to send the optional IBI payload size.

See also:

i3c_do_ccc

Parameters

• target – [in] Pointer to the target device descriptor.
• mrl – [out] Pointer to GETMRL payload.

Returns

int i3c_ccc_do_getstatus(const struct i3c_device_desc *target, union i3c_ccc_getstatus *status, enum i3c_ccc_getstatus_fmt fmt, enum i3c_ccc_getstatus_defbyte defbyte)

Single target GETSTATUS to Get Target Status.
Helper function to do GETSTATUS (Get Target Status) of one target.
Note this uses the BCR of the target to determine whether to send the optional IBI payload size.

See also:

i3c_do_ccc

Parameters

• target – [in] Pointer to the target device descriptor.
• status – [out] Pointer to GETSTATUS payload.

Returns

static inline int i3c_ccc_do_getstatus_fmt1(const struct i3c_device_desc *target, union i3c_ccc_getstatus *status)

Single target GETSTATUS to Get Target Status (Format 1).
Helper function to do GETSTATUS (Get Target Status, format 1) of one target.

See also:

i3c_do_ccc

Parameters

• target – [in] Pointer to the target device descriptor.
• status – [out] Pointer to GETSTATUS payload.
Zephyr Project Documentation, Release 3.6.0-rc3

Returns

static inline int i3c_ccc_do_getstatus_fmt2(const struct i3c_device_desc *target, union i3c_ccc_getstatus *status, enum i3c_ccc_getstatus_defbyte defbyte)

Single target GETSTATUS to Get Target Status (Format 2).
Helper function to do GETSTATUS (Get Target Status, format 2) of one target.

See also:
i3c_do_ccc

Parameters

- **target** – [in] Pointer to the target device descriptor.
- **status** – [out] Pointer to GETSTATUS payload.

Returns

struct i3c_ccc_target_payload
#include <ccc.h> Payload structure for Direct CCC to one target.

Public Members

uint8_t addr
Target address.

uint8_t rnw
0 for Write, 1 for Read

uint8_t *data
- For Write CCC, pointer to the byte array of data to be sent, which may contain the Sub-Command Byte and additional data.
- For Read CCC, pointer to the byte buffer for data to be read into.

size_t data_len
Length in bytes for data.

size_t num_xfer
Total number of bytes transferred.
A Target can issue an EoD or the Controller can abort a transfer before the length of the buffer. It is expected for the driver to write to this after the transfer.

struct i3c_ccc_payload
#include <ccc.h> Payload structure for one CCC transaction.
Public Members

```c
uint8_t id
    The CCC ID (I3C_CCC_*)
```

```c
uint8_t *data
    Pointer to byte array of data for this CCC.
    This is the bytes following the CCC command in CCC frame. Set to NULL if no associated data.
```

```c
size_t data_len
    Length in bytes for optional data array.
```

```c
size_t num_xfer
    Total number of bytes transferred.
    A Controller can abort a transfer before the length of the buffer. It is expected for the driver to write to this after the transfer.
```

```c
struct i3c_ccc_target_payload *payloads
    Array of struct i3c_ccc_target_payload.
    Each element describes the target and associated payloads for this CCC.
    Use with Direct CCC.
```

```c
size_t num_targets
    Number of targets.
```

```c
struct i3c_ccc_events
    #include <ccc.h> Payload for ENEC/DISEC CCC (Target Events Command).
```

Public Members

```c
uint8_t events
    Event byte:
    - Bit[0]: ENINT/DISINT: Target Interrupt Requests
    - Bit[1]: ENCR/DISCR: Controller Role Requests
    - Bit[3]: ENHJ/DISHJ: Hot-Join Event
```

```c
struct i3c_ccc_mwl
    #include <ccc.h> Payload for SETMWL/GETMWL CCC (Set/Get Maximum Write Length).
```

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.
Public Members

uint16_t len
Maximum Write Length.

struct i3c_ccc_mrl
#include <ccc.h> Payload for SETMRL/GETMRL CCC (Set/Get Maximum Read Length).

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.

Public Members

uint16_t len
Maximum Read Length.

uint8_t ibi_len
Optional IBI Payload Size.

struct i3c_ccc_deftgts_active_controller
#include <ccc.h> The active controller part of payload for DEFTGTS CCC.
This is used by DEFTGTS (Define List of Targets) CCC to describe the active controller on the I3C bus.

Public Members

uint8_t addr
Dynamic Address of Active Controller.

uint8_t dcr
Device Characteristic Register of Active Controller.

uint8_t bcr
Bus Characteristic Register of Active Controller.

uint8_t static_addr
Static Address of Active Controller.

struct i3c_ccc_deftgts_target
#include <ccc.h> The target device part of payload for DEFTGTS CCC.
This is used by DEFTGTS (Define List of Targets) CCC to describe the existing target devices on the I3C bus.
Public Members

uint8_t addr
  Dynamic Address of a target device, or a group address.

uint8_t dcr
  Device Characteristic Register of a I3C target device or a group.

uint8_t lvr
  Legacy Virtual Register for legacy I2C device.

uint8_t bcr
  Bus Characteristic Register of a target device or a group.

uint8_t static_addr
  Static Address of a target device or a group.

struct i3c_ccc_deftgts
  #include <ccc.h> Payload for DEFTGTS CCC (Define List of Targets).

Note: i3c_ccc_deftgts_target is an array of targets, where the number of elements is dependent on the number of I3C targets on the bus. Please have enough space for both read and write of this CCC.

Public Members

struct i3c_ccc_deftgts_active_controller active_controller
  Data describing the active controller.

struct i3c_ccc_deftgts_target targets[
  Data describing the target(s) on the bus.

struct i3c_ccc_address
  #include <ccc.h> Payload for a single device address.

This is used for:
  • SETDASA (Set Dynamic Address from Static Address)
  • SETNEWDA (Set New Dynamic Address)
  • SETGRPA (Set Group Address)
  • GETACCCR (Get Accept Controller Role)

Note that the target address is encoded within struct i3c_ccc_target_payload instead of being encoded in this payload.

Public Members
uint8_t addr

• For SETDASA, Static Address to be assigned as Dynamic Address.
• For SETNEWDA, new Dynamic Address to be assigned.
• For SETGRPA, new Group Address to be set.
• For GETACCCR, the correct address of Secondary Controller.

Note: For SETDATA, SETNEWDA and SETGRPA, the address is left-shift by 1, and bit[0] is always 0.

Note: For SET GETACCCR, the address is left-shift by 1, and bit[0] is the calculated odd parity bit.

struct i3c_ccc_getpid
#include <ccc.h> Payload for GETPID CCC (Get Provisioned ID).

Public Members

uint8_t pid[6]
48-bit Provisioned ID.

Note: Data is big-endian where first byte is MSB.

struct i3c_ccc_getbcr
#include <ccc.h> Payload for GETBCR CCC (Get Bus Characteristics Register).

Public Members

uint8_t bcr
Bus Characteristics Register.

struct i3c_ccc_getdcr
#include <ccc.h> Payload for GETDCR CCC (Get Device Characteristics Register).

Public Members

uint8_t dcr
Device Characteristics Register.

union i3c_ccc_getstatus
#include <ccc.h> Payload for GETSTATUS CCC (Get Device Status).

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Public Members

uint16_t status
   Device Status.
   
   • Bit[15:8]: Reserved.
   • Bit[7:6]: Activity Mode.
   • Bit[5]: Protocol Error.
   • Bit[4]: Reserved.
   • Bit[3:0]: Number of Pending Interrupts.

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.

struct i3c_ccc_getstatus fmt1

uint16_t tgtstat
   Defining Byte 0x00: TGTSTAT.

See also:
   i3c_ccc_getstatus::fmt1::status

uint16_t precr
   Defining Byte 0x91: PRECR.
   
   • Bit[15:8]: Vendor Reserved
   • Bit[7:2]: Reserved
   • Bit[1]: Handoff Delay NACK
   • Bit[0]: Deep Sleep Detected

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.

uint16_t raw_u16

union i3c_ccc_getstatus fmt2

struct i3c_ccc_setbrgtgt_tgt
   #include <ccc.h> One Bridged Target for SETBRGTGT payload.

Public Members

uint8_t addr
   Dynamic address of the bridged target.
**Note:** The address is left-shift by 1, and bit[0] is always 0.

`uint16_t id`
16-bit ID for the bridged target.

**Note:** For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.

```c
struct i3c_ccc_setbrgtgt
#include <ccc.h>
Payload for SETBRGTGT CCC (Set Bridge Targets).
Note that the bridge target address is encoded within struct `i3c_ccc_target_payload` instead of being encoded in this payload.

**Public Members**

`uint8_t count`
Number of bridged targets.

`struct i3c_ccc_setbrgtgt_tgt targets[]`
Array of bridged targets.

```c
union i3c_ccc_getmxds
#include <ccc.h>
Payload for GETMXDS CCC (Get Max Data Speed).

**Note:** This is only for GETMXDS Format 1 and Format 2.

**Public Members**

`uint8_t maxwr`
maxWr

`uint8_t maxrd`
maxRd

`struct i3c_ccc_getmxds fmt1`

`uint8_t maxrdturn[3]`
Maximum Read Turnaround Time in microsecond.
This is in little-endian where first byte is LSB.

`struct i3c_ccc_getmxds fmt2`
uint8_t wrrdtturn

Defining Byte 0x00: WRRDTURN.

See also:

i3c_ccc_getmxds::fmt2

uint8_t crhdly1

Defining Byte 0x91: CRHDLY.

• Bit[2]: Set Bus Activity State
• Bit[1:0]: Controller Handoff Activity State

struct i3c_ccc_getmxds fmt3

struct i3c_ccc_getcaps

#include <ccc.h> Payload for GETCAPS CCC (Get Optional Feature Capabilities).

Note: Only support GETCAPS Format 1.

Public Members

uint8_t getcaps[4]


group i3c_addresses

I3C Address-related Helper Code.

Defines

I3C_BROADCAST_ADDR

Broadcast Address on I3C bus.

I3C_MAX_ADDR

Maximum value of device addresses.

Enums

enum i3c_addr_slot_status

Enum to indicate whether an address is reserved, has I2C/I3C device attached, or no device attached.

Values:
enumerator I3C_ADDR_SLOT_STATUS_FREE = 0U
Address has not device attached.

enumerator I3C_ADDR_SLOT_STATUS_RSVD
Address is reserved.

enumerator I3C_ADDR_SLOT_STATUS_I3C_DEV
Address is associated with an I3C device.

enumerator I3C_ADDR_SLOT_STATUS_I2C_DEV
Address is associated with an I2C device.

enumerator I3C_ADDR_SLOT_STATUS_MASK = 0x03U
Bit masks used to filter status bits.

Functions

int i3c_addr_slots_init(const struct device *dev)
Initialize the I3C address slots struct.
This clears out the assigned address bits, and set the reserved address bits according
to the I3C specification.

Parameters
  • dev – Pointer to controller device driver instance.

Return values
  • 0 – if successful.
  • -EINVAL – if duplicate addresses.

void i3c_addr_slots_set(struct i3c_addr_slots *slots, uint8_t dev_addr, enum
i3c_addr_slot_status status)
Set the address status of a device.

Parameters
  • slots – Pointer to the address slots structure.
  • dev_addr – Device address.
  • status – New status for the address dev_addr.

enum i3c_addr_slot_status i3c_addr_slots_status(struct i3c_addr_slots *slots, uint8_t
dev_addr)
Get the address status of a device.

Parameters
  • slots – Pointer to the address slots structure.
  • dev_addr – Device address.

Returns
  Address status for the address dev_addr.
bool i3c_addr_slots_is_free(struct i3c_addr_slots *slots, uint8_t dev_addr)

Check if the address is free.

**Parameters**

• slots – Pointer to the address slots structure.
• dev_addr – Device address.

**Return values**

• true – if address is free.
• false – if address is not free.

uint8_t i3c_addr_slots_next_free_find(struct i3c_addr_slots *slots, uint8_t start_addr)

This can be used to find the next free address that can be assigned to a new device.

**Parameters**

• slots – Pointer to the address slots structure.
• start_addr – Where to start searching

**Returns**

The next free address, or 0 if none found.

static inline void i3c_addr_slots_mark_free(struct i3c_addr_slots *addr_slots, uint8_t addr)

Mark the address as free (not used) in device list.

**Parameters**

• addr_slots – Pointer to the address slots struct.
• addr – Device address.

static inline void i3c_addr_slots_mark_rsvd(struct i3c_addr_slots *addr_slots, uint8_t addr)

Mark the address as reserved in device list.

**Parameters**

• addr_slots – Pointer to the address slots struct.
• addr – Device address.

static inline void i3c_addr_slots_mark_i3c(struct i3c_addr_slots *addr_slots, uint8_t addr)

Mark the address as I3C device in device list.

**Parameters**

• addr_slots – Pointer to the address slots struct.
• addr – Device address.

static inline void i3c_addr_slots_mark_i2c(struct i3c_addr_slots *addr_slots, uint8_t addr)

Mark the address as I2C device in device list.

**Parameters**

• addr_slots – Pointer to the address slots struct.
• addr – Device address.
struct i3c_addr_slots
#include <addresses.h> Structure to keep track of addresses on I3C bus.

group i3c_target_device
I3C Target Device API.

Functions

static inline int i3c_target_tx_write(const struct device *dev, uint8_t *buf, uint16_t len)
Writes to the target's TX FIFO.
Write to the TX FIFO dev I3C bus driver using the provided buffer and length. Some
I3C targets will NACK read requests until data is written to the TX FIFO. This function
will write as much as it can to the FIFO return the total number of bytes written. It is
then up to the application to utilize the target callbacks to write the remaining data.
Negative returns indicate error.
Most of the existing hardware allows simultaneous support for master and target
mode. This is however not guaranteed.

Parameters
• dev – Pointer to the device structure for an I3C controller driver config-
ured in target mode.
• buf – Pointer to the buffer
• len – Length of the buffer

Return values
• Total – number of bytes written
• -ENOTSUP – Not in Target Mode
• -ENOSPC – No space in Tx FIFO
• -ENOSYS – If target mode is not implemented

static inline int i3c_target_register(const struct device *dev, struct i3c_target_config *cfg)
Registers the provided config as target device of a controller.
Enable I3C target mode for the dev I3C bus driver using the provided config struct
(cfg) containing the functions and parameters to send bus events. The I3C target will
be registered at the address provided as i3c_target_config::address struct member. Any
I3C bus events related to the target mode will be passed onto I3C target device driver
via a set of callback functions provided in the 'callbacks' struct member.
Most of the existing hardware allows simultaneous support for master and target
mode. This is however not guaranteed.

Parameters
• dev – Pointer to the device structure for an I3C controller driver config-
ured in target mode.
• cfg – Config struct with functions and parameters used by the I3C target
driver to send bus events

Return values
• 0 – Is successful
• -EINVAL – If parameters are invalid
• -EIO – General input / output error.
• -ENOSYS – If target mode is not implemented

static inline int i3c_target_unregister(const struct device *dev, struct i3c_target_config *cfg)

Unregisters the provided config as target device.

This routine disables I3C target mode for the dev I3C bus driver using the provided config struct (cfg) containing the functions and parameters to send bus events.

Parameters

• dev – Pointer to the device structure for an I3C controller driver configured in target mode.
• cfg – Config struct with functions and parameters used by the I3C target driver to send bus events

Return values

• 0 – Is successful
• -EINVAL – If parameters are invalid
• -ENOSYS – If target mode is not implemented

struct i3c_config_target

#include <target_device.h> Configuration parameters for I3C hardware to act as target device.

This can also be used to configure the controller if it is to act as a secondary controller on the bus.

Public Members

bool enable

If the hardware is to act as a target device on the bus.

uint8_t static_addr

I3C target address.

Used used when operates as secondary controller or as a target device.

uint64_t pid

Provisioned ID.

bool pid_random

True if lower 32-bit of Provisioned ID is random.

This sets the bit 32 of Provisioned ID which means the lower 32-bit is random value.

uint8_t bcr

Bus Characteristics Register (BCR).

uint8_t dcr

Device Characteristics Register (DCR).
uint16_t max_read_len
    Maximum Read Length (MRL).

uint16_t max_write_len
    Maximum Write Length (MWL).

uint8_t supported_hdr
    Bit mask of supported HDR modes (0 - 7).
    This can be used to enable or disable HDR mode supported by the hardware at runtime.

struct i3c_target_config
    #include <target_device.h> Structure describing a device that supports the I3C target API.
    Instances of this are passed to the i3c_target_register() and i3c_target_unregister() functions to indicate addition and removal of a target device, respective.
    Fields other than node must be initialized by the module that implements the device behavior prior to passing the object reference to i3c_target_register().

Public Members

sys_snipe_t node
    Private, do not modify.

uint8_t flags
    Flags for the target device defined by I3C_TARGET_FLAGS_* constants.

uint8_t address
    Address for this target device.

const struct i3c_target_callbacks *callbacks
    Callback functions.

struct i3c_target_callbacks
    #include <target_device.h>

Public Members

int (*write_requested_cb)(struct i3c_target_config *config)
    Function called when a write to the device is initiated.
    This function is invoked by the controller when the bus completes a start condition for a write operation to the address associated with a particular device.
    A success return shall cause the controller to ACK the next byte received. An error return shall cause the controller to NACK the next byte received.

    Param config
        Configuration structure associated with the device to which the operation is addressed.
Return
0 if the write is accepted, or a negative error code.

```c
int (*write_received_cb)(struct i3c_target_config *config, uint8_t val)
```

Function called when a write to the device is continued.

This function is invoked by the controller when it completes reception of a byte of data in an ongoing write operation to the device.

A success return shall cause the controller to ACK the next byte received. An error return shall cause the controller to NACK the next byte received.

**Param config**
Configuration structure associated with the device to which the operation is addressed.

**Param val**
the byte received by the controller.

**Return**
0 if more data can be accepted, or a negative error code.

```c
int (*read_requested_cb)(struct i3c_target_config *config, uint8_t *val)
```

Function called when a read from the device is initiated.

This function is invoked by the controller when the bus completes a start condition for a read operation from the address associated with a particular device.

The value returned in val will be transmitted. A success return shall cause the controller to react to additional read operations. An error return shall cause the controller to ignore bus operations until a new start condition is received.

**Param config**
Configuration structure associated with the device to which the operation is addressed.

**Param val**
Pointer to storage for the first byte of data to return for the read request.

**Return**
0 if more data can be requested, or a negative error code.

```c
int (*read_processed_cb)(struct i3c_target_config *config, uint8_t *val)
```

Function called when a read from the device is continued.

This function is invoked by the controller when the bus is ready to provide additional data for a read operation from the address associated with the device device.

The value returned in val will be transmitted. A success return shall cause the controller to react to additional read operations. An error return shall cause the controller to ignore bus operations until a new start condition is received.

**Param config**
Configuration structure associated with the device to which the operation is addressed.

**Param val**
Pointer to storage for the next byte of data to return for the read request.

**Return**
0 if data has been provided, or a negative error code.

```c
int (*stop_cb)(struct i3c_target_config *config)
```

Function called when a stop condition is observed after a start condition addressed to a particular device.

This function is invoked by the controller when the bus is ready to provide additional data for a read operation from the address associated with the device device.
After the function returns the controller shall enter a state where it is ready to react to new start conditions.

**Param config**
Configuration structure associated with the device to which the operation is addressed.

**Return**
Ignored.

```c
struct i3c_target_driver_api
#include <target_device.h>
```

## 7.6.26 Inter-Integrated Circuit (I2C) Bus

### Overview

**Note:** The terminology used in Zephyr I2C APIs follows that of the *NXP I2C Bus Specification Rev 7.0*. These changed from previous revisions as of its release October 1, 2021.

I2C (Inter-Integrated Circuit, pronounced “eye squared see”) is a commonly-used two-signal shared peripheral interface bus. Many system-on-chip solutions provide controllers that communicate on an I2C bus. Devices on the bus can operate in two roles: as a “controller” that initiates transactions and controls the clock, or as a “target” that responds to transaction commands. A I2C controller on a given SoC will generally support the controller role, and some will also support the target mode. Zephyr has API for both roles.

**I2C Controller API**  Zephyr’s I2C controller API is used when an I2C peripheral controls the bus, in particularly the start and stop conditions and the clock. This is the most common mode, used to interact with I2C devices like sensors and serial memory.

This API is supported in all in-tree I2C peripheral drivers and is considered stable.

**I2C Target API**  Zephyr’s I2C target API is used when an I2C peripheral responds to transactions initiated by a different controller on the bus. It might be used for a Zephyr application with transducer roles that are controlled by another device such as a host processor.

This API is supported in very few in-tree I2C peripheral drivers. The API is considered experimental, as it is not compatible with the capabilities of all I2C peripherals supported in controller mode.

### Configuration Options

Related configuration options:

- `CONFIG_I2C`

### API Reference

*group* `i2c_interface`

I2C Interface.


Defines

I2C_SPEED_STANDARD
I2C Standard Speed: 100 kHz.

I2C_SPEED_FAST
I2C Fast Speed: 400 kHz.

I2C_SPEED_FAST_PLUS
I2C Fast Plus Speed: 1 MHz.

I2C_SPEED_HIGH
I2C High Speed: 3.4 MHz.

I2C_SPEED_ULTRA
I2C Ultra Fast Speed: 5 MHz.

I2C_SPEED_DT
Device Tree specified speed.

I2C_SPEED_SHIFT
I2C_SPEED_SET(speed)

I2C_SPEED_MASK
I2C_SPEED_GET(cfg)

I2C_ADDR_10_BITS
Use 10-bit addressing.
DEPRECATED - Use I2C_MSG_ADDR_10_BITS instead.

I2C_MODE_CONTROLLER
Peripheral to act as Controller.

I2C_DT_SPEC_GET_ON_I3C(node_id)
Structure initializer for i2c_dt_spec from devicetree (on I3C bus)
This helper macro expands to a static initializer for a struct i2c_dt_spec by reading the relevant bus and address data from the devicetree.

Parameters
  • node_id – Devicetree node identifier for the I2C device whose struct i2c_dt_spec to create an initializer for

I2C_DT_SPEC_GET_ON_I2C(node_id)
Structure initializer for i2c_dt_spec from devicetree (on I2C bus)
This helper macro expands to a static initializer for a struct i2c_dt_spec by reading the relevant bus and address data from the devicetree.

Parameters
  • node_id – Devicetree node identifier for the I2C device whose struct i2c_dt_spec to create an initializer for
I2C_DT_SPEC_GET(node_id)
Structure initializer for \texttt{i2c\_dt\_spec} from devicetree.
This helper macro expands to a static initializer for a struct \texttt{i2c\_dt\_spec} by reading the relevant bus and address data from the devicetree.

**Parameters**
- \texttt{node\_id} – Devicetree node identifier for the I2C device whose struct \texttt{i2c\_dt\_spec} to create an initializer for

I2C_DT_SPEC_INST_GET(inst)
Structure initializer for \texttt{i2c\_dt\_spec} from devicetree instance.
This is equivalent to \texttt{I2C\_DT\_SPEC\_GET(DT\_DRV\_INST(inst))}.

**Parameters**
- \texttt{inst} – Devicetree instance number

I2C_MSG_WRITE
Write message to I2C bus.

I2C_MSG_READ
Read message from I2C bus.

I2C_MSG_STOP
Send STOP after this message.

I2C_MSG_RESTART
RESTART I2C transaction for this message.

**Note:** Not all I2C drivers have or require explicit support for this feature. Some drivers require this be present on a read message that follows a write, or vice-versa. Some drivers will merge adjacent fragments into a single transaction using this flag; some will not.

I2C_MSG_ADDR_10_BITS
Use 10-bit addressing for this message.

**Note:** Not all SoC I2C implementations support this feature.

I2C_TARGET_FLAGS_ADDR_10_BITS
Target device responds to 10-bit addressing.

I2C_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, level, prio, api, ...)
Like \texttt{DEVICE\_DT\_DEFINE()} with I2C specifics.
Defines a device which implements the I2C API. May generate a custom \texttt{device\_state} container struct and \texttt{init\_fn} wrapper when needed depending on \texttt{I2C\_CONFIG\_I2C\_STATS}.

**Parameters**
- \texttt{node\_id} – The devicetree node identifier.
- \texttt{init\_fn} – Name of the init function of the driver. Can be \texttt{NULL}.
• pm – PM device resources reference (NULL if device does not use PM).
• data – Pointer to the device's private data.
• config – The address to the structure containing the configuration information for this instance of the driver.
• level – The initialization level. See SYS_INIT() for details.
• prio – Priority within the selected initialization level. See SYS_INIT() for details.
• api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.

I2C_DEVICE_DT_INST_DEFINE(inst, ...)
Like I2C_DEVICE_DT_DEFINE() for an instance of a DT_DRV_COMPAT compatible.

Parameters
• inst – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to I2C_DEVICE_DT_DEFINE().
• ... – other parameters as expected by I2C_DEVICE_DT_DEFINE().

I2C_DT_IODEV_DEFINE(name, node_id)
Define an iodev for a given dt node on the bus.
These do not need to be shared globally but doing so will save a small amount of memory.

Parameters
• name – Symbolic name of the iodev to define
• node_id – Devicetree node identifier

Typedefs
typedef void (*i2c_callback_t)(const struct device *dev, int result, void *data)
I2C callback for asynchronous transfer requests.

Param dev
I2C device which is notifying of transfer completion or error

Param result
Result code of the transfer request. 0 is success, -errno for failure.

Param data
Transfer requester supplied data which is passed along to the callback.

typedef int (*i2c_target_write_requested_cb_t)(struct i2c_target_config *config)
Function called when a write to the device is initiated.
This function is invoked by the controller when the bus completes a start condition for a write operation to the address associated with a particular device.
A success return shall cause the controller to ACK the next byte received. An error return shall cause the controller to NACK the next byte received.

Param config
the configuration structure associated with the device to which the operation is addressed.

Return
0 if the write is accepted, or a negative error code.
typedef int (*i2c_target_write_received_cb_t)(struct i2c_target_config *config, uint8_t val)

Function called when a write to the device is continued.
This function is invoked by the controller when it completes reception of a byte of data in an ongoing write operation to the device.

A success return shall cause the controller to ACK the next byte received. An error return shall cause the controller to NACK the next byte received.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Param val**
the byte received by the controller.

**Return**
0 if more data can be accepted, or a negative error code.

typedef int (*i2c_target_read_requested_cb_t)(struct i2c_target_config *config, uint8_t *val)

Function called when a read from the device is initiated.
This function is invoked by the controller when the bus completes a start condition for a read operation from the address associated with a particular device.

The value returned in `*val` will be transmitted. A success return shall cause the controller to react to additional read operations. An error return shall cause the controller to ignore bus operations until a new start condition is received.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Param val**
pointer to storage for the first byte of data to return for the read request.

**Return**
0 if more data can be requested, or a negative error code.

typedef int (*i2c_target_read_processed_cb_t)(struct i2c_target_config *config, uint8_t *val)

Function called when a read from the device is continued.
This function is invoked by the controller when the bus is ready to provide additional data for a read operation from the address associated with the device device.

The value returned in `*val` will be transmitted. A success return shall cause the controller to react to additional read operations. An error return shall cause the controller to ignore bus operations until a new start condition is received.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Param val**
pointer to storage for the next byte of data to return for the read request.

**Return**
0 if data has been provided, or a negative error code.
typedef int (*i2c_target_stop_cb_t)(struct i2c_target_config *config)

Function called when a stop condition is observed after a start condition addressed to a particular device.

This function is invoked by the controller when the bus is ready to provide additional data for a read operation from the address associated with the device device. After the function returns the controller shall enter a state where it is ready to react to new start conditions.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Return**
Ignored.

**Functions**

static inline bool i2c_is_ready_dt(const struct i2c_dt_spec *spec)
Validate that I2C bus is ready.

**Parameters**
- **spec** – I2C specification from devicetree

**Return values**
- **true** – if the I2C bus is ready for use.
- **false** – if the I2C bus is not ready for use.

static inline bool i2c_is_read_op(struct i2c_msg *msg)
Check if the current message is a read operation.

**Parameters**
- **msg** – The message to check

**Returns**
true if the I2C message is a read operation

**Returns**
false if the I2C message is a write operation

void i2c_dump_msgs_rw(const struct device *dev, const struct i2c_msg *msgs, uint8_t num_msgs, uint16_t addr, bool dump_read)
Dump out an I2C message.

Dumps out a list of I2C messages. For any that are writes (W), the data is displayed in hex. Setting dump_read will dump the data for read messages too, which only makes sense when called after the messages have been processed.

It looks something like this (with name “testing”):

| D: | I2C msg: testing, addr=56 |
| D: | W len=01: 06 |
| D: | W len=0e: |
| D: | contents: |
| D: | 00 01 02 03 04 05 06 07 | ........ |
| D: | 08 09 0a 0b 0c 0d | ...... |
| D: | W len=01: 0f |
| D: | R len=01: 6c |

**Parameters**
• dev – Target for the messages being sent. Its name will be printed in the log.
• msgs – Array of messages to dump.
• num_msgs – Number of messages to dump.
• addr – Address of the I2C target device.
• dump_read – Dump data from I2C reads, otherwise only writes have data dumped.

static inline void i2c_dump_msgs(const struct device *dev, const struct i2c_msg *msgs, uint8_t num_msgs, uint16_t addr)

Dump out an I2C message, before it is executed.
This is equivalent to:

i2c_dump_msgs_rw(dev, msgs, num_msgs, addr, false);

The read messages' data isn't dumped.

Parameters
• dev – Target for the messages being sent. Its name will be printed in the log.
• msgs – Array of messages to dump.
• num_msgs – Number of messages to dump.
• addr – Address of the I2C target device.

static inline void i2c_xfer_stats(const struct device *dev, struct i2c_msg *msgs, uint8_t num_msgs)

Updates the i2c stats for i2c transfers.

Parameters
• dev – I2C device to update stats for
• msgs – Array of struct i2c_msg
• num_msgs – Number of i2c_msgs

int i2c_configure(const struct device *dev, uint32_t dev_config)

Configure operation of a host controller.

Parameters
• dev – Pointer to the device structure for the driver instance.
• dev_config – Bit-packed 32-bit value to the device runtime configuration for the I2C controller.

Return values
• 0 – If successful.
• -EIO – General input / output error, failed to configure device.

int i2c_get_config(const struct device *dev, uint32_t *dev_config)

Get configuration of a host controller.

This routine provides a way to get current configuration. It is allowed to call the function before i2c_configure, because some I2C ports can be configured during init process. However, if the I2C port is not configured, i2c_get_config returns an error.
i2c_get_config can return cached config or probe hardware, but it has to be up to date with current configuration.
Parameters

- dev – Pointer to the device structure for the driver instance.
- dev_config – Pointer to return bit-packed 32-bit value of the I2C controller configuration.

Return values

- 0 – If successful.
- -EIO – General input / output error.
- -ERANGE – Configured I2C frequency is invalid.
- -ENOSYS – If get config is not implemented

```c
int i2c_transfer(const struct device *dev, struct i2c_msg *msgs, uint8_t num_msgs, uint16_t addr);
```

Perform data transfer to another I2C device in controller mode.

This routine provides a generic interface to perform data transfer to another I2C device synchronously. Use `i2c_read()`/`i2c_write()` for simple read or write.

The array of message `msgs` must not be NULL. The number of message `num_msgs` may be zero, in which case no transfer occurs.

**Note:** Not all scatter/gather transactions can be supported by all drivers. As an example, a gather write (multiple consecutive `i2c_msg` buffers all configured for `I2C_MSG_WRITE`) may be packed into a single transaction by some drivers, but others may emit each fragment as a distinct write transaction, which will not produce the same behavior. See the documentation of `struct i2c_msg` for limitations on support for multi-message bus transactions.

Parameters

- dev – Pointer to the device structure for an I2C controller driver configured in controller mode.
- msgs – Array of messages to transfer.
- num_msgs – Number of messages to transfer.
- addr – Address of the I2C target device.

Return values

- 0 – If successful.
- -EIO – General input / output error.

```c
static inline int i2c_transfer_cb(const struct device *dev, struct i2c_msg *msgs, uint8_t num_msgs, uint16_t addr, i2c_callback_t cb, void *userdata);
```

Perform data transfer to another I2C device in controller mode.

This routine provides a generic interface to perform data transfer to another I2C device asynchronously with a callback completion.

**See also:**

`i2c_transfer()`
Function properties (list may not be complete)

*isr-ok*

**Parameters**

- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
- `msgs` – Array of messages to transfer, must live until callback completes.
- `num_msgs` – Number of messages to transfer.
- `addr` – Address of the I2C target device.
- `cb` – Function pointer for completion callback.
- `userdata` – Userdata passed to callback.

**Return values**

- `0` – If successful.
- `-EIO` – General input / output error.
- `-ENOSYS` – If transfer async is not implemented
- `-EWOULDBLOCK` – If the device is temporarily busy doing another transfer

```c
static inline int i2c_transfer_cb_dt(const struct i2c_dt_spec *spec, struct i2c_msg *msgs, uint8_t num_msgs, i2c_callback_t cb, void *userdata)
```
Perform data transfer to another I2C device in master mode asynchronously.
This is equivalent to:

```
i2c_transfer_cb(spec->bus, msgs, num_msgs, spec->addr, cb, userdata);
```

**Parameters**

- `spec` – I2C specification from devicetree.
- `msgs` – Array of messages to transfer.
- `num_msgs` – Number of messages to transfer.
- `cb` – Function pointer for completion callback.
- `userdata` – Userdata passed to callback.

**Returns**

a value from `i2c_transfer_cb()`

```c
static inline int i2c_write_read_cb(const struct device *dev, struct i2c_msg *msgs, uint8_t num_msgs, uint16_t addr, const void *write_buf, size_t num_write, void *read_buf, size_t num_read, i2c_callback_t cb, void *userdata)
```
Write then read data from an I2C device asynchronously.

This supports the common operation “this is what I want”, “now give it to me” transaction pair through a combined write-then-read bus transaction but using `i2c_transfer_cb`. This helper function expects caller to pass a message pointer with 2 and only 2 size.

**Parameters**
• **dev** – Pointer to the device structure for an I2C controller driver configured in master mode.

• **msgs** – Array of messages to transfer.

• **num_msgs** – Number of messages to transfer.

• **addr** – Address of the I2C device

• **write_buf** – Pointer to the data to be written

• **num_write** – Number of bytes to write

• **read_buf** – Pointer to storage for read data

• **num_read** – Number of bytes to read

• **cb** – Function pointer for completion callback.

• **userdata** – Userdata passed to callback.

**Return values**

• **0** – if successful

• **negative** – on error.

```c
static inline int i2c_write_read_cb_dt(const struct i2c_dt_spec *spec, struct i2c_msg *msgs, uint8_t num_msgs, const void *write_buf, size_t num_write, void *read_buf, size_t num_read, i2c_callback_t cb, void *userdata)
```

Write then read data from an I2C device asynchronously.

This is equivalent to:

```c
i2c_write_read_cb(spec->bus, msgs, num_msgs, spec->addr, write_buf, num_write, read_buf, num_read, i2c_callback_t cb, void *userdata);
```

**Parameters**

• **spec** – I2C specification from devicetree.

• **msgs** – Array of messages to transfer.

• **num_msgs** – Number of messages to transfer.

• **write_buf** – Pointer to the data to be written

• **num_write** – Number of bytes to write

• **read_buf** – Pointer to storage for read data

• **num_read** – Number of bytes to read

• **cb** – Function pointer for completion callback.

• **userdata** – Userdata passed to callback.

**Returns**

a value from **i2c_write_read_cb()**

```c
static inline int i2c_transfer_signal(const struct device *dev, struct i2c_msg *msgs, uint8_t num_msgs, uint16_t addr, struct k_poll_signal *sig)
```

Perform data transfer to another I2C device in controller mode.

This routine provides a generic interface to perform data transfer to another I2C device asynchronously with a **k_poll_signal** completion.
See also:
i2c_transfer_cb()

Function properties (list may not be complete)
isr-ok

Parameters
- **dev** – Pointer to the device structure for an I2C controller driver configured in controller mode.
- **msgs** – Array of messages to transfer, must live until callback completes.
- **num_msgs** – Number of messages to transfer.
- **addr** – Address of the I2C target device.
- **sig** – Signal to notify of transfer completion.

Return values
- **0** – If successful.
- **-EIO** – General input / output error.
- **-ENOSYS** – If transfer async is not implemented
- **-EWOULD BLOCK** – If the device is temporarily busy doing another transfer

static inline void i2c_iodev_submit(struct rtio_iodev_sqe *iodev_sqe)
Submit request(s) to an I2C device with RTIO.

Parameters
- **iodev_sqe** – Prepared submissions queue entry connected to an iodev defined by I2C_DT_IODEV_DEFINE.

struct rtio_sqe *i2c_rtio_copy(struct rtio *r, struct rtio_iodev *iodev, const struct i2c_msg *msgs, uint8_t num_msgs)
Copy the i2c_msgs into a set of RTIO requests.

Parameters
- **r** – RTIO context
- **iodev** – RTIO IODev to target for the submissions
- **msgs** – Array of messages
- **num_msgs** – Number of i2c msgs in array

Return values
- **sqe** – Last submission in the queue added
- **NULL** – Not enough memory in the context to copy the requests

static inline int i2c_transfer_dt(const struct i2c_dt_spec *spec, struct i2c_msg *msgs, uint8_t num_msgs)
Perform data transfer to another I2C device in controller mode.
This is equivalent to:

```c
i2c_transfer(spec->bus, msgs, num_msgs, spec->addr);
```

Parameters
• `spec` – I2C specification from devicetree.
• `msgs` – Array of messages to transfer.
• `num_msgs` – Number of messages to transfer.

**Returns**
a value from `i2c_transfer()`

```c
int i2c_recover_bus(const struct device *dev)
```
Recover the I2C bus.

**Parameters**
• `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.

**Return values**
• 0 – If successful
• -EBUSY – If bus is not clear after recovery attempt.
• -EIO – General input / output error.
• -ENOSYS – If bus recovery is not implemented

```c
static inline int i2c_target_register(const struct device *dev, struct i2c_target_config *cfg)
```
Registers the provided config as Target device of a controller.

Enable I2C target mode for the ‘dev’ I2C bus driver using the provided ‘config’ struct containing the functions and parameters to send bus events. The I2C target will be registered at the address provided as ‘address’ struct member. Addressing mode - 7 or 10 bit - depends on the ‘flags’ struct member. Any I2C bus events related to the target mode will be passed onto I2C target device driver via a set of callback functions provided in the ‘callbacks’ struct member.

Most of the existing hardware allows simultaneous support for controller and target mode. This is however not guaranteed.

**Parameters**
• `dev` – Pointer to the device structure for an I2C controller driver configured in target mode.
• `cfg` – Config struct with functions and parameters used by the I2C driver to send bus events

**Return values**
• 0 – Is successful
• -EINVAL – If parameters are invalid
• -EIO – General input / output error.
• -ENOSYS – If target mode is not implemented

```c
static inline int i2c_target_unregister(const struct device *dev, struct i2c_target_config *cfg)
```
Unregisters the provided config as Target device.

This routine disables I2C target mode for the ‘dev’ I2C bus driver using the provided ‘config’ struct containing the functions and parameters to send bus events.

**Parameters**
dev – Pointer to the device structure for an I2C controller driver configured in target mode.

cfg – Config struct with functions and parameters used by the I2C driver to send bus events

Return values

• 0 – Is successful
• -EINVAL – If parameters are invalid
• -ENOSYS – If target mode is not implemented

int i2c_target_driver_register(const struct device *dev)

Instructs the I2C Target device to register itself to the I2C Controller.

This routine instructs the I2C Target device to register itself to the I2C Controller via its parent controller's i2c_target_register() API.

Parameters

• dev – Pointer to the device structure for the I2C target device (not itself an I2C controller).

Return values

• 0 – Is successful
• -EINVAL – If parameters are invalid
• -EIO – General input / output error.

int i2c_target_driver_unregister(const struct device *dev)

Instructs the I2C Target device to unregister itself from the I2C Controller.

This routine instructs the I2C Target device to unregister itself from the I2C Controller via its parent controller's i2c_target_register() API.

Parameters

• dev – Pointer to the device structure for the I2C target device (not itself an I2C controller).

Return values

• 0 – Is successful
• -EINVAL – If parameters are invalid

static inline int i2c_write(const struct device *dev, const uint8_t *buf, uint32_t num_bytes, uint16_t addr)

Write a set amount of data to an I2C device.

This routine writes a set amount of data synchronously.

Parameters

• dev – Pointer to the device structure for an I2C controller driver configured in controller mode.
• buf – Memory pool from which the data is transferred.
• num_bytes – Number of bytes to write.
• addr – Address to the target I2C device for writing.

Return values

• 0 – If successful.
• -EIO – General input / output error.
static inline int i2c_write_dt(const struct i2c_dt_spec *spec, const uint8_t *buf, uint32_t num_bytes)

Write a set amount of data to an I2C device.
This is equivalent to:

    i2c_write(spec->bus, buf, num_bytes, spec->addr);

**Parameters**
- *spec* – I2C specification from devicetree.
- *buf* – Memory pool from which the data is transferred.
- *num_bytes* – Number of bytes to write.

**Returns**
a value from `i2c_write()`

static inline int i2c_read(const struct device *dev, uint8_t *buf, uint32_t num_bytes, uint16_t addr)

Read a set amount of data from an I2C device.
This routine reads a set amount of data synchronously.

**Parameters**
- *dev* – Pointer to the device structure for an I2C controller driver configured in controller mode.
- *buf* – Memory pool that stores the retrieved data.
- *num_bytes* – Number of bytes to read.
- *addr* – Address of the I2C device being read.

**Return values**
- **0** – If successful.
- **-EIO** – General input / output error.

static inline int i2c_read_dt(const struct i2c_dt_spec *spec, uint8_t *buf, uint32_t num_bytes)

Read a set amount of data from an I2C device.
This is equivalent to:

    i2c_read(spec->bus, buf, num_bytes, spec->addr);

**Parameters**
- *spec* – I2C specification from devicetree.
- *buf* – Memory pool that stores the retrieved data.
- *num_bytes* – Number of bytes to read.

**Returns**
a value from `i2c_read()`

static inline int i2c_write_read(const struct device *dev, uint16_t addr, const void *write_buf, size_t num_write, void *read_buf, size_t num_read)
Write then read data from an I2C device.

This supports the common operation “this is what I want”, “now give it to me” transaction pair through a combined write-then-read bus transaction.

**Parameters**

- **dev** – Pointer to the device structure for an I2C controller driver configured in controller mode.
- **addr** – Address of the I2C device
- **write_buf** – Pointer to the data to be written
- **num_write** – Number of bytes to write
- **read_buf** – Pointer to storage for read data
- **num_read** – Number of bytes to read

**Return values**

- **0** – if successful
- **negative** – on error.

```c
static inline int i2c_write_read_dt(const struct i2c_dt_spec *spec, const void *write_buf, size_t num_write, void *read_buf, size_t num_read)
```

Write then read data from an I2C device.

This is equivalent to:

```c
i2c_write_read(spec->bus, spec->addr, write_buf, num_write, read_buf, num_read);
```

**Parameters**

- **spec** – I2C specification from devicetree.
- **write_buf** – Pointer to the data to be written
- **num_write** – Number of bytes to write
- **read_buf** – Pointer to storage for read data
- **num_read** – Number of bytes to read

**Returns**

A value from `i2c_write_read()`

```c
static inline int i2c_burst_read(const struct device *dev, uint16_t dev_addr, uint8_t start_addr, uint8_t *buf, uint32_t num_bytes)
```

Read multiple bytes from an internal address of an I2C device.

This routine reads multiple bytes from an internal address of an I2C device synchronously.

Instances of this may be replaced by `i2c_write_read()`.

**Parameters**

- **dev** – Pointer to the device structure for an I2C controller driver configured in controller mode.
• **dev_addr** – Address of the I2C device for reading.
• **start_addr** – Internal address from which the data is being read.
• **buf** – Memory pool that stores the retrieved data.
• **num_bytes** – Number of bytes being read.

**Return values**
• 0 – If successful.
• -EIO – General input / output error.

```c
static inline int i2c_burst_read_dt(const struct i2c_dt_spec *spec, uint8_t start_addr, uint8_t *buf, uint32_t num_bytes)
```

Read multiple bytes from an internal address of an I2C device.

This is equivalent to:

```c
i2c_burst_read(spec->bus, spec->addr, start_addr, buf, num_bytes);
```

**Parameters**
• **spec** – I2C specification from devicetree.
• **start_addr** – Internal address from which the data is being read.
• **buf** – Memory pool that stores the retrieved data.
• **num_bytes** – Number of bytes to read.

**Returns**

a value from `i2c_burst_read()`

```c
static inline int i2c_burst_write(const struct device *dev, uint16_t dev_addr, uint8_t start_addr, const uint8_t *buf, uint32_t num_bytes)
```

Write multiple bytes to an internal address of an I2C device.

This routine writes multiple bytes to an internal address of an I2C device synchronously.

**Warning:** The combined write synthesized by this API may not be supported on all I2C devices. Uses of this API may be made more portable by replacing them with calls to `i2c_write()` passing a buffer containing the combined address and data.

**Parameters**
• **dev** – Pointer to the device structure for an I2C controller driver configured in controller mode.
• **dev_addr** – Address of the I2C device for writing.
• **start_addr** – Internal address to which the data is being written.
• **buf** – Memory pool from which the data is transferred.
• **num_bytes** – Number of bytes being written.

**Return values**
• 0 – If successful.
• -EIO – General input / output error.
static inline int i2c_burst_write_dt(const struct i2c_dt_spec *spec, uint8_t start_addr, const uint8_t *buf, uint32_t num_bytes)

Write multiple bytes to an internal address of an I2C device. This is equivalent to:

```
    i2c_burst_write(spec->bus, spec->addr, start_addr, buf, num_bytes);
```

**Parameters**

- `spec` – I2C specification from devicetree.
- `start_addr` – Internal address to which the data is being written.
- `buf` – Memory pool from which the data is transferred.
- `num_bytes` – Number of bytes being written.

**Returns**
a value from `i2c_burst_write()`

static inline int i2c_reg_read_byte(const struct device *dev, uint16_t dev_addr, uint8_t reg_addr, uint8_t *value)

Read internal register of an I2C device. This routine reads the value of an 8-bit internal register of an I2C device synchronously.

**Parameters**

- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
- `dev_addr` – Address of the I2C device for reading.
- `reg_addr` – Address of the internal register being read.
- `value` – Memory pool that stores the retrieved register value.

**Return values**

- `0` – If successful.
- `-EIO` – General input / output error.

static inline int i2c_reg_read_byte_dt(const struct i2c_dt_spec *spec, uint8_t reg_addr, uint8_t *value)

Read internal register of an I2C device. This is equivalent to:

```
    i2c_reg_read_byte(spec->bus, spec->addr, reg_addr, value);
```

**Parameters**

- `spec` – I2C specification from devicetree.
- `reg_addr` – Address of the internal register being read.
- `value` – Memory pool that stores the retrieved register value.

**Returns**
a value from `i2c_reg_read_byte()`
static inline int i2c_reg_write_byte(const struct device *dev, uint16_t dev_addr, uint8_t reg_addr, uint8_t value)

Write internal register of an I2C device.

This routine writes a value to an 8-bit internal register of an I2C device synchronously.

Note: This function internally combines the register and value into a single bus transaction.

Parameters
- dev – Pointer to the device structure for an I2C controller driver configured in controller mode.
- dev_addr – Address of the I2C device for writing.
- reg_addr – Address of the internal register being written.
- value – Value to be written to internal register.

Return values
- 0 – If successful.
- -EIO – General input / output error.

static inline int i2c_reg_write_byte_dt(const struct i2c_dt_spec *spec, uint8_t reg_addr, uint8_t value)

Write internal register of an I2C device.

This is equivalent to:

i2c_reg_write_byte(spec->bus, spec->addr, reg_addr, value);

Parameters
- spec – I2C specification from devicetree.
- reg_addr – Address of the internal register being written.
- value – Value to be written to internal register.

Returns
a value from i2c_reg_write_byte()

static inline int i2c_reg_update_byte(const struct device *dev, uint16_t dev_addr, uint8_t reg_addr, uint8_t mask, uint8_t value)

Update internal register of an I2C device.

This routine updates the value of a set of bits from an 8-bit internal register of an I2C device synchronously.

Note: If the calculated new register value matches the value that was read this function will not generate a write operation.

Parameters
- dev – Pointer to the device structure for an I2C controller driver configured in controller mode.
- dev_addr – Address of the I2C device for updating.
• **reg_addr** – Address of the internal register being updated.
• **mask** – Bitmask for updating internal register.
• **value** – Value for updating internal register.

**Return values**
• **0** – If successful.
• **-EIO** – General input / output error.

```c
static inline int i2c_reg_update_byte_dt(const struct i2c_dt_spec *spec, uint8_t reg_addr, uint8_t mask, uint8_t value)
```

Update internal register of an I2C device.
This is equivalent to:

```
i2c_reg_update_byte(spec->bus, spec->addr, reg_addr, mask, value);
```

**Parameters**
• **spec** – I2C specification from devicetree.
• **reg_addr** – Address of the internal register being updated.
• **mask** – Bitmask for updating internal register.
• **value** – Value for updating internal register.

**Returns**
a value from `i2c_reg_update_byte()

**Variables**

```c
const struct rtio_iodev_api i2c_iodev_api
```

```c
struct i2c_dt_spec
#include <i2c.h> Complete I2C DT information.
```

**Param bus**
is the I2C bus

**Param addr**
is the target address

```c
struct i2c_msg
#include <i2c.h> One I2C Message.
```

This defines one I2C message to transact on the I2C bus.

**Note:** Some of the configurations supported by this API may not be supported by specific SoC I2C hardware implementations, in particular features related to bus transactions intended to read or write data from different buffers within a single transaction. Invocations of `i2c_transfer()` may not indicate an error when an unsupported configuration is encountered. In some cases drivers will generate separate transactions for each message fragment, with or without presence of `I2C_MSG_RESTART` in `flags`.  

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Public Members

`uint8_t *buf`
Data buffer in bytes.

`uint32_t len`
Length of buffer in bytes.

`uint8_t flags`
Flags for this message.

```
struct i2c_target_callbacks
#include <i2c.h>
Structure providing callbacks to be implemented for devices that supports the I2C target API.
This structure may be shared by multiple devices that implement the same API at different addresses on the bus.
```

```
struct i2c_target_config
#include <i2c.h>
Structure describing a device that supports the I2C target API.
Instances of this are passed to the `i2c_target_register()` and `i2c_target_unregister()` functions to indicate addition and removal of a target device, respective.
Fields other than `node` must be initialized by the module that implements the device behavior prior to passing the object reference to `i2c_target_register()`.
```

Public Members

```
sys_snode_t node
Private, do not modify.
```

```
uint8_t flags
Flags for the target device defined by I2C_TARGET_FLAGS_* constants.
```

```
uint16_t address
Address for this target device.
```

```
const struct i2c_target_callbacks *callbacks
Callback functions.
```

```
struct i2c_device_state
#include <i2c.h>
I2C specific device state which allows for i2c device class specific additions.
```

7.6.27 Inter-Processor Mailbox (IPM)

Overview
API Reference

Related code samples

**IPM on ESP32**
Implement inter-processor mailbox (IPM) between ESP32 APP and PRO CPUs.

**IPM on NXP LPC**
Implement inter-processor mailbox (IPM) on NXP LPC family.

**IPM on NXP i.MX**
Implement inter-processor mailbox (IPM) on i.MX SoCs containing a Messaging Unit peripheral.

**IPM over IVSHMEM**
Implement inter-processor mailbox (IPM) over IVSHMEM (Inter-VM shared memory)

**IPM with ARM MHU**
Implement inter-processor mailbox (IPM) using an MHU (Message Handling Unit)

**OpenAMP**
Send messages between two cores using OpenAMP.

**OpenAMP using resource table**
Send messages between two cores using OpenAMP and a resource table.

```c
typedef void (*ipm_callback_t)(const struct device *ipmdev, void *user_data, uint32_t id, volatile void *data)
```
Callback API for incoming IPM messages. These callbacks execute in interrupt context. Therefore, use only interrupt-safe APIs. Registration of callbacks is done via `ipm_register_callback`

**Param ipmdev**
Driver instance

**Param user_data**
Pointer to some private data provided at registration time.

**Param id**
Message type identifier.

**Param data**
Message data pointer. The correct amount of data to read out must be inferred using the message id/upper level protocol.

```c
typedef int (*ipm_send_t)(const struct device *ipmdev, int wait, uint32_t id, const void *data, int size)
```
Callback API to send IPM messages.
See `ipm_send()` for argument definitions.
typedef int (*ipm_max_data_size_get_t)(const struct device *ipmdev)
    Callback API to get maximum data size.
    See ipm_max_data_size_get() for argument definitions.

typedef uint32_t (*ipm_max_id_val_get_t)(const struct device *ipmdev)
    Callback API to get the ID’s maximum value.
    See ipm_max_id_val_get() for argument definitions.

typedef void (*ipm_register_callback_t)(const struct device *port,
                        ipm_callback_t cb, void *user_data)
    Callback API upon registration.
    See ipm_register_callback() for argument definitions.

typedef int (*ipm_set_enabled_t)(const struct device *ipmdev, int enable)
    Callback API upon enablement of interrupts.
    See ipm_set_enabled() for argument definitions.

typedef void (*ipm_complete_t)(const struct device *ipmdev)
    Callback API upon command completion.
    See ipm_complete() for argument definitions.

Functions

int ipm_send(const struct device *ipmdev, int wait, uint32_t id, const void *data, int size)
    Try to send a message over the IPM device.
    A message is considered consumed once the remote interrupt handler finishes. If there is deferred processing on the remote side, or if outgoing messages must be queued and wait on an event/semaphore, a high-level driver can implement that.
    There are constraints on how much data can be sent or the maximum value of id. Use the ipm_max_data_size_get and ipm_max_id_val_get routines to determine them.
    The size parameter is used only on the sending side to determine the amount of data to put in the message registers. It is not passed along to the receiving side. The upper-level protocol dictates the amount of data read back.

Parameters

- ipmdev – Driver instance
- wait – If nonzero, busy-wait for remote to consume the message. The message is considered consumed once the remote interrupt handler finishes. If there is deferred processing on the remote side, or you would like to queue outgoing messages and wait on an event/semaphore, you can implement that in a high-level driver
- id – Message identifier. Values are constrained by ipm_max_data_size_get since many boards only allow for a subset of bits in a 32-bit register to store the ID.
- data – Pointer to the data sent in the message.
- size – Size of the data.

Return values
• -EBUSY – If the remote hasn’t yet read the last data sent.
• -EMSGSIZE – If the supplied data size is unsupported by the driver.
• -EINVAL – If there was a bad parameter, such as: too-large id value. or the device isn’t an outbound IPM channel.
• 0 – On success.

static inline void ipm_register_callback(const struct device *ipmdev, ipm_callback_t cb, void *user_data)

Register a callback function for incoming messages.

Parameters
• ipmdev – Driver instance pointer.
• cb – Callback function to execute on incoming message interrupts.
• user_data – Application-specific data pointer which will be passed to the callback function when executed.

int ipm_max_data_size_get(const struct device *ipmdev)

Return the maximum number of bytes possible in an outbound message.
IPM implementations vary on the amount of data that can be sent in a single message since the data payload is typically stored in registers.

Parameters
• ipmdev – Driver instance pointer.

Returns
Maximum possible size of a message in bytes.

uint32_t ipm_max_id_val_get(const struct device *ipmdev)

Return the maximum id value possible in an outbound message.
Many IPM implementations store the message's ID in a register with some bits reserved for other uses.

Parameters
• ipmdev – Driver instance pointer.

Returns
Maximum possible value of a message ID.

int ipm_set_enabled(const struct device *ipmdev, int enable)
Enable interrupts and callbacks for inbound channels.

Parameters
• ipmdev – Driver instance pointer.
• enable – Set to 0 to disable and to nonzero to enable.

Return values
• 0 – On success.
• -EINVAL – If it isn’t an inbound channel.

void ipm_complete(const struct device *ipmdev)

Signal asynchronous command completion.

Some IPM backends have an ability to deliver a command asynchronously. The callback will be invoked in interrupt context, but the message (including the provided data pointer) will stay “active” and unacknowledged until later code (presumably in thread mode) calls ipm_complete().
This function is, obviously, a noop on drivers without async support.

**Parameters**

- `ipmdev` – Driver instance pointer.

```c
struct ipm_driver_api
#include <ipm.h>
```

## 7.6.28 Keyboard Scan

### Overview

The `kscan` driver (keyboard scan matrix) is used for detecting a key press in a connected matrix keyboard or any device with buttons such as joysticks. Typically, matrix keyboards are implemented using a two-dimensional configuration in order to sense several keys. This allows interfacing to many keys through fewer physical pins. Keyboard matrix drivers read the rows while applying power through the columns one at a time with the purpose of detecting key events. There is no correlation between the physical and electrical layout of keys. For example, the physical layout may be one array of 16 or fewer keys, which may be electrically connected to a 4 x 4 array. In addition, key values are defined by a keymap provided by the keyboard manufacturer.

### Configuration Options

Related configuration options:

- `CONFIG_KSCAN`

### API Reference

**Related code samples**

**HT16K33 LED driver with keyscan**

Control up to 128 LEDs connected to an HT16K33 LED driver and log keyscan events.

**KSCAN**

Use the KSCAN API to read key presses and releases on a keyboard matrix.

### Typedefs

```c
typedef void (*kscan_callback_t)(const struct device *dev, uint32_t row, uint32_t column, bool pressed)
```

Keyboard scan callback called when user press/release a key on a matrix keyboard.

**Param dev**

Pointer to the device structure for the driver instance.

**Param row**

Describes row change.
**Param column**
Describes column change.

**Param pressed**
Describes the kind of key event.

**Functions**

```c
int kscan_config(const struct device *dev, kscan_callback_t callback)
Configure a Keyboard scan instance.
```

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.
- `callback` – called when keyboard devices reply to to a keyboard event such as key pressed/released.

**Return values**
- `0` – If successful.
- `Negative` – errno code if failure.

```c
int kscan_enable_callback(const struct device *dev)
Enables callback.
```

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.

**Return values**
- `0` – If successful.
- `Negative` – errno code if failure.

```c
int kscan_disable_callback(const struct device *dev)
Disables callback.
```

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.

**Return values**
- `0` – If successful.
- `Negative` – errno code if failure.

### 7.6.29 Light-Emitting Diode (LED)

**Overview**

The LED API provides access to Light Emitting Diodes, both in individual and strip form.

**Configuration Options**

Related configuration options:
- `CONFIG_LED`
- `CONFIG_LED_STRIP`
API Reference

**LED**

Related code samples

**Breathing-blinking LED (BBLED)**
Control a BBLED (Breathing-Blinking LED) using Microchip XEC driver.

**HT16K33 LED driver with keyscan**
Control up to 128 LEDs connected to an HT16K33 LED driver and log keyscan events.

**IS31FL3216A LED**
Control up to 16 PWM LEDs connected to an IS31FL3216A driver chip.

**IS31FL3733 LED Matrix**
Control a matrix of up to 192 LEDs connected to an IS31FL3733 driver chip.

**LED PWM**
Control PWM LEDs using the LED API.

**LP3943 RGBW LED**
Control up to 16 RGBW LEDs connected to an LP3943 driver chip.

**LP50XX RGB LED**
Control up to 12 RGB LEDs connected to an LP50xx driver chip.

**LP5562 RGB LED**
Control 4 RGB LEDs connected to an LP5562 driver chip.

**LP5569 9-channel LED controller**
Control 9 LEDs connected to an LP5569 driver chip.

**PCA9633 LED**
Control 4 LEDs connected to a PCA9633 driver chip.

**SX1509B RGB LED**
Control an RGB LED connected to an SX1509B driver chip.

---

group led_interface
LED Interface.

**Typedefs**

typedef int (*led_api_blink)(const struct device *dev, uint32_t led, uint32_t delay_on, uint32_t delay_off)

Callback API for blinking an LED.

**See also:**

*led_blink()* for argument descriptions.

typedef int (*led_api_get_info)(const struct device *dev, uint32_t led, const struct led_info **info)

Optional API callback to get LED information.

**See also:**

*led_get_info()* for argument descriptions.
typedef int (*led_api_set_brightness)(const struct device *dev, uint32_t led, uint8_t value)

Callback API for setting brightness of an LED.

**See also:**

*led_set_brightness()* for argument descriptions.

typedef int (*led_api_set_color)(const struct device *dev, uint32_t led, uint8_t num_colors, const uint8_t *color)

Optional API callback to set the colors of a LED.

**See also:**

*led_set_color()* for argument descriptions.

typedef int (*led_api_on)(const struct device *dev, uint32_t led)

Callback API for turning on an LED.

**See also:**

*led_on()* for argument descriptions.

typedef int (*led_api_off)(const struct device *dev, uint32_t led)

Callback API for turning off an LED.

**See also:**

*led_off()* for argument descriptions.

typedef int (*led_api_write_channels)(const struct device *dev, uint32_t start_channel, uint32_t num_channels, const uint8_t *buf)

Callback API for writing a strip of LED channels.

**See also:**

*led_api_write_channels()* for arguments descriptions.

**Functions**

```c
int led_blink(const struct device *dev, uint32_t led, uint32_t delay_on, uint32_t delay_off)
```

Blink an LED.

This optional routine starts blinking a LED forever with the given time period.

**Parameters**

- **dev** – LED device
- **led** – LED number
- **delay_on** – Time period (in milliseconds) an LED should be ON
- **delay_off** – Time period (in milliseconds) an LED should be OFF
Returns
0 on success, negative on error

int led_get_info(const struct device *dev, uint32_t led, const struct led_info **info)
Get LED information.
This optional routine provides information about a LED.

Parameters
• dev – LED device
• led – LED number
• info – Pointer to a pointer filled with LED information

Returns
0 on success, negative on error

int led_set_brightness(const struct device *dev, uint32_t led, uint8_t value)
Set LED brightness.
This optional routine sets the brightness of a LED to the given value. Calling this function after led_blink() won’t affect blinking.
LEDs which can only be turned on or off may provide this function. These should simply turn the LED on if value is nonzero, and off if value is zero.

Parameters
• dev – LED device
• led – LED number
• value – Brightness value to set in percent

Returns
0 on success, negative on error

int led_write_channels(const struct device *dev, uint32_t start_channel, uint32_t num_channels, const uint8_t *buf)
Write/update a strip of LED channels.
This optional routine writes a strip of LED channels to the given array of levels. Therefore it can be used to configure several LEDs at the same time.
Calling this function after led_blink() won’t affect blinking.

Parameters
• dev – LED device
• start_channel – Absolute number (i.e. not relative to a LED) of the first channel to update.
• num_channels – The number of channels to write/update.
• buf – array of values to configure the channels with. num_channels entries must be provided.

Returns
0 on success, negative on error

int led_set_channel(const struct device *dev, uint32_t channel, uint8_t value)
Set a single LED channel.
This optional routine sets a single LED channel to the given value.
Calling this function after led_blink() won’t affect blinking.

Parameters
- dev – LED device
- channel – Absolute channel number (i.e. not relative to a LED)
- value – Value to configure the channel with

**Returns**
0 on success, negative on error

```c
int led_set_color(const struct device *dev, uint32_t led, uint8_t num_colors, const uint8_t *color)
```

Set LED color.
This routine configures all the color channels of a LED with the given color array.
Calling this function after `led_blink()` won’t affect blinking.

**Parameters**
- dev – LED device
- led – LED number
- num_colors – Number of colors in the array.
- color – Array of colors. It must be ordered following the color mapping of the LED controller. See the the color_mapping member in struct `led_info`.

**Returns**
0 on success, negative on error

```c
int led_on(const struct device *dev, uint32_t led)
```

Turn on an LED.
This routine turns on an LED

**Parameters**
- dev – LED device
- led – LED number

**Returns**
0 on success, negative on error

```c
int led_off(const struct device *dev, uint32_t led)
```

Turn off an LED.
This routine turns off an LED

**Parameters**
- dev – LED device
- led – LED number

**Returns**
0 on success, negative on error

```c
struct led_info
```

#include `<led.h>` LED information structure.
This structure gathers useful information about LED controller.

**Public Members**
const char *label
        LED label.

uint32_t index
        Number of colors per LED.

uint8_t num_colors
        Index of the LED on the controller.

color_mapping
        Mapping of the LED colors.

struct led_driver_api
        #include <led.h> LED driver API.

LED Strip
Related code samples

APA102 LED strip
        Control an LED strip using an APA102, Adafruit DotStar, or compatible driver chip.

LPD880x LED strip
        Control an LED strip using an LPD880x-compatible driver chip.

WS2812 LED strip
        Control an LED strip using a WS2812 (or compatible) driver chip.

group led_strip_interface
        LED Strip Interface.

Typedefs

typedef int (*led_api_update_rgb)(const struct device *dev, struct led_rgb *pixels, size_t num_pixels)
        Callback API for updating an RGB LED strip.

        See also:
        led_strip_update_rgb() for argument descriptions.

typedef int (*led_api_update_channels)(const struct device *dev, uint8_t *channels, size_t num_channels)
        Callback API for updating channels without an RGB interpretation.

        See also:
        led_strip_update_channels() for argument descriptions.
Functions

static inline int led_strip_update_rgb(const struct device *dev, struct led_rgb *pixels, size_t num_pixels)

Update an LED strip made of RGB pixels.
Important: This routine may overwrite pixels.
This routine immediately updates the strip display according to the given pixels array.

Warning: May overwrite pixels

Parameters

• dev – LED strip device
• pixels – Array of pixel data
• num_pixels – Length of pixels array

Returns
0 on success, negative on error

static inline int led_strip_update_channels(const struct device *dev, uint8_t *channels, size_t num_channels)

Update an LED strip on a per-channel basis.
Important: This routine may overwrite channels.
This routine immediately updates the strip display according to the given channels array. Each channel byte corresponds to an individually addressable color channel or LED. Channels are updated linearly in strip order.

Warning: May overwrite channels

Parameters

• dev – LED strip device
• channels – Array of per-channel data
• num_channels – Length of channels array

Returns
0 on success, negative on error

struct led_rgb

#include <led_strip.h> Color value for a single RGB LED.

Individual strip drivers may ignore lower-order bits if their resolution in any channel is less than a full byte.

Public Members

uint8_t r

Red channel.

7.6. Peripherals
uint8_t g
    Green channel.

uint8_t b
    Blue channel.

struct led_strip_driver_api
#include <led_strip.h> LED strip driver API.
    This is the mandatory API any LED strip driver needs to expose.

7.6.30 Management Data Input/Output (MDIO)

Overview

MDIO is a bus that is commonly used to communicate with ethernet PHY devices. Many ethernet MAC controllers also provide hardware to communicate over MDIO bus with a peripheral device. This API is intended to be used primarily by PHY drivers but can also be used by user firmware.

API Reference

group mdio_interface
    MDIO Interface.

Functions

void mdio_bus_enable(const struct device *dev)
    Enable MDIO bus.

    Parameters
        • dev – [in] Pointer to the device structure for the controller

void mdio_bus_disable(const struct device *dev)
    Disable MDIO bus and tri-state drivers.

    Parameters
        • dev – [in] Pointer to the device structure for the controller

int mdio_read(const struct device *dev, uint8_t prtad, uint8_t regad, uint16_t *data)
    Read from MDIO Bus.

    This routine provides a generic interface to perform a read on the MDIO bus.

    Parameters
        • dev – [in] Pointer to the device structure for the controller
        • prtad – [in] Port address
        • regad – [in] Register address
        • data – Pointer to receive read data

    Return values
        • 0 – If successful.
• -EIO – General input / output error.
• -ETIMEDOUT – If transaction timed out on the bus
• -ENOSYS – if read is not supported

```
int mdio_write(const struct device *dev, uint8_t prtad, uint8_t regad, uint16_t data)
```

Write to MDIO bus.

This routine provides a generic interface to perform a write on the MDIO bus.

**Parameters**

- `dev` – [in] Pointer to the device structure for the controller
- `prtad` – [in] Port address
- `regad` – [in] Register address
- `data` – [in] Data to write

**Return values**

- 0 – If successful.
- -EIO – General input / output error.
- -ETIMEDOUT – If transaction timed out on the bus
- -ENOSYS – if write is not supported

```
int mdio_read_c45(const struct device *dev, uint8_t prtad, uint8_t devad, uint16_t regad,
                  uint16_t *data)
```

Read from MDIO Bus using Clause 45 access.

This routine provides an interface to perform a read on the MDIO bus using IEEE 802.3 Clause 45 access.

**Parameters**

- `dev` – [in] Pointer to the device structure for the controller
- `prtad` – [in] Port address
- `devad` – [in] Device address
- `regad` – [in] Register address
- `data` – Pointer to receive read data

**Return values**

- 0 – If successful.
- -EIO – General input / output error.
- -ETIMEDOUT – If transaction timed out on the bus
- -ENOSYS – if write using Clause 45 access is not supported

```
int mdio_write_c45(const struct device *dev, uint8_t prtad, uint8_t devad, uint16_t regad,
                    uint16_t data)
```

Write to MDIO bus using Clause 45 access.

This routine provides an interface to perform a write on the MDIO bus using IEEE 802.3 Clause 45 access.

**Parameters**

- `dev` – [in] Pointer to the device structure for the controller
- `prtad` – [in] Port address
- `devad` – [in] Device address
7.6.31 MIPI Display Bus Interface (DBI)

The MIPI DBI driver class implements support for MIPI DBI compliant display controllers. MIPI DBI defines 3 interface types:

- Type A: Motorola 6800 parallel bus
- Type B: Intel 8080 parallel bus
- Type C: SPI Type serial bit bus with 3 options:
  1. 9 write clocks per byte, final bit is command/data selection bit
  2. Same as above, but 16 write clocks per byte
  3. 8 write clocks per byte. Command/data selected via GPIO pin

Currently, the API only supports Type C controllers, options 1 and 3.

API Reference

group mipi_dbi_interface
MIPI-DBI driver APIs.

Defines

MIPI_DBI_MODE_SPI_3WIRE
SPI 3 wire (Type C1).
Uses 9 write clocks to send a byte of data. The bit sent on the 9th clock indicates whether the byte is a command or data byte.

```
SCK : ---'---'---'---'---'---'---'---'---'---'---'---'---'---'---'---'
DOUT |[D/C| D7| D6| D5| D4| D3| D2| D1| D0|D/C| D7| D6| D5| D4|...|
     |   '---'---'---'---'---'---'---'---'---'---'---'---'---'---'---'---'
     | Word 1 | Word n
CS : '-----------------------------------------------'~
```
MIPI_DBI_MODE_SPI_4WIRE
SPI 4 wire (Type C3).

Uses 8 write clocks to send a byte of data. An additional C/D pin will be used to indicate
whether the byte is a command or data byte.

| SCK | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
|     | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
| DOUT | D7 | D6 | D5 | D4 | D3 | D2 | D1 | D0 | D7 | D6 | D5 | D4 | D3 | D2 | D1 | D0 |
|      | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
|      | | Word 1 | | Word n |

CS

CD

MIPI_DBI_SPI_CONFIG_DT(node_id, operation_, delay_)
initialize a MIPI DBI SPI configuration struct from devicetree

This helper allows drivers to initialize a MIPI DBI SPI configuration structure using
devicetree.

Parameters

- **node_id** – Devicetree node identifier for the MIPI DBI device whose struct
  *spi_config* to create an initializer for
- **operation_** – the desired operation field in the struct *spi_config*
- **delay_** – the desired delay field in the struct *spi_config*’s
  *spi_cs_control*, if there is one

Functions

static inline int miapi_dbi_command_write(const struct device *dev, const struct
  miapi_dbi_config *config, uint8_t cmd, const
  uint8_t *data, size_t len)

Write a command to the display controller.

Writes a command, along with an optional data buffer to the display. If data buffer
and buffer length are NULL and 0 respectively, then only a command will be sent.

Parameters

- **dev** – miapi dbi controller
- **config** – MIPI DBI configuration
- **cmd** – command to write to display controller
- **data** – optional data buffer to write after command
- **len** – size of data buffer in bytes. Set to 0 to skip sending data.

Return values

- 0 – command write succeeded
- -EIO – I/O error
• -ETIMEDOUT – transfer timed out
• -EBUSY – controller is busy
• -ENOSYS – not implemented

static inline int miipi_dbi_command_read(const struct device *dev, const struct miipi_dbi_config *config, uint8_t *cmds, size_t num_cmd, uint8_t *response, size_t len)

Read a command response from the display controller.

Parameters
• dev – miipi dbi controller
• config – MIPI DBI configuration
• cmds – array of one byte commands to send to display controller
• num_cmd – number of commands to write to display controller
• response – response buffer, filled with display controller response
• len – size of response buffer in bytes.

Return values
• 0 – command read succeeded
• -EIO – I/O error
• -ETIMEDOUT – transfer timed out
• -EBUSY – controller is busy
• -ENOSYS – not implemented

static inline int miipi_dbi_write_display(const struct device *dev, const struct miipi_dbi_config *config, const uint8_t *framebuf, struct display_bufferDescriptor *desc, enum display_pixel_format pixfmt)

Write a display buffer to the display controller.

Parameters
• dev – miipi dbi controller
• config – MIPI DBI configuration
• framebuffer – framebuffer to write to display
• desc – descriptor of framebuffer to write. Note that the pitch must be equal to width. “buf_size” field determines how many bytes will be written.
• pixfmt – pixel format of framebuffer data

Return values
• 0 – buffer write succeeded.
• -EIO – I/O error
• -ETIMEDOUT – transfer timed out
• -EBUSY – controller is busy
static inline int mipi_dbi_reset(const struct device *dev, uint32_t delay)
Resets the attached display controller.

Parameters

- `dev` – mipi dbi controller
- `delay` – duration to set reset signal for, in milliseconds

Return values

- `0` – reset succeeded
- `-EIO` – I/O error
- `-ENOSYS` – not implemented
- `-ENOTSUP` – not supported

struct `mipi_dbi_config`

```c
#include <mipi_dbi.h>
```
MIPI DBI controller configuration.

Configuration for MIPI DBI controller write

Public Members

```c
uint8_t mode
```
MIPI DBI mode (SPI 3 wire or 4 wire)

```c
struct spi_config config
```
SPI configuration.

```c
struct `mipi_dbi_driver_api`
#include <mipi_dbi.h> MIPI-DBI host driver API.
```

7.6.32 MIPI Display Serial Interface (DSI)

API Reference

`group mipi_dsi_interface`
MIPI-DSI driver APIs.

MIPI-DSI Device mode flags.

```c
MIPI_DSI_MODE_VIDEO
```
Video mode.

```c
MIPI_DSI_MODE_VIDEO_BURST
```
Video burst mode.
MIPI_DSI_MODE_VIDEO_SYNC_PULSE
Video pulse mode.

MIPI_DSI_MODE_VIDEO_AUTO_VERT
Enable auto vertical count mode.

MIPI_DSI_MODE_VIDEO_HSE
Enable hsync-end packets in vsync-pulse and v-porch area.

MIPI_DSI_MODE_VIDEO_HFP
Disable hfront-porch area.

MIPI_DSI_MODE_VIDEO_HBP
Disable hback-porch area.

MIPI_DSI_MODE_VIDEO_HSA
Disable hsync-active area.

MIPI_DSI_MODE_VSYNC_FLUSH
Flush display FIFO on vsync pulse.

MIPI_DSI_MODE_EOT_PACKET
Disable EoT packets in HS mode.

MIPI_DSI_CLOCK_NON_CONTINUOUS
Device supports non-continuous clock behavior (DSI spec 5.6.1)

MIPI_DSI_MODE_LPM
Transmit data in low power.

MIPI-DSI Pixel formats.

MIPI_DSI_PIXFMT_RGB888
RGB888 (24bpp).

MIPI_DSI_PIXFMT_RGB666
RGB666 (24bpp).

MIPI_DSI_PIXFMT_RGB666_PACKED
Packed RGB666 (18bpp).

MIPI_DSI_PIXFMT_RGB565
RGB565 (16bpp).

Defines

MIPI_DSI_MSG_USE_LPM
Functions

static inline int mipi_dsi_attach(const struct device *dev, uint8_t channel, const struct mipi_dsi_device *mdev)

Attach a new device to the MIPI-DSI bus.

Parameters

- dev – MIPI-DSI host device.
- channel – Device channel (VID).
- mdev – MIPI-DSI device description.

Returns

0 on success, negative on error

static inline ssize_t mipi_dsi_transfer(const struct device *dev, uint8_t channel, struct mipi_dsi_msg *msg)

Transfer data to/from a device attached to the MIPI-DSI bus.

Parameters

- dev – MIPI-DSI device.
- channel – Device channel (VID).
- msg – Message.

Returns

Size of the transferred data on success, negative on error.

ssize_t mipi_dsi_generic_read(const struct device *dev, uint8_t channel, const void *params, size_t nparams, void *buf, size_t len)

MIPI-DSI generic read.

Parameters

- dev – MIPI-DSI host device.
- channel – Device channel (VID).
- params – Buffer containing request parameters.
- nparams – Number of parameters.
- buf – Buffer where read data will be stored.
- len – Length of the reception buffer.

Returns

Size of the read data on success, negative on error.

ssize_t mipi_dsi_generic_write(const struct device *dev, uint8_t channel, const void *buf, size_t len)

MIPI-DSI generic write.

Parameters

- dev – MIPI-DSI host device.
- channel – Device channel (VID).
- buf – Transmission buffer.
- len – Length of the transmission buffer.

Returns

Size of the written data on success, negative on error.
ssize_t mihi_dsi_dcs_read(const struct device *dev, uint8_t channel, uint8_t cmd, void *buf, size_t len)

MIPI-DSI DCS read.

**Parameters**
- **dev** – MIPI-DSI host device.
- **channel** – Device channel (VID).
- **cmd** – DCS command.
- **buf** – Buffer where read data will be stored.
- **len** – Length of the reception buffer.

**Returns**
Size of the read data on success, negative on error.

ssize_t mihi_dsi_dcs_write(const struct device *dev, uint8_t channel, uint8_t cmd, const void *buf, size_t len)

MIPI-DSI DCS write.

**Parameters**
- **dev** – MIPI-DSI host device.
- **channel** – Device channel (VID).
- **cmd** – DCS command.
- **buf** – Transmission buffer.
- **len** – Length of the transmission buffer

**Returns**
Size of the written data on success, negative on error.

static inline int mihi_dsi_detach(const struct device *dev, uint8_t channel, const struct mihi_dsi_device *mdev)

Detach a device from the MIPI-DSI bus.

**Parameters**
- **dev** – MIPI-DSI host device.
- **channel** – Device channel (VID).
- **mdev** – MIPI-DSI device description.

**Returns**
0 on success, negative on error

struct mihi_dsi_timings
#include <mihi_dsi.h> MIPI-DSI display timings.

**Public Members**

**uint32_t hactive**
Horizontal active video.

**uint32_t hfp**
Horizontal front porch.
uint32_t hbp
    Horizontal back porch.

uint32_t hsync
    Horizontal sync length.

uint32_t vactive
    Vertical active video.

uint32_t vfp
    Vertical front porch.

uint32_t vbp
    Vertical back porch.

uint32_t vsync
    Vertical sync length.

struct mipi_dsi_device
    #include <mipi_dsi.h> MIPI-DSI device.

Public Members

uint8_t data_lanes
    Number of data lanes.

struct mipi_dsi_timings timings
    Display timings.

uint32_t pixfmt
    Pixel format.

uint32_t mode_flags
    Mode flags.

struct mipi_dsi_msg
    #include <mipi_dsi.h> MIPI-DSI read/write message.

Public Members

uint8_t type
    Payload data type.

uint16_t flags
    Flags controlling message transmission.
```c
uint8_t cmd
    Command (only for DCS)

size_t tx_len
    Transmission buffer length.

const void *tx_buf
    Transmission buffer.

size_t rx_len
    Reception buffer length.

void *rx_buf
    Reception buffer.
```

```c
struct mipi_dsi_driver_api
    #include <mipi_dsi.h> MIPI-DSI host driver API.
```

### 7.6.33 Multi-Channel Inter-Processor Mailbox (MBOX)

#### Overview

An MBOX device is a peripheral capable of passing signals (and data depending on the peripheral) between CPUs and clusters in the system. Each MBOX instance is providing one or more channels, each one targeting one other CPU cluster (multiple channels can target the same cluster).

#### API Reference

**Related code samples**

**MBOX**

Perform inter-processor mailbox communication using the MBOX API.

**MBOX Data**

Perform inter-processor mailbox communication using the MBOX API with data.

**group mbox_interface**

MBOX Interface.
An MBOX device is a peripheral capable of passing signals (and data depending on the peripheral) between CPUs and clusters in the system. Each MBOX instance is providing one or more channels, each one targeting one other CPU cluster (multiple channels can target the same cluster).

For example in the plot the device ‘dev A’ is using the TX channel 9 to signal (or send data to) the CPU #2 and it’s expecting data or signals on the RX channel 8. Thus it can send the message through the channel 9, and it can register a callback on the channel 8 of the MBOX device.

This API supports two modes: signalling mode and data transfer mode.

In signalling mode:
- \texttt{mbox_mtu_get()} must return 0
- \texttt{mbox_send()} must have (msg == NULL)
- the callback must be called with (data == NULL)

In data transfer mode:
- \texttt{mbox_mtu_get()} must return a (value != 0)
- \texttt{mbox_send()} must have (msg != NULL)
- the callback must be called with (data != NULL)
- The msg content must be the same between sender and receiver

\textbf{Defines}

\texttt{MBOX_DT_CHANNEL_GET(node_id, name)}

Structure initializer for \texttt{mbox\_channel} from devicetree.

This helper macro expands to a static initializer for a \texttt{mbox\_channel} by reading the relevant device controller and channel number from the devicetree.

Example devicetree fragment:

```c
mbox1: mbox-controller@... { ... };

n: node {
    mboxes = <&mbox1 8>,
     <&mbox1 9>;
    mbox-names = "tx", "rx";
};
```

Example usage:

```c
const struct mbox\_channel channel = MBOX\_DT\_CHANNEL\_GET(DT\_NODELABEL(n), tx);
```

\textbf{Parameters}

- \texttt{node\_id} – Devicetree node identifier for the MBOX device
- \texttt{name} – lowercase-and-underscores name of the mboxes element
**Typedefs**

typedef void (*mbox_callback_t)(const struct device *dev, uint32_t channel, void *user_data, struct mbox_msg *data)

Callback API for incoming MBOX messages.

These callbacks execute in interrupt context. Therefore, use only interrupt-safe APIS. Registration of callbacks is done via **mbox_register_callback()**

The data parameter must be NULL in signalling mode.

**Param dev**
Driver instance

**Param channel**
Channel ID

**Param user_data**
Pointer to some private data provided at registration time

**Param data**
Message struct

typedef int (*mbox_send_t)(const struct device *dev, uint32_t channel, const struct mbox_msg *msg)

Callback API to send MBOX messages.

See **mbox_send()** for function description

**Param dev**
Driver instance

**Param channel**
Channel ID

**Param msg**
Message struct

**Return**
See return values for **mbox_send()**

typedef int (*mbox_mtu_get_t)(const struct device *dev)

Callback API to get maximum data size.

See **mbox_mtu_get()** for argument definitions.

typedef int (*mbox_register_callback_t)(const struct device *dev, uint32_t channel, mbox_callback_t cb, void *user_data)

Callback API upon registration.

See **mbox_register_callback()** for function description

**Param dev**
Driver instance

**Param channel**
Channel ID

**Param cb**
Callback function to execute on incoming message interrupts.

**Param user_data**
Application-specific data pointer which will be passed to the callback function when executed.
Return
See return values for `mbox_register_callback()`

typedef int (*mbox_set_enabled_t)(const struct device *dev, uint32_t channel, bool enable)
Callback API upon enablement of interrupts.
See `mbox_set_enabled()` for function description

Param dev
Driver instance

Param channel
Channel ID

Param enable
Set to 0 to disable and to nonzero to enable.

Return
See return values for `mbox_set_enabled()`

typedef uint32_t (*mbox_max_channels_get_t)(const struct device *dev)
Callback API to get maximum number of channels.
See `mbox_max_channels_get()` for argument definitions.

Functions

static inline void mbox_init_channel(struct mbox_channel *channel, const struct device *dev, uint32_t ch_id)
Initialize a channel struct.

Initialize an `mbox_channel` passed by the user with a provided MBOX device and channel ID. This function is needed when the information about the device and the channel ID is not in the DT. In the DT case `MBOX_DT_CHANNEL_GET()` must be used instead.

Parameters
• channel – Pointer to the channel struct
• dev – Driver instance
• ch_id – Channel ID

int mbox_send(const struct mbox_channel *channel, const struct mbox_msg *msg)
Try to send a message over the MBOX device.

Send a message over an `mbox_channel`. The msg parameter must be NULL when the driver is used for signalling.

If the msg parameter is not NULL, this data is expected to be delivered on the receiving side using the data parameter of the receiving callback.

Parameters
• channel – Channel instance pointer
• msg – Pointer to the message struct

Return values
• -EBUSY – If the remote hasn’t yet read the last data sent.
• -EMSGSIZE – If the supplied data size is unsupported by the driver.
• -EINVAL – If there was a bad parameter, such as: too-large channel descriptor or the device isn’t an outbound MBOX channel.
• 0 – On success, negative value on error.

static inline int mbox_register_callback(const struct mbox_channel *channel,
                                           mbox_callback_t cb, void *user_data)

Register a callback function on a channel for incoming messages.

This function doesn't assume anything concerning the status of the interrupts. Use mbox_set_enabled() to enable or to disable the interrupts if needed.

Parameters
• channel – Channel instance pointer.
• cb – Callback function to execute on incoming message interrupts.
• user_data – Application-specific data pointer which will be passed to the callback function when executed.

Return values
0 – On success, negative value on error.

int mbox_mtu_get(const struct device *dev)

Return the maximum number of bytes possible in an outbound message.

Returns the actual number of bytes that it is possible to send through an outgoing channel.

This number can be 0 when the driver only supports signalling or when on the receiving side the content and size of the message must be retrieved in an indirect way (i.e. probing some other peripheral, reading memory regions, etc...).

If this function returns 0, the msg parameter in mbox_send() is expected to be NULL.

Parameters
• dev – Driver instance pointer.

Returns
Maximum possible size of a message in bytes, 0 for signalling, negative value on error.

int mbox_set_enabled(const struct mbox_channel *channel, bool enable)

Enable (disable) interrupts and callbacks for inbound channels.

Enable interrupt for the channel when the parameter ‘enable’ is set to true. Disable it otherwise.

Immediately after calling this function with ‘enable’ set to true, the channel is considered enabled and ready to receive signal and messages (even already pending), so the user must take care of installing a proper callback (if needed) using mbox_register_callback() on the channel before enabling it. For this reason it is recommended that all the channels are disabled at probe time.

Enabling a channel for which there is no installed callback is considered undefined behavior (in general the driver must take care of gracefully handling spurious interrupts with no installed callback).

Parameters
• channel – Channel instance pointer.
• enable – Set to 0 to disable and to nonzero to enable.

Return values
• 0 – On success.
• -EINVAL – If it isn’t an inbound channel.
uint32_t mbox_max_channels_get(const struct device *dev)

Return the maximum number of channels.

Return the maximum number of channels supported by the hardware.

Parameters

• dev – Driver instance pointer.

Returns

Maximum possible number of supported channels on success, negative value on error.

struct mbox_msg

#include <mbox.h> Message struct (to hold data and its size).

Public Members

const void *data  
Pointer to the data sent in the message.

size_t size  
Size of the data.

struct mbox_channel

#include <mbox.h> Provides a type to hold an MBOX channel.
Struct type to hold an MBOX device pointer and the channel ID.

Public Members

const struct device *dev  
MBOX device pointer.

uint32_t id  
Channel ID.

struct mbox_driver_api

#include <mbox.h>

7.6.34 Peripheral Component Interconnect express Bus (PCIe)

Overview

API Reference

group pcie_host_interface

PCle Host Interface.
Defines

PCIE_ID_IS_VALID(id)

PCIE_DT_ID(node_id)
Get the PCIe Vendor and Device ID for a node.

Parameters
  • node_id – DTS node identifier

Returns
  The VID/DID combination as pcie_id_t

PCIE_DT_INST_ID(inst)
Get the PCIe Vendor and Device ID for a node.
This is equivalent to PCIE_DT_ID(DT_DRV_INST(inst))

Parameters
  • inst – Devicetree instance number

Returns
  The VID/DID combination as pcie_id_t

DEVICE_PCIE_DECLARE(node_id)
Declare a PCIe context variable for a DTS node.
Declares a PCIe context for a DTS node. This must be done before using the DEVICE_PCIE_INIT() macro for the same node.

Parameters
  • node_id – DTS node identifier

DEVICE_PCIE_INST_DECLARE(inst)
Declare a PCIe context variable for a DTS node.
This is equivalent to DEVICE_PCIE_DECLARE(DT_DRV_INST(inst))

Parameters
  • inst – Devicetree instance number

DEVICE_PCIE_INIT(node_id, name)
Initialize a named struct member to point at a PCIe context.
Initialize PCIe-related information within a specific instance of a device config struct, using information from DTS. Using the macro requires having first created PCIe context struct using the DEVICE_PCIE_DECLARE() macro.

Example for an instance of a driver belonging to the “foo” subsystem
struct foo_config { struct pcie_dev *pcie; ... };
DEVICE_PCIE_ID_DECLARE(DT_DRV_INST(...)); struct foo_config my_config = { DEVICE_PCIE_INIT(pcie, DT_DRV_INST(...)), ... };

Parameters
  • node_id – DTS node identifier
  • name – Member name within config for the MMIO region

DEVICE_PCIE_INST_INIT(inst, name)
Initialize a named struct member to point at a PCIe context.
This is equivalent to DEVICE_PCIE_INIT(DT_DRV_INST(inst), name)
Parameters
- \textit{inst} – Devicetree instance number
- \textit{name} – Name of the struct member (of type struct \textit{pcie_dev} *)

\textbf{PCIE\_HOST\_CONTROLLER}(\textit{n})
Get the BDF for a given PCI host controller.
This macro is useful when the PCI host controller behind PCIE\_BDF(0, 0, 0) indicates a multifunction device. In such a case each function of this endpoint is a potential host controller itself.

Parameters
- \textit{n} – Bus number

Returns
BDF value of the given host controller

PCIE\_CONF\_CAPPTR
PCIE\_CONF\_CAPPTR\_FIRST(\textit{w})
PCIE\_CONF\_CAP\_ID(\textit{w})
PCIE\_CONF\_CAP\_NEXT(\textit{w})

PCIE\_CONF\_EXT\_CAPPTR
PCIE\_CONF\_EXT\_CAP\_ID(\textit{w})
PCIE\_CONF\_EXT\_CAP\_VER(\textit{w})
PCIE\_CONF\_EXT\_CAP\_NEXT(\textit{w})

PCIE\_CONF\_ID
PCIE\_CONF\_CMDSTAT
PCIE\_CONF\_CMDSTAT\_IO
PCIE\_CONF\_CMDSTAT\_MEM
PCIE\_CONF\_CMDSTAT\_MASTER
PCIE\_CONF\_CMDSTAT\_INTERRUPT
PCIE\_CONF\_CMDSTAT\_CAPS
PCIE\_CONF\_CLASSREV
PCIE\_CONF\_CLASSREV\_CLASS(\textit{w})
PCIE\_CONF\_CLASSREV\_SUBCLASS(\textit{w})
PCIE\_CONF\_CLASSREV\_PROGIF(\textit{w})
PCIE_CONF_CLASSREV_REV(w)

PCIE_CONF_TYPE

PCIE_CONF_MULTIFUNCTION(w)

PCIE_CONF_TYPE_BRIDGE(w)

PCIE_CONF_TYPE_GET(w)

PCIE_CONF_TYPE_STANDARD

PCIE_CONF_TYPE_PCI_BRIDGE

PCIE_CONF_TYPE_CARDBUS_BRIDGE

PCIE_CONF_BAR0

PCIE_CONF_BAR1

PCIE_CONF_BAR2

PCIE_CONF_BAR3

PCIE_CONF_BAR4

PCIE_CONF_BAR5

PCIE_CONF_BAR_IO(w)

PCIE_CONF_BAR_MEM(w)

PCIE_CONF_BAR_64(w)

PCIE_CONF_BAR_ADDR(w)

PCIE_CONF_BAR_IO_ADDR(w)

PCIE_CONF_BAR_FLAGS(w)

PCIE_CONF_BAR_NONE

PCIE_CONF_BAR_INVAL

PCIE_CONF_BAR_INVAL64

PCIE_CONF_BAR_INVAL_FLAGS(w)

PCIE_BUS_NUMBER

PCIE_BUS_PRIMARY_NUMBER(w)

PCIE_BUS_SECONDARY_NUMBER(w)
PCIE_BUS_SUBORDINATE_NUMBER (w)
PCIE_SECONDARY_LATENCY_TIMER (w)
PCIE_BUS_NUMBER_VAL (prim, sec, sub, lat)

PCIE_IO_SEC_STATUS
PCIE_IO_BASE (w)
PCIE_IO_LIMIT (w)
PCIE_SEC_STATUS (w)
PCIE_IO_SEC_STATUS_VAL (job, iol, sec_status)

PCIE_MEM_BASE_LIMIT
PCIE_MEM_BASE (w)
PCIE_MEM_LIMIT (w)
PCIE_MEM_BASE_LIMIT_VAL (memb, meml)

PCIE_PREFETCH_BASE_LIMIT
PCIE_PREFETCH_BASE (w)
PCIE_PREFETCH_LIMIT (w)
PCIE_PREFETCH_BASE_LIMIT_VAL (pmemb, pmeml)

PCIE_PREFETCH_BASE_UPPER
PCIE_PREFETCH_LIMIT_UPPER
PCIE_IO_BASE_LIMIT_UPPER
PCIE_IO_BASE_UPPER (w)
PCIE_IO_LIMIT_UPPER (w)
PCIE_IO_BASE_LIMIT_UPPER_VAL (iobu, iolu)

PCIE_CONF_INTR
PCIE_CONF_INTR_IRQ (w)
PCIE_CONF_INTR_IRQ_NONE

PCIE_MAX_BUS
PCIE_MAX_DEV
PCIE_MAX_FUNC
PCIE_IRQ_CONNECT(bdf_p, irq_p, priority_p, isr_p, isr_param_p, flags_p)
Initialize an interrupt handler for a PCIe endpoint IRQ.

This routine is only meant to be used by drivers using PCIe bus and having fixed or MSI based IRQ (so no runtime detection of the IRQ). In case of runtime detection see pcie_connect_dynamic_irq()

Parameters
- bdf_p – PCIe endpoint BDF
- irq_p – IRQ line number.
- priority_p – Interrupt priority.
- isr_p – Address of interrupt service routine.
- isr_param_p – Parameter passed to interrupt service routine.
- flags_p – Architecture-specific IRQ configuration flags.

Typedefs

typedef uint32_t pcie_bdf_t
A unique PCI(e) endpoint (bus, device, function).
A PCI(e) endpoint is uniquely identified topologically using a (bus, device, function) tuple. The internal structure is documented in include/dt-bindings/pcie/pcie.h: see PCIE_BDF() and friends, since these tuples are referenced from devicetree.

typedef uint32_t pcie_id_t
A unique PCI(e) identifier (vendor ID, device ID).
The PCIE_CONF_ID register for each endpoint is a (vendor ID, device ID) pair, which is meant to tell the system what the PCI(e) endpoint is. Again, look to PCIE_ID_* macros in include/dt-bindings/pcie/pcie.h for more.

typedef bool (*pcie_scan_cb_t)(pcie_bdf_t bdf, pcie_id_t id, void *cb_data)
Callback type used for scanning for PCI endpoints.

Param bdf
BDF value for a found endpoint.

Param id
Vendor & Device ID for the found endpoint.

Param cb_data
Custom, use case specific data.

Return
true to continue scanning, false to stop scanning.

Enums

Values:

enumerator PCIE_SCAN_RECURSIVE = BIT(0)
Scan all available PCI host controllers and sub-busses.
enumerator PCIE_SCAN_CB_ALL = BIT(1)
    Do the callback for all endpoint types, including bridges.

Functions

pcie_bdf_t pcie_bdf_lookup(pcie_id_t id)
    Look up the BDF based on PCI(e) vendor & device ID.
    This function is used to look up the BDF for a device given its vendor and device ID.

    Deprecated:
    See also:
    DEVICE_PCIE_DECLARE

    Parameters
    • id – PCI(e) vendor & device ID encoded using PCIE_ID()

    Returns
    The BDF for the device, or PCIE_BDF_NONE if it was not found

uint32_t pcie_conf_read(pcie_bdf_t bdf, unsigned int reg)
    Read a 32-bit word from an endpoint's configuration space.
    This function is exported by the arch/SoC/board code.

    Parameters
    • bdf – PCI(e) endpoint
    • reg – the configuration word index (not address)

    Returns
    the word read (0xFFFFFFFFU if nonexistent endpoint or word)

void pcie_conf_write(pcie_bdf_t bdf, unsigned int reg, uint32_t data)
    Write a 32-bit word to an endpoint's configuration space.
    This function is exported by the arch/SoC/board code.

    Parameters
    • bdf – PCI(e) endpoint
    • reg – the configuration word index (not address)
    • data – the value to write

int pcie_scan(const struct pcie_scan_opt *opt)
    Scan for PCIe devices.
    Scan the PCI bus (or busses) for available endpoints.

    Parameters
    • opt – Options determining how to perform the scan.

    Returns
    0 on success, negative POSIX error number on failure.
bool pcie_probe(pcie_bdf_t bdf, pcie_id_t id)
    Probe for the presence of a PCI(e) endpoint.

    Deprecated:
    See also:
    DEVICE_PCIE_DECLARE

    Parameters
    • bdf – the endpoint to probe
    • id – the endpoint ID to expect, or PCIE_ID_NONE for “any device”

    Returns
    true if the device is present, false otherwise

bool pcie_get_mbar(pcie_bdf_t bdf, unsigned int bar_index, struct pcie_bar *mbar)
    Get the MBAR at a specific BAR index.

    Parameters
    • bdf – the PCI(e) endpoint
    • bar_index – 0-based BAR index
    • mbar – Pointer to struct pcie_bar

    Returns
    true if the mbar was found and is valid, false otherwise

bool pcie_probe_mbar(pcie_bdf_t bdf, unsigned int index, struct pcie_bar *mbar)
    Probe the nth MMIO address assigned to an endpoint.

    A PCI(e) endpoint has 0 or more memory-mapped regions. This function allows the
caller to enumerate them by calling with index=0..n. Value of n has to be below 6,
as there is a maximum of 6 BARs. The indices are order-preserving with respect to
the endpoint BARs: e.g., index 0 will return the lowest-numbered memory BAR on the
endpoint.

    Parameters
    • bdf – the PCI(e) endpoint
    • index – (0-based) index
    • mbar – Pointer to struct pcie_bar

    Returns
    true if the mbar was found and is valid, false otherwise

bool pcie_get_iobar(pcie_bdf_t bdf, unsigned int bar_index, struct pcie_bar *iobar)
    Get the I/O BAR at a specific BAR index.

    Parameters
    • bdf – the PCI(e) endpoint
    • bar_index – 0-based BAR index
    • iobar – Pointer to struct pcie_bar

    Returns
    true if the I/O BAR was found and is valid, false otherwise
bool `pcie_probe_iobar` *(pcie_bdf_t bdf, unsigned int index, struct pcie_bar *iobar)*
Probes the nth I/O BAR address assigned to an endpoint.

A PCI(e) endpoint has 0 or more I/O regions. This function allows the caller to enumerate them by calling with index=0..n. Value of n has to be below 6, as there is a maximum of 6 BARs. The indices are order-preserving with respect to the endpoint BARs: e.g., index 0 will return the lowest-numbered I/O BAR on the endpoint.

**Parameters**
- `bdf` – the PCI(e) endpoint
- `index` – (0-based) index
- `iobar` – Pointer to struct `pcie_bar`

**Returns**
true if the I/O BAR was found and is valid, false otherwise

void `pcie_set_cmd` *(pcie_bdf_t bdf, uint32_t bits, bool on)*
Set or reset bits in the endpoint command/status register.

**Parameters**
- `bdf` – the PCI(e) endpoint
- `bits` – the powerset of bits of interest
- `on` – use true to set bits, false to reset them

unsigned int `pcie_alloc_irq` *(pcie_bdf_t bdf)*
Allocate an IRQ for an endpoint.
This function first checks the IRQ register and if it contains a valid value this is returned. If the register does not contain a valid value allocation of a new one is attempted. Such function is only exposed if CONFIG_PCIE_CONTROLLER is unset. It is thus available where architecture tied dynamic IRQ allocation for PCIe device makes sense.

**Parameters**
- `bdf` – the PCI(e) endpoint

**Returns**
the IRQ number, or PCIE_CONF_INTR_IRQ_NONE if allocation failed.

unsigned int `pcie_get_irq` *(pcie_bdf_t bdf)*
Return the IRQ assigned by the firmware/board to an endpoint.

**Parameters**
- `bdf` – the PCI(e) endpoint

**Returns**
the IRQ number, or PCIE_CONF_INTR_IRQ_NONE if unknown.

void `pcie_irq_enable` *(pcie_bdf_t bdf, unsigned int irq)*
Enable the PCI(e) endpoint to generate the specified IRQ.

If MSI is enabled and the endpoint supports it, the endpoint will be configured to generate the specified IRQ via MSI. Otherwise, it is assumed that the IRQ has been routed by the boot firmware to the specified IRQ, and the IRQ is enabled (at the I/O APIC, or wherever appropriate).

**Parameters**
uint32_t pcie_get_cap(pcie_bdf_t bdf, uint32_t cap_id)
Find a PCI(e) capability in an endpoint's configuration space.

Parameters
• bdf – the PCI endpoint to examine
• cap_id – the capability ID of interest

Returns
the index of the configuration word, or 0 if no capability.

uint32_t pcie_get_ext_cap(pcie_bdf_t bdf, uint32_t cap_id)
Find an Extended PCI(e) capability in an endpoint's configuration space.

Parameters
• bdf – the PCI endpoint to examine
• cap_id – the capability ID of interest

Returns
the index of the configuration word, or 0 if no capability.

bool pcie_connect_dynamic_irq(pcie_bdf_t bdf, unsigned int irq, unsigned int priority,
void (*routine)(const void *parameter), const void *parameter,
uint32_t flags)
Dynamically connect a PCIe endpoint IRQ to an ISR handler.

Parameters
• bdf – the PCI endpoint to examine
• irq – the IRQ to connect (see pcie_alloc_irq())
• priority – priority of the IRQ
• routine – the ISR handler to connect to the IRQ
• parameter – the parameter to provide to the handler
• flags – IRQ connection flags

Returns
true if connected, false otherwise

struct pcie_dev
#include <pcie.h>

struct pcie_bar
#include <pcie.h>

struct pcie_scan_opt
#include <pcie.h> Options for performing a scan for PCI devices.

Public Members

uint8_t bus
Initial bus number to scan.
7.6.35 Platform Environment Control Interface (PECI)

Overview

The Platform Environment Control Interface, abbreviated as PECI, is a thermal management standard introduced in 2006 with the Intel Core 2 Duo Microprocessors. The PECI interface allows external devices to read processor temperature, perform processor manageability functions, and manage processor interface tuning and diagnostics. The PECI bus driver APIs enable the interaction between Embedded Microcontrollers and CPUs.

Configuration Options

Related configuration options:

- CONFIG_PECI

API Reference

Related code samples

PECI interface

Monitor CPU temperature using PECI.

PECI read/write supported responses.

- PECI_CC_RSP_SUCCESS
- PECI_CC_RSP_TIMEOUT
- PECI_CC_OUT_OF_RESOURCES_TIMEOUT
- PECI_CC_RESOURCES_LOWPWR_TIMEOUT
- PECI_CC_ILLEGAL_REQUEST
Ping command format.

PECI_PING_WR_LEN
PECI_PING_RD_LEN
PECI_PING_LEN

GetDIB command format.

PECI_GET_DIB_WR_LEN
PECI_GET_DIB_RD_LEN
PECI_GET_DIB_CMD_LEN
PECI_GET_DIB_DEVINFO
PECI_GET_DIB_REVNUM
PECI_GET_DIB_DOMAIN_BIT_MASK
PECI_GET_DIB_MAJOR_REV_MASK
PECI_GET_DIB_MINOR_REV_MASK

GetTemp command format.

PECI_GET_TEMP_WR_LEN
PECI_GET_TEMP_RD_LEN
PECI_GET_TEMP_CMD_LEN
PECI_GET_TEMP_LSB
PECI_GET_TEMP_MSB
PECI_GET_TEMP_ERR_MSB
PECI_GET_TEMP_ERR_LSB_GENERAL
PECI_GET_TEMP_ERR_LSB_RES
PECI_GET_TEMP_ERR_LSB_TEMP_LO
PECI_GET_TEMP_ERR_LSB_TEMP_HI

**RdPkgConfig command format.**

PECI_RD_PKG_WR_LEN
PECI_RD_PKG_LEN_BYTE
PECI_RD_PKG_LEN_WORD
PECI_RD_PKG_LEN_DWORD
PECI_RD_PKG_CMD_LEN

**WrPkgConfig command format.**

PECI_WR_PKG_RD_LEN
PECI_WR_PKG_LEN_BYTE
PECI_WR_PKG_LEN_WORD
PECI_WR_PKG_LEN_DWORD
PECI_WR_PKG_CMD_LEN

**RdIAMSR command format.**

PECI_RD_IAMSR_WR_LEN
PECI_RD_IAMSR_LEN_BYTE
PECI_RD_IAMSR_LEN_WORD
PECI_RD_IAMSR_LEN_DWORD
PECI_RD_IAMSR_LEN_QWORD
PECI_RD_IAMSR_CMD_LEN
WrIAMS Rincomand format.

PECI_WR_IAMSRRD_LEN
PECI_WR_IAMSR_LEN_BYTE
PECI_WR_IAMSR_LENWORD
PECI_WR_IAMSR_LEN_DWORD
PECI_WR_IAMSR_LEN_QWORD
PECI_WR_IAMSR_CMD_LEN

RdPClConfig command format.

PECI_RD_PCICFG_WR_LEN
PECI_RD_PCICFG_LEN_BYTE
PECI_RD_PCICFG_LEN_WORD
PECI_RD_PCICFG_LEN_DWORD
PECI_RD_PCICFG_CMD_LEN

WrPClConfig command format.

PECI_WR_PCICFG_RD_LEN
PECI_WR_PCICFG_LEN_BYTE
PECI_WR_PCICFG_LEN_WORD
PECI_WR_PCICFG_LEN_DWORD
PECI_WR_PCICFG_CMD_LEN

RdPClConfigLocal command format.

PECI_RD_PCICFGL_WR_LEN
PECI_RD_PCICFGL_RD_LEN_BYTE
PECI_RD_PCICFGL_RD_LEN_WORD
PECI_RD_PCICFGL_RD_LEN_DWORD
PECI_RD_PCICFGL_CMD_LEN

**WrPCIConfigLocal command format.**

PECI_WR_PCICFGL_RD_LEN
PECI_WR_PCICFGL_WR_LEN_BYTE
PECI_WR_PCICFGL_WR_LEN_WORD
PECI_WR_PCICFGL_WR_LEN_DWORD
PECI_WR_PCICFGL_CMD_LEN

**Enums**

enum peci_error_code

PECI error codes.

**Values:**

enumerator PECI_GENERAL_SENSOR_ERROR = 0x8000
enumerator PECI_UNDERFLOW_SENSOR_ERROR = 0x8002
enumerator PECI_OVERFLOW_SENSOR_ERROR = 0x8003

denum peci_command_code

PECI commands.

**Values:**

enumerator PECI_CMD_PING = 0x00
enumerator PECI_CMD_GET_TEMP0 = 0x01
enumerator PECI_CMD_GET_TEMP1 = 0x02
enumerator PECI_CMD_RD_PCI_CFG0 = 0x61
enumerator PECI_CMD_RD_PCI_CFG1 = 0x62
enumerator PECI_CMD_WR_PCI_CFG0 = 0x65
enumerator PECI_CMD_WR_PCI_CFG1 = 0x66
enumerator PECI_CMD_RD_PKG_CFG0 = 0xA1
enumerator PECI_CMD_RD_PKG_CFG1 = 0xA
enumerator PECI_CMD_WR_PKG_CFG0 = 0xA5
enumerator PECI_CMD_WR_PKG_CFG1 = 0xA6
enumerator PECI_CMD_RD_IAMSR0 = 0xB1
enumerator PECI_CMD_RD_IAMSR1 = 0xB2
enumerator PECI_CMD_WR_IAMSR0 = 0xB5
enumerator PECI_CMD_WR_IAMSR1 = 0xB6
enumerator PECI_CMD_RD_PCI_CFG_LOCAL0 = 0xE1
enumerator PECI_CMD_RD_PCI_CFG_LOCAL1 = 0xE2
enumerator PECI_CMD_WR_PCI_CFG_LOCAL0 = 0xE5
enumerator PECI_CMD_WR_PCI_CFG_LOCAL1 = 0xE6
enumerator PECI_CMD_GET_DIB = 0xF7

Functions

int peci_config(const struct device *dev, uint32_t bitrate)
Configures the PECI interface.

Parameters
• dev – Pointer to the device structure for the driver instance.
• bitrate – the selected bitrate expressed in Kbps.

Return values
• 0 – If successful.
• Negative – errno code if failure.

int peci_enable(const struct device *dev)
Enable PECI interface.

Parameters
• dev – Pointer to the device structure for the driver instance.
Return values

- 0 – If successful.
- Negative – errno code if failure.

int peci_disable(const struct device *dev)

Disable PECI interface.

Parameters

- dev – Pointer to the device structure for the driver instance.

Return values

- 0 – If successful.
- Negative – errno code if failure.

int peci_transfer(const struct device *dev, struct peci_msg *msg)

Performs a PECI transaction.

Parameters

- dev – Pointer to the device structure for the driver instance.
- msg – Structure representing a PECI transaction.

Return values

- 0 – If successful.
- Negative – errno code if failure.

struct peci_buf

#include <peci.h> PECI buffer structure.

Public Members

uint8_t *buf

Valid pointer on a data buffer, or NULL otherwise.

size_t len

Length of the data buffer expected to be received without considering the frame check sequence byte.

Note: Frame check sequence byte is added into rx buffer: need to allocate an additional byte for this in rx buffer.

struct peci_msg

#include <peci.h> PECI transaction packet format.

Public Members

uint8_t addr

Client address.
enum peci_command_code cmd_code
    Command code.

struct peci_buf tx_buffer
    Pointer to buffer of write data.

struct peci_buf rx_buffer
    Pointer to buffer of read data.

uint8_t flags
    PECI msg flags.

7.6.36 PS/2

Overview

The PS/2 connector first hit the market in 1987 on IBM’s desktop PC line of the same name before becoming an industry-wide standard for mouse and keyboard connections. Starting around 2007, USB superseded PS/2 and is the modern peripheral device connection standard. For legacy support on boards with a PS/2 connector, Zephyr provides these PS/2 driver APIs.

Configuration Options

Related configuration options:

- CONFIG_PS2

API Reference

Related code samples

PS/2 interface
    Communicate with a PS/2 mouse.

group ps2_interface
    PS/2 Driver APIs.

Typedefs

typedef void (*ps2_callback_t)(const struct device *dev, uint8_t data)
    PS/2 callback called when user types or click a mouse.

    Param dev
        Pointer to the device structure for the driver instance.

    Param data
        Data byte passed pack to the user.
Functions

int ps2_config(const struct device *dev, ps2_callback_t callback_isr)
Configure a ps2 instance.

Parameters
• dev – Pointer to the device structure for the driver instance.
• callback_isr – called when PS/2 devices reply to a configuration command or when a mouse/keyboard send data to the client application.

Return values
• 0 – If successful.
• Negative – errno code if failure.

int ps2_write(const struct device *dev, uint8_t value)
Write to PS/2 device.

Parameters
• dev – Pointer to the device structure for the driver instance.
• value – Data for the PS2 device.

Return values
• 0 – If successful.
• Negative – errno code if failure.

int ps2_read(const struct device *dev, uint8_t *value)
Read slave-to-host values from PS/2 device.

Parameters
• dev – Pointer to the device structure for the driver instance.
• value – Pointer used for reading the PS/2 device.

Return values
• 0 – If successful.
• Negative – errno code if failure.

int ps2_enable_callback(const struct device *dev)
Enables callback.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• Negative – errno code if failure.

int ps2_disable_callback(const struct device *dev)
Disables callback.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• Negative – errno code if failure.
7.6.37 Pulse Width Modulation (PWM)

Overview

API Reference

Related code samples

Fade LED
Fade an LED using the PWM API.

PWM Blinky
Blink an LED using the PWM API.

PWM RGB LED
Drive an RGB LED using the PWM API.

Servomotor
Drive a servomotor using the PWM API.

group pwm_interface
PWM Interface.

PWM capture configuration flags

PWM_CAPTURE_TYPE_PERIOD
PWM pin capture captures period.

PWM_CAPTURE_TYPE_PULSE
PWM pin capture captures pulse width.

PWM_CAPTURE_TYPE_BOTH
PWM pin capture captures both period and pulse width.

PWM_CAPTURE_MODE_SINGLE
PWM pin capture captures a single period/pulse width.

PWM_CAPTURE_MODE_CONTINUOUS
PWM pin capture captures period/pulse width continuously.

PWM period set helpers

The period cell in the PWM specifier needs to be provided in nanoseconds. However, in some applications it is more convenient to use another scale.

PWM_NSEC(x)
Specify PWM period in nanoseconds.

PWM_USEC(x)
Specify PWM period in microseconds.
PWM_MSEC(x)
Specify PWM period in milliseconds.

PWM_SEC(x)
Specify PWM period in seconds.

PWM_HZ(x)
Specify PWM frequency in hertz.

PWM_KHZ(x)
Specify PWM frequency in kilohertz.

**PWM polarity flags**

The `PWM_POLARITY_*` flags are used with `pwm_set_cycles()`, `pwm_set()` or `pwm_configure_capture()` to specify the polarity of a PWM channel.

The flags are on the lower 8 bits of the `pwm_flags_t` union.

**PWM_POLARITY_NORMAL**
PWM pin normal polarity (active-high pulse).

**PWM_POLARITY_INVERTED**
PWM pin inverted polarity (active-low pulse).

**Defines**

`PWM_DT_SPEC_GET_BY_NAME(node_id, name)`
Static initializer for a struct `pwm_dt_spec`.

This returns a static initializer for a struct `pwm_dt_spec` given a devicetree node identifier and an index.

Example devicetree fragment:
```
{n: node {
    pwns = <&pwm1 1 1000 PWM_POLARITY_NORMAL>,
          <&pwm2 3 2000 PWM_POLARITY_INVERTED>;
    pwm-names = "alpha", "beta";
};
```

Example usage:
```
const struct pwm_dt_spec spec =
    PWM_DT_SPEC_GET_BY_NAME(DT_NODELABEL(n), alpha);

// Initializes 'spec' to:
// { 
//    .dev = DEVICE_DT_GET(DT_NODELABEL(pwm1)),
//    .channel = 1,
//    .period = 1000,
//    .flags = PWM_POLARITY_NORMAL,
// }
```

The device (dev) must still be checked for readiness, e.g. using `device_is_ready()`. It is an error to use this macro unless the node exists, has the 'pwms' property, and that 'pwms' property specifies a PWM controller, a channel, a period in nanoseconds and optionally flags.
See also:

**PWM_DT_SPEC_INST_GET_BY_NAME**

**Parameters**

- `node_id` – Devicetree node identifier.
- `name` – Lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property.

**Returns**

Static initializer for a struct `pwm_dt_spec` for the property.

`PWM_DT_SPEC_INST_GET_BY_NAME(inst, name)`  
Static initializer for a struct `pwm_dt_spec` from a DT_DRV_COMPAT instance.

See also:

**PWM_DT_SPEC_GET_BY_NAME**

**Parameters**

- `inst` – DT_DRV_COMPAT instance number
- `name` – Lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property

**Returns**

Static initializer for a struct `pwm_dt_spec` for the property.

`PWM_DT_SPEC_GET_BY_NAME_OR(node_id, name, default_value)`  
Like `PWM_DT_SPEC_GET_BY_NAME()`, with a fallback to a default value.

If the devicetree node identifier ‘node_id’ refers to a node with a property ‘pwms’, this expands to `PWM_DT_SPEC_GET_BY_NAME(node_id, name)`. The default_value parameter is not expanded in this case. Otherwise, this expands to `default_value`.

See also:

**PWM_DT_SPEC_INST_GET_BY_NAME_OR**

**Parameters**

- `node_id` – Devicetree node identifier.
- `name` – Lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property
- `default_value` – Fallback value to expand to.

**Returns**

Static initializer for a struct `pwm_dt_spec` for the property, or `default_value` if the node or property do not exist.

`PWM_DT_SPEC_INST_GET_BY_NAME_OR(inst, name, default_value)`  
Like `PWM_DT_SPEC_INST_GET_BY_NAME_OR()` , with a fallback to a default value.

See also:

**PWM_DT_SPEC_GET_BY_NAME_OR**
Parameters

- `inst` – DT_DRV_COMPAT instance number
- `name` – Lowercase-and-underscores name of a pwms element as defined by the node's pwm-names property.
- `default_value` – Fallback value to expand to.

Returns

Static initializer for a struct `pwm_dt_spec` for the property, or `default_value` if the node or property do not exist.

`PWM_DT_SPEC_GET_BY_IDX(node_id, idx)`

Static initializer for a struct `pwm_dt_spec`.

This returns a static initializer for a struct `pwm_dt_spec` given a devicetree node identifier and an index.

Example devicetree fragment:

```plaintext
n: node {
  pwms = <&pwm1 1 1000 PWM_POLARITY_NORMAL>,
         <&pwm2 3 2000 PWM_POLARITY_INVERTED>;
}
```

Example usage:

```c
const struct pwm_dt_spec spec = 
  PWM_DT_SPEC_GET_BY_IDX(DT_NODELABEL(n), 1);
// Initializes 'spec' to:
// { 
//   .dev = DEVICE_DT_GET(DT_NODELABEL(pwm2)),
//   .channel = 3,
//   .period = 2000,
//   .flags = PWM_POLARITY_INVERTED,
// }
```

The device (dev) must still be checked for readiness, e.g. using `device_is_ready()`. It is an error to use this macro unless the node exists, has the ‘pwms’ property, and that ‘pwms’ property specifies a PWM controller, a channel, a period in nanoseconds and optionally flags.

See also:

`PWM_DT_SPEC_INST_GET_BY_IDX`

Parameters

- `node_id` – Devicetree node identifier.
- `idx` – Logical index into ‘pwms’ property.

Returns

Static initializer for a struct `pwm_dt_spec` for the property.

`PWM_DT_SPEC_INST_GET_BY_IDX(inst, idx)`

Static initializer for a struct `pwm_dt_spec` from a DT_DRV_COMPAT instance.

See also:

`PWM_DT_SPEC_GET_BY_IDX`
Parameters

- `inst` – DT_DRV_COMPAT instance number
- `idx` – Logical index into ‘pwms’ property.

Returns
Static initializer for a struct `pwm_dt_spec` for the property.

`PWM_DT_SPEC_GET_BY_IDX_OR(node_id, idx, default_value)`

Like `PWM_DT_SPEC_GET_BY_IDX()`, with a fallback to a default value.

If the devicetree node identifier `node_id` refers to a node with a property ‘pwms’, this expands to `PWM_DT_SPEC_GET_BY_IDX(node_id, idx)`. The `default_value` parameter is not expanded in this case. Otherwise, this expands to `default_value`.

See also:
`PWM_DT_SPEC_INST_GET_BY_IDX_OR`

Parameters

- `node_id` – Devicetree node identifier.
- `idx` – Logical index into ‘pwms’ property.
- `default_value` – Fallback value to expand to.

Returns
Static initializer for a struct `pwm_dt_spec` for the property, or `default_value` if the node or property do not exist.

`PWM_DT_SPEC_INST_GET_BY_IDX_OR(inst, idx, default_value)`

Like `PWM_DT_SPEC_INST_GET_BY_IDX_OR()`, with a fallback to a default value.

See also:
`PWM_DT_SPEC_INST_GET_BY_IDX_OR`

Parameters

- `inst` – DT_DRV_COMPAT instance number
- `idx` – Logical index into ‘pwms’ property.
- `default_value` – Fallback value to expand to.

Returns
Static initializer for a struct `pwm_dt_spec` for the property, or `default_value` if the node or property do not exist.

`PWM_DT_SPEC_GET(node_id)`

Equivalent to `PWM_DT_SPEC_GET_BY_IDX(node_id, 0)`.

See also:

`PWM_DT_SPEC_GET_BY_IDX`

See also:

`PWM_DT_SPEC_INST_GET`
• node_id – Devicetree node identifier.

**Returns**
Static initializer for a struct `pwm_dt_spec` for the property.

```c
PWM_DT_SPEC_INST_GET(inst)
```
Equivalent to `PWM_DT_SPEC_INST_GET_BY_IDX(inst, 0)`.

**See also:**
`PWM_DT_SPEC_INST_GET_BY_IDX`

**See also:**
`PWM_DT_SPEC_GET`

**Parameters**

• inst – DT_DRV_COMPAT instance number

**Returns**
Static initializer for a struct `pwm_dt_spec` for the property.

```c
PWM_DT_SPEC_GET_OR(node_id, default_value)
```
Equivalent to `PWM_DT_SPEC_GET_BY_IDX_OR(node_id, 0, default_value)`.

**See also:**
`PWM_DT_SPEC_GET_BY_IDX_OR`

**See also:**
`PWM_DT_SPEC_INST_GET_OR`

**Parameters**

• node_id – Devicetree node identifier.

• default_value – Fallback value to expand to.

**Returns**
Static initializer for a struct `pwm_dt_spec` for the property.

```c
PWM_DT_SPEC_INST_GET_OR(inst, default_value)
```
Equivalent to `PWM_DT_SPEC_INST_GET_BY_IDX_OR(inst, 0, default_value)`.

**See also:**
`PWM_DT_SPEC_INST_GET_BY_IDX_OR`

**See also:**
`PWM_DT_SPEC_GET_OR`

**Parameters**

• inst – DT_DRV_COMPAT instance number

• default_value – Fallback value to expand to.

**Returns**
Static initializer for a struct `pwm_dt_spec` for the property.
**Typedefs**

typedef uint16_t pwm_flags_t

Provides a type to hold PWM configuration flags.

The lower 8 bits are used for standard flags. The upper 8 bits are reserved for SoC specific flags.

**See also:**

PWM_CAPTURE_FLAGS.

typedef void (*pwm_capture_callback_handler_t)(const struct device *dev, uint32_t channel, uint32_t period_cycles, uint32_t pulse_cycles, int status, void *user_data)

PWM capture callback handler function signature.

**Note:** The callback handler will be called in interrupt context.

**Note:** CONFIG_PWM_CAPTURE must be selected to enable PWM capture support.

**Param dev**

[in] PWM device instance.

**Param channel**

PWM channel.

**Param period_cycles**

Captured PWM period width (in clock cycles). HW specific.

**Param pulse_cycles**

Captured PWM pulse width (in clock cycles). HW specific.

**Param status**

Status for the PWM capture (0 if no error, negative errno otherwise. See pwm_capture_cycles() return value descriptions for details).

**Param user_data**

User data passed to pwm_configure_capture()

**Functions**

int pwm_set_cycles(const struct device *dev, uint32_t channel, uint32_t period, uint32_t pulse, pwm_flags_t flags)

Set the period and pulse width for a single PWM output.

The PWM period and pulse width will synchronously be set to the new values without glitches in the PWM signal, but the call will not block for the change to take effect.

Passing 0 as pulse will cause the pin to be driven to a constant inactive level. Passing a non-zero pulse equal to period will cause the pin to be driven to a constant active level.
Note: Not all PWM controllers support synchronous, glitch-free updates of the PWM period and pulse width. Depending on the hardware, changing the PWM period and/or pulse width may cause a glitch in the generated PWM signal.

Note: Some multi-channel PWM controllers share the PWM period across all channels. Depending on the hardware, changing the PWM period for one channel may affect the PWM period for the other channels of the same PWM controller.

**Parameters**

- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **period** – Period (in clock cycles) set to the PWM. HW specific.
- **pulse** – Pulse width (in clock cycles) set to the PWM. HW specific.
- **flags** – Flags for pin configuration.

**Return values**

- **0** – If successful.
- **-EINVAL** – If pulse > period.
- **-errno** – Negative errno code on failure.

```
int pwm_get_cycles_per_sec(const struct device *dev, uint32_t channel, uint64_t *cycles)
```

Get the clock rate (cycles per second) for a single PWM output.

**Parameters**

- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **cycles** – [out] Pointer to the memory to store clock rate (cycles per sec). HW specific.

**Return values**

- **0** – If successful.
- **-errno** – Negative errno code on failure.

```
static inline int pwm_set(const struct device *dev, uint32_t channel, uint32_t period,
                          uint32_t pulse, pwm_flags_t flags)
```

Set the period and pulse width in nanoseconds for a single PWM output.

**Note:** Utility macros such as `PWM_MSEC` can be used to convert from other scales or units to nanoseconds, the units used by this function.

**Parameters**

- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **period** – Period (in nanoseconds) set to the PWM.
- **pulse** – Pulse width (in nanoseconds) set to the PWM.
- **flags** – Flags for pin configuration (polarity).
Return values

- 0 – If successful.
- -ENOTSUP – If requested period or pulse cycles are not supported.
- -errno – Other negative errno code on failure.

static inline int pwm_set_dt(const struct pwm_dt_spec *spec, uint32_t period, uint32_t pulse)

Set the period and pulse width in nanoseconds from a struct pwm_dt_spec (with custom period).

This is equivalent to:
```
pwm_set(spec->dev, spec->channel, period, pulse, spec->flags)
```

The period specified in spec is ignored. This API call can be used when the period specified in Devicetree needs to be changed at runtime.

See also:
```
pwm_set_pulse_dt()
```

Parameters

- period – Period (in nanoseconds) set to the PWM.
- pulse – Pulse width (in nanoseconds) set to the PWM.

Returns

A value from pwm_set().

static inline int pwm_set_pulse_dt(const struct pwm_dt_spec *spec, uint32_t pulse)

Set the period and pulse width in nanoseconds from a struct pwm_dt_spec.

This is equivalent to:
```
pwm_set(spec->dev, spec->channel, spec->period, pulse, spec->flags)
```

See also:
```
pwm_set_pulse_dt()
```

Parameters

- pulse – Pulse width (in nanoseconds) set to the PWM.

Returns

A value from pwm_set().

static inline int pwm_cycles_to_usec(const struct device *dev, uint32_t channel, uint32_t cycles, uint64_t *usec)

Convert from PWM cycles to microseconds.

Parameters

- channel – PWM channel.
- cycles – Cycles to be converted.
• **usec** – **[out]** Pointer to the memory to store calculated usec.

**Return values**

- **0** – If successful.
- **-ERANGE** – If result is too large.
- **-errno** – Other negative errno code on failure.

static inline int pwm_cycles_to_nsec(const struct device *dev, uint32_t channel, uint32_t cycles, uint64_t *nsec)

Convert from PWM cycles to nanoseconds.

**Parameters**

- **dev** – **[in]** PWM device instance.
- **channel** – PWM channel.
- **cycles** – Cycles to be converted.
- **nsec** – **[out]** Pointer to the memory to store the calculated nsec.

**Return values**

- **0** – If successful.
- **-ERANGE** – If result is too large.
- **-errno** – Other negative errno code on failure.

static inline int pwm_configure_capture(const struct device *dev, uint32_t channel, pwm_flags_t flags, pwm_capture_callback_handler_t cb, void *user_data)

Configure PWM period/pulse width capture for a single PWM input.

After configuring PWM capture using this function, the capture can be enabled/disabled using **pwm_enable_capture()** and **pwm_disable_capture()**.

**Note:** This API function cannot be invoked from user space due to the use of a function callback. In user space, one of the simpler API functions (**pwm_capture_cycles()**, **pwm_capture_usec()**, or **pwm_capture_nsec()**) can be used instead.

**Note:** **CONFIG_PWM_CAPTURE** must be selected for this function to be available.

**Parameters**

- **dev** – **[in]** PWM device instance.
- **channel** – PWM channel.
- **flags** – PWM capture flags
- **cb** – **[in]** Application callback handler function to be called upon capture
- **user_data** – **[in]** User data to pass to the application callback handler function

**Return values**

- **-EINVAL** – if invalid function parameters were given
- **-ENOSYS** – if PWM capture is not supported or the given flags are not supported
• -EIO – if IO error occurred while configuring
• -EBUSY – if PWM capture is already in progress

int pwm_enable_capture(const struct device *dev, uint32_t channel)
Enable PWM period/pulse width capture for a single PWM input.
The PWM pin must be configured using pwm_configure_capture() prior to calling this function.

Note: CONFIG_PWM_CAPTURE must be selected for this function to be available.

Parameters
• dev – [in] PWM device instance.
• channel – PWM channel.

Return values
• 0 – If successful.
• -EINVAL – if invalid function parameters were given
• -ENOSYS – if PWM capture is not supported
• -EIO – if IO error occurred while enabling PWM capture
• -EBUSY – if PWM capture is already in progress

int pwm_disable_capture(const struct device *dev, uint32_t channel)
Disable PWM period/pulse width capture for a single PWM input.

Note: CONFIG_PWM_CAPTURE must be selected for this function to be available.

Parameters
• dev – [in] PWM device instance.
• channel – PWM channel.

Return values
• 0 – If successful.
• -EINVAL – if invalid function parameters were given
• -ENOSYS – if PWM capture is not supported
• -EIO – if IO error occurred while disabling PWM capture

int pwm_capture_cycles(const struct device *dev, uint32_t channel, pwm_flags_t flags, uint32_t *period, uint32_t *pulse, k_timeout_t timeout)
Capture a single PWM period/pulse width in clock cycles for a single PWM input.
This API function wraps calls to pwm_configure_capture(), pwm_enable_capture(), and pwm_disable_capture() and passes the capture result to the caller. The function is blocking until either the PWM capture is completed or a timeout occurs.

Note: CONFIG_PWM_CAPTURE must be selected for this function to be available.

Parameters
Capture a single PWM period/pulse width in microseconds for a single PWM input. This API function wraps calls to `pwm_capture_cycles()` and `pwm_cycles_to_usec()` and passes the capture result to the caller. The function is blocking until either the PWM capture is completed or a timeout occurs.

**Parameters**

- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **flags** – PWM capture flags.
- **period** – [out] Pointer to the memory to store the captured PWM period width (in clock cycles). HW specific.
- **pulse** – [out] Pointer to the memory to store the captured PWM pulse width (in clock cycles). HW specific.
- **timeout** – Waiting period for the capture to complete.

**Return values**

- **0** – If successful.
- **-EBUSY** – PWM capture already in progress.
- **-EAGAIN** – Waiting period timed out.
- **-EIO** – IO error while capturing.
- **-ERANGE** – If result is too large.

```c
static inline int pwm_capture_usec(const struct device *dev, uint32_t channel, pwm_flags_t flags, uint64_t *period, uint64_t *pulse, k_timeout_t timeout)
```

Capture a single PWM period/pulse width in microseconds for a single PWM input. This API function wraps calls to `pwm_capture_cycles()` and `pwm_cycles_to_usec()` and passes the capture result to the caller. The function is blocking until either the PWM capture is completed or a timeout occurs.

**Note:** `CONFIG_PWM_CAPTURE` must be selected for this function to be available.
static inline int pwm_capture_nsec(const struct device *dev, uint32_t channel, pwm_flags_t flags, uint64_t *period, uint64_t *pulse, k_timeout_t timeout)

Capture a single PWM period/pulse width in nanoseconds for a single PWM input.
This API function wraps calls to pwm_capture_cycles() and pwm_cycles_to_nsec() and passes the capture result to the caller. The function is blocking until either the PWM capture is completed or a timeout occurs.

Note: CONFIG_PWM_CAPTURE must be selected for this function to be available.

Parameters
- channel – PWM channel.
- flags – PWM capture flags.
- period – [out] Pointer to the memory to store the captured PWM period width (in nsec).
- pulse – [out] Pointer to the memory to store the captured PWM pulse width (in nsec).
- timeout – Waiting period for the capture to complete.

Return values
- 0 – If successful.
- -EBUSY – PWM capture already in progress.
- -EAGAIN – Waiting period timed out.
- -EIO – IO error while capturing.
- -ERANGE – If result is too large.
- -errno – Other negative errno code on failure.

static inline bool pwm_is_ready_dt(const struct pwm_dt_spec *spec)
Validate that the PWM device is ready.

Parameters
- spec – PWM specification from devicetree

Return values
- true – If the PWM device is ready for use
- false – If the PWM device is not ready for use

struct pwm_dt_spec
#include <pwm.h> Container for PWM information specified in devicetree.
This type contains a pointer to a PWM device, channel number (controlled by the PWM device), the PWM signal period in nanoseconds and the flags applicable to the channel. Note that not all PWM drivers support flags. In such case, flags will be set to 0.

See also:
PWM_DT_SPEC_GET_BY_NAME
See also:
PWM_DT_SPEC_GET_BY_NAME_OR
See also:
PWM_DT_SPEC_GET_BY_IDX
See also:
PWM_DT_SPEC_GET_BY_IDX_OR
See also:
PWM_DT_SPEC_GET
See also:
PWM_DT_SPEC_GET_OR

Public Members

```c
const struct device *dev
```
PWM device instance.

```c
uint32_t channel
```
Channel number.

```c
uint32_t period
```
Period in nanoseconds.

```c
pwm_flags_t flags
```
Flags.

### 7.6.38 Real-Time Clock (RTC)

#### Overview

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An RTC is a low power device which tracks time using broken-down time. It should not be confused with low-power counters which sometimes share the same name, acronym, or both.

RTCs are usually optimized for low energy consumption and are usually kept running even when the system is in a low power state.

RTCs usually contain one or more alarms which can be configured to trigger at a given time. These alarms are commonly used to wake up the system from a low power state.
History of RTCs in Zephyr

RTCs have been supported before this API was created, using the Counter API. The unix timestamp was used to convert between broken-down time and the unix timestamp within the RTC drivers, which internally used the broken-down time representation.

The disadvantages of this approach were that hardware counters could not be set to a specific count, requiring all RTCs to use device specific APIs to set the time, converting from unix time to broken-down time, unnecessarily in some cases, and some common features missing, like input clock calibration and the update callback.

Configuration Options

Related configuration options:

- CONFIG_RTC
- CONFIG_RTC_ALARM
- CONFIG_RTC_UPDATE
- CONFIG_RTC_CALIBRATION

API Reference

*group rtc_interface*

RTC Interface.

**RTC Interface Alarm**

**int rtc_alarm_get_supported_fields**(*const struct device* dev, uint16_t id, uint16_t mask)*

API for getting the supported fields of the RTC alarm time.

**Note:** Bits in the mask param are defined here `RTC_ALARM_TIME_MASK`.

**Parameters**

- *dev* – Device instance
- *id* – Id of the alarm
- *mask* – Mask of fields in the alarm time which are supported

**Returns**

- 0 if successful
- -EINVAL if id is out of range or time is invalid

**Returns**

- -ENOTSUP if API is not supported by hardware

**Returns**

- errno code if failure
int rtc_alarm_set_time(const struct device *dev, uint16_t id, uint16_t mask, const struct rtc_time *timeptr)

API for setting RTC alarm time.

To enable an RTC alarm, one or more fields of the RTC alarm time must be enabled. The mask designates which fields of the RTC alarm time to enable. If the mask parameter is 0, the alarm will be disabled. The RTC alarm will trigger when all enabled fields of the alarm time match the RTC time.

**Note:** The timeptr param may be NULL if the mask param is 0

**Note:** Only the enabled fields in the timeptr param need to be configured

**Note:** Bits in the mask param are defined here `RTC_ALARM_TIME_MASK`

**Parameters**
- dev – Device instance
- id – Id of the alarm
- mask – Mask of fields in the alarm time to enable
- timeptr – The alarm time to set

**Returns**
- 0 if successful

**Returns**
- EINVAL if id is out of range or time is invalid

**Returns**
- ENOTSUP if API is not supported by hardware

**Returns**
- errno code if failure

int rtc_alarm_get_time(const struct device *dev, uint16_t id, uint16_t *mask, struct rtc_time *timeptr)

API for getting RTC alarm time.

**Note:** Bits in the mask param are defined here `RTC_ALARM_TIME_MASK`

**Parameters**
- dev – Device instance
- id – Id of the alarm
- mask – Destination for mask of fields which are enabled in the alarm time
- timeptr – Destination for the alarm time

**Returns**
- 0 if successful

**Returns**
- EINVAL if id is out of range
Returns
- ENOTSUP if API is not supported by hardware

Returns
-_errno code if failure

int rtc_alarm_is_pending(const struct device *dev, uint16_t id)
API for testing if RTC alarm is pending.
Test whether or not the alarm with id is pending. If the alarm is pending, the pending
status is cleared.

Parameters
  • dev – Device instance
  • id – Id of the alarm to test

Returns
  1 if alarm was pending

Returns
  0 if alarm was not pending

Returns
  -EINVAL if id is out of range

Returns
  -ENOTSUP if API is not supported by hardware

Returns
-_errno code if failure

int rtc_alarm_set_callback(const struct device *dev, uint16_t id, rtc_alarm_callback callback, void *user_data)
API for setting alarm callback.
Setting the alarm callback for an alarm, will enable the alarm callback. When the
callback for an alarm is enabled, the alarm triggered event will invoke the callback,
after which the alarm pending status will be cleared automatically. The alarm will
remain enabled until manually disabled using rtc_alarm_set_time().
To disable the alarm callback for an alarm, the callback and user_data parameters
must be set to NULL. When the alarm callback for an alarm is disabled, the alarm
triggered event will set the alarm status to “pending”. To check if the alarm status is
“pending”, use rtc_alarm_is_pending().

Parameters
  • dev – Device instance
  • id – Id of the alarm for which the callback shall be set
  • callback – Callback called when alarm occurs
  • user_data – Optional user data passed to callback

Returns
  0 if successful

Returns
  -EINVAL if id is out of range

Returns
  -ENOTSUP if API is not supported by hardware

Returns
-_errno code if failure
RTC Interface Update

int rtc_update_set_callback(const struct device *dev, rtc_update_callback callback, void *user_data)

API for setting update callback.

Setting the update callback will enable the update callback. The update callback will be invoked every time the RTC clock is updated by 1 second. It can be used to synchronize the RTC clock with other clock sources.

To disable the update callback for the RTC clock, the callback and user_data parameters must be set to NULL.

Parameters

- dev – Device instance
- callback – Callback called when update occurs
- user_data – Optional user data passed to callback

Returns

- 0 if successful
- -ENOTSUP if API is not supported by hardware
- -errno code if failure

RTC Interface Calibration

int rtc_set_calibration(const struct device *dev, int32_t calibration)

API for setting RTC calibration.

Calibration is applied to the RTC clock input. A positive calibration value will increase the frequency of the RTC clock, a negative value will decrease the frequency of the RTC clock.

Parameters

- dev – Device instance
- calibration – Calibration to set in parts per billion

Returns

- 0 if successful
- -EINVAL if calibration is out of range
- -ENOTSUP if API is not supported by hardware
- -errno code if failure

int rtc_get_calibration(const struct device *dev, int32_t *calibration)

API for getting RTC calibration.

Parameters

- dev – Device instance
- calibration – Destination for calibration in parts per billion
Returns
0 if successful

Returns
-ENOTSUP if API is not supported by hardware

Returns
-errno code if failure

RTC Interface Helpers

static inline struct tm *rtc_time_to_tm(struct rtc_time *timeptr)
   Convenience function for safely casting a rtc_time pointer to a tm pointer.

RTC Alarm Time Mask

Mask for alarm time fields to enable when setting alarm time

RTC_ALARM_TIME_MASK_SECOND
RTC_ALARM_TIME_MASK_MINUTE
RTC_ALARM_TIME_MASK_HOUR
RTC_ALARM_TIME_MASK_MONTHDAY
RTC_ALARM_TIME_MASK_MONTH
RTC_ALARM_TIME_MASK_YEAR
RTC_ALARM_TIME_MASK_WEEKDAY
RTC_ALARM_TIME_MASK_YEARDAY
RTC_ALARM_TIME_MASK_NSEC

Typedefs

typedef void (*rtc_update_callback)(const struct device *dev, void *user_data)
RTC update event callback.

Param dev
   Device instance invoking the handler

Param user_data
   Optional user data provided when update irq callback is set
typedef void (*rtc_alarm_callback)(const struct device *dev, uint16_t id, void *user_data)
RTC alarm triggered callback.

**Param dev**
Device instance invoking the handler

**Param id**
Alarm id

**Param user_data**
Optional user data passed with the alarm configuration

**Functions**

```c
int rtc_set_time(const struct device *dev, const struct rtc_time *timeptr)
```
API for setting RTC time.

**Parameters**
- `dev` – Device instance
- `timeptr` – The time to set

**Returns**
- 0 if successful
- -EINVAL if RTC time is invalid or exceeds hardware capabilities
- -errno code if failure

```c
int rtc_get_time(const struct device *dev, struct rtc_time *timeptr)
```
API for getting RTC time.

**Parameters**
- `dev` – Device instance
- `timeptr` – Destination for the time

**Returns**
- 0 if successful
- -ENODATA if RTC time has not been set
- -errno code if failure

```c
struct rtc_time
#include <rtc.h> Structure for storing date and time values with sub-second precision.
The structure is 1-1 mapped to the struct tm for the members tm_sec to tm_isdst making it compatible with the standard time library.
```

**Note:** Use `rtc_time_to_tm()` to safely cast from a `rtc_time` pointer to a tm pointer.
Public Members

```c
int tm_sec
    Seconds [0, 59].

int tm_min
    Minutes [0, 59].

int tm_hour
    Hours [0, 23].

int tm_mday
    Day of the month [1, 31].

int tm_mon
    Month [0, 11].

int tm_year
    Year - 1900.

int tm_wday
    Day of the week [0, 6] (Sunday = 0) (Unknown = -1)

int tm_yday
    Day of the year [0, 365] (Unknown = -1)

int tm_isdst
    Daylight saving time flag [-1] (Unknown = -1)

int tm_nsec
    Nanoseconds [0, 999999999] (Unknown = 0)
```

RTC device driver test suite

The test suite validates the behavior of the RTC device driver. It is designed to be portable between boards. It uses the device tree alias `rtc` to designate the RTC device to test.

This test suite tests the following:

- Setting and getting the time.
- RTC Time incrementing correctly.
- Alarms if supported by hardware, with and without callback enabled
- Calibration if supported by hardware.

The calibration test tests a range of values which are printed to the console to be manually compared. The user must review the set and gotten values to ensure they are valid.

By default, only the mandatory setting and getting of time is enabled for testing. To test the optional alarms, update event callback and clock calibration, these must be enabled by selecting `CONFIG_RTC_ALARM`, `CONFIG_RTC_UPDATE` and `CONFIG_RTC_CALIBRATION`.

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The following examples build the test suite for the native_sim board. To build the test suite for a different board, replace the native_sim board with your board.

To build the test application with the default configuration, testing only the mandatory features, the following command can be used for reference:

```
# From the root of the zephyr repository
west build -b native_sim tests/drivers/rtc/rtc_api
```

To build the test with additional RTC features enabled, use menuconfig to enable the additional features by updating the configuration. The following command can be used for reference:

```
# From the root of the zephyr repository
west build -b native_sim tests/drivers/rtc/rtc_api
west build -t menuconfig
```

Then build the test application using the following command:

```
# From the root of the zephyr repository
west build -b native_sim tests/drivers/rtc/rtc_api
```

To run the test suite, flash and run the application on your board, the output will be printed to the console.

**Note:** The tests take up to 30 seconds each if they are testing real hardware.

**RTC emulated device**

The emulated RTC device fully implements the RTC API, and will behave like a real RTC device, with the following limitations:

- RTC time is not persistent across application initialization.
- RTC alarms are not persistent across application initialization.
- RTC time will drift over time.

Every time an application is initialized, the RTC's time and alarms are reset. Reading the time using `rtc_get_time()` will return -ENODATA, until the time is set using `rtc_set_time()`. The RTC will then behave as a real RTC, until the application is reset.

The emulated RTC device driver is built for the compatible zephyr,rtc-emul and will be included if CONFIG_RTC is selected.

**7.6.39 Regulators**

This subsystem provides control of voltage and current regulators. A common example is a GPIO that controls a transistor that supplies current to a device that is not always needed. Another example is a PMIC, typically a much more complex device.

The *-supply devicetree properties are used to identify the regulator(s) that a devicetree node directly depends on. Within the driver for the node the regulator API is used to issue requests for power when the device is to be active, and release the power request when the device shuts down.

The simplest case where a regulator is needed is one where there is only one client. For those situations the cost of using the regulator device infrastructure is not justified, and *-gpios devicetree properties should be used. There is no device interface to these regulators as they are entirely controlled within the driver for the corresponding node, e.g. a sensor.
API Reference

*group regulator_interface*

Regulator Interface.

**Regulator error flags.**

- **REGULATOR_ERROR_OVER_VOLTAGE**
  Voltage is too high.

- **REGULATOR_ERROR_OVER_CURRENT**
  Current is too high.

- **REGULATOR_ERROR_OVER_TEMP**
  Temperature is too high.

**Typedefs**

- **typedef uint8_t regulator_dvs_state_t**
  Opaque type to store regulator DVS states.

- **typedef uint8_t regulator_mode_t**
  Opaque type to store regulator modes.

- **typedef uint8_t regulator_error_flags_t**
  Opaque bit map for regulator error flags (see *REGULATOR_ERRORS*)

**Functions**

- **int regulator_enable(const struct device *dev)**
  Enable a regulator.

  Reference-counted request that a regulator be turned on. A regulator is considered “on” when it has reached a stable/usable state. Regulators that are always on, or configured in devicetree with *regulator-always-on* will always stay enabled, and so this function will always succeed.

  **Parameters**
  - *dev* – Regulator device instance

  **Return values**
  - 0 – If regulator has been successfully enabled.
  - -errno – Negative errno in case of failure.
  - -ENOTSUP – If regulator enablement can not be controlled.
bool regulator_is_enabled(const struct device *dev)

Check if a regulator is enabled.

**Parameters**

- dev – Regulator device instance.

**Return values**

- true – If regulator is enabled.
- false – If regulator is disabled.

int regulator_disable(const struct device *dev)

Disable a regulator.

Release a regulator after a previous regulator_enable() completed successfully. Regulators that are always on, or configured in devicetree with regulator-always-on will always stay enabled, and so this function will always succeed.

This must be invoked at most once for each successful regulator_enable().

**Parameters**

- dev – Regulator device instance.

**Return values**

- 0 – If regulator has been successfully disabled.
- -errno – Negative errno in case of failure.
- -ENOTSUP – If regulator disablement can not be controlled.

static inline unsigned int regulator_count_voltages(const struct device *dev)

Obtain the number of supported voltage levels.

Each voltage level supported by a regulator gets an index, starting from zero. The total number of supported voltage levels can be used together with regulator_list_voltage() to list all supported voltage levels.

**Parameters**

- dev – Regulator device instance.

**Returns**

Number of supported voltages.

static inline int regulator_list_voltage(const struct device *dev, unsigned int idx, int32_t *volt_uv)

Obtain the value of a voltage given an index.

Each voltage level supported by a regulator gets an index, starting from zero. Together with regulator_count_voltages(), this function can be used to iterate over all supported voltages.

**Parameters**

- dev – Regulator device instance.
- idx – Voltage index.
- volt_uv – [out] Where voltage for the given index will be stored, in microvolts.

**Return values**

- 0 – If index corresponds to a supported voltage.
- -EINVAL – If index does not correspond to a supported voltage.

7.6. Peripherals
bool regulator_is_supported_voltage(const struct device *dev, int32_t min_uv, int32_t max_uv)

Check if a voltage within a window is supported.

Parameters

- `dev` – Regulator device instance.
- `min_uv` – Minimum voltage in microvolts.
- `max_uv` – maximum voltage in microvolts.

Return values

- `true` – If voltage is supported.
- `false` – If voltage is not supported.

int regulator_set_voltage(const struct device *dev, int32_t min_uv, int32_t max_uv)

Set the output voltage.

The output voltage will be configured to the closest supported output voltage. `regulator_get_voltage()` can be used to obtain the actual configured voltage. The voltage will be applied to the active or selected mode. Output voltage may be limited using `regulator-min-microvolt` and/or `regulator-max-microvolt` in devicetree.

Parameters

- `dev` – Regulator device instance.
- `min_uv` – Minimum acceptable voltage in microvolts.
- `max_uv` – Maximum acceptable voltage in microvolts.

Return values

- `0` – If successful.
- `-EINVAL` – If the given voltage window is not valid.
- `-ENOSYS` – If function is not implemented.
- `-errno` – In case of any other error.

static inline int regulator_get_voltage(const struct device *dev, int32_t *volt_uv)

Obtain output voltage.

Parameters

- `dev` – Regulator device instance.
- `volt_uv` – [out] Where configured output voltage will be stored.

Return values

- `0` – If successful
- `-ENOSYS` – If function is not implemented.
- `-errno` – In case of any other error.

static inline unsigned int regulator_count_current_limits(const struct device *dev)

Obtain the number of supported current limit levels.

Each current limit level supported by a regulator gets an index, starting from zero. The total number of supported current limit levels can be used together with `regulator_list_current_limit()` to list all supported current limit levels.

Parameters

- `dev` – Regulator device instance.
Returns
Number of supported current limits.

static inline int regulator_list_current_limit(const struct device *dev, unsigned int idx, int32_t *current_ua)

Obtain the value of a current limit given an index.

Each current limit level supported by a regulator gets an index, starting from zero. Together with regulator_count_current_limits(), this function can be used to iterate over all supported current limits.

Parameters
• dev – Regulator device instance.
• idx – Current index.
• current_ua – [out] Where current for the given index will be stored, in microamps.

Return values
• 0 – If index corresponds to a supported current limit.
• -EINVAL – If index does not correspond to a supported current limit.

int regulator_set_current_limit(const struct device *dev, int32_t min_ua, int32_t max_ua)

Set output current limit.

The output current limit will be configured to the closest supported output current limit. regulator_get_current_limit() can be used to obtain the actual configured current limit. Current may be limited using current-min-microamp and/or current-max-microamp in Devicetree.

Parameters
• dev – Regulator device instance.
• min_ua – Minimum acceptable current limit in microamps.
• max_ua – Maximum acceptable current limit in microamps.

Return values
• 0 – If successful.
• -EINVAL – If the given current limit window is not valid.
• -ENOSYS – If function is not implemented.
• -errno – In case of any other error.

static inline int regulator_get_current_limit(const struct device *dev, int32_t *curr_ua)

Get output current limit.

Parameters
• dev – Regulator device instance.
• curr_ua – [out] Where output current limit will be stored.

Return values
• 0 – If successful.
• -ENOSYS – If function is not implemented.
• -errno – In case of any other error.
int regulator_set_mode(const struct device *dev, regulator_mode_t mode)
    Set mode.

Regulators can support multiple modes in order to permit different voltage configuration or better power savings. This API will apply a mode for the regulator. Allowed modes may be limited using regulator-allowed-modes devicetree property.

Parameters
• dev – Regulator device instance.
• mode – Mode to select for this regulator.

Return values
• 0 – If successful.
• -ENOTSUP – If mode is not supported.
• -ENOSYS – If function is not implemented.
• -errno – In case of any other error.

static inline int regulator_get_mode(const struct device *dev, regulator_mode_t *mode)
Get mode.

Parameters
• dev – Regulator device instance.
• mode – [out] Where mode will be stored.

Return values
• 0 – If successful.
• -ENOSYS – If function is not implemented.
• -errno – In case of any other error.

static inline int regulator_set_active_discharge(const struct device *dev, bool active_discharge)
Set active discharge setting.

Parameters
• dev – Regulator device instance.
• active_discharge – Active discharge enable or disable.

Return values
• 0 – If successful.
• -ENOSYS – If function is not implemented.
• -errno – In case of any other error.

static inline int regulator_get_active_discharge(const struct device *dev, bool *active_discharge)
Get active discharge setting.

Parameters
• dev – Regulator device instance.
• active_discharge – [out] Where active discharge will be stored.

Return values
• 0 – If successful.
• -ENOSYS – If function is not implemented.
Parameters

- dev – Regulator device instance.
- flags – [out] Where error flags will be stored.

Return values

- 0 – If successful.
- -ENOSYS – If function is not implemented.
- -errno – In case of any other error.

### 7.6.40 Reset Controller

**Overview**

Reset controllers are units that control the reset signals to multiple peripherals. The reset controller API allows peripheral drivers to request control over their reset input signals, including the ability to assert, deassert and toggle those signals. Also, the reset status of the reset input signal can be checked.

Mainly, the line_assert and line_deassert API functions are optional because in most cases we want to toggle the reset signals.

**Configuration Options**

Related configuration options:

- CONFIG_RESET

**API Reference**

group reset_controller_interface

Reset Controller Interface.

**Defines**

RESET_DT_SPEC_GET_BY_IDX(node_id, idx)

Static initializer for a reset_dt_spec.

This returns a static initializer for a reset_dt_spec structure given a devicetree node identifier, a property specifying a Reset Controller and an index.

Example devicetree fragment:

```bash
n: node {
    resets = &reset 10;
}
```

Example usage:
const struct reset_dt_spec spec = RESET_DT_SPEC_GET_BY_IDX(DT_NODELABEL(n), 0);
// Initializes 'spec' to:
// {
//   .dev = DEVICE_DT_GET(DT_NODELABEL(reset)),
//   .id = 10
// }

The `reset` field must still be checked for readiness, e.g. using `device_is_ready()`. It is an error to use this macro unless the node exists, has the given property, and that property specifies a reset controller reset line id as shown above.

Parameters

- `node_id` – devicetree node identifier
- `idx` – logical index into “resets”

Returns

static initializer for a struct `reset_dt_spec` for the property

RESET_DT_SPEC_GET(node_id)
Equivalent to `RESET_DT_SPEC_GET_BY_IDX(node_id, 0)`.

See also:

`RESET_DT_SPEC_GET_BY_IDX()`

Parameters

- `node_id` – devicetree node identifier

Returns

static initializer for a struct `reset_dt_spec` for the property

RESET_DT_SPEC_INST_GET_BY_IDX(inst, idx)
Static initializer for a `reset_dt_spec` from a DT_DRV_COMPAT instance's Reset Controller property at an index.

See also:

`RESET_DT_SPEC_GET_BY_IDX()`

Parameters

- `inst` – DT_DRV_COMPAT instance number
- `idx` – logical index into “resets”

Returns

static initializer for a struct `reset_dt_spec` for the property

RESET_DT_SPEC_INST_GET(inst)
Equivalent to `RESET_DT_SPEC_INST_GET_BY_IDX(inst, 0)`.

See also:

`RESET_DT_SPEC_INST_GET_BY_IDX()`

Parameters

- `inst` – DT_DRV_COMPAT instance number
Returns
static initializer for a struct reset_dt_spec for the property

Functions

int reset_status(const struct device *dev, uint32_t id, uint8_t *status)
Get the reset status.
This function returns the reset status of the device.

Parameters
• dev – Reset controller device.
• id – Reset line.
• status – Where to write the reset status.

Return values
• 0 – On success.
• -ENOSYS – If the functionality is not implemented by the driver.
• -errno – Other negative errno in case of failure.

static inline int reset_status_dt(const struct reset_dt_spec *spec, uint8_t *status)
Get the reset status from a reset_dt_spec.
This is equivalent to:
reset_status(spec->dev, spec->id, status);

Parameters
• spec – Reset controller specification from devicetree
• status – Where to write the reset status.

Returns
a value from reset_status()

int reset_line_assert(const struct device *dev, uint32_t id)
Put the device in reset state.
This function sets/clears the reset bits of the device, depending on the logic level
(active-high/active-low).

Parameters
• dev – Reset controller device.
• id – Reset line.

Return values
• 0 – On success.
• -ENOSYS – If the functionality is not implemented by the driver.
• -errno – Other negative errno in case of failure.

static inline int reset_line_assert_dt(const struct reset_dt_spec *spec)
Assert the reset state from a reset_dt_spec.
This is equivalent to:
reset_line_assert(spec->dev, spec->id);
Parameters
- `spec` – Reset controller specification from devicetree

Returns
a value from `reset_line_assert()`

```c
int reset_line_deassert(const struct device *dev, uint32_t id)
```

Take out the device from reset state.
This function sets/clears the reset bits of the device, depending on the logic level (active-low/active-high).

Parameters
- `dev` – Reset controller device.
- `id` – Reset line.

Return values
- `0` – On success.
- `-ENOSYS` – If the functionality is not implemented by the driver.
- `-errno` – Other negative errno in case of failure.

```c
static inline int reset_line_deassert_dt(const struct reset_dt_spec *spec)
```

Deassert the reset state from a `reset_dt_spec`.
This is equivalent to:

```c
reset_line_deassert(spec->dev, spec->id)
```

Parameters
- `spec` – Reset controller specification from devicetree

Returns
a value from `reset_line_deassert()

```c
int reset_line_toggle(const struct device *dev, uint32_t id)
```

Reset the device.
This function performs reset for a device (assert + deassert).

Parameters
- `dev` – Reset controller device.
- `id` – Reset line.

Return values
- `0` – On success.
- `-ENOSYS` – If the functionality is not implemented by the driver.
- `-errno` – Other negative errno in case of failure.

```c
static inline int reset_line_toggle_dt(const struct reset_dt_spec *spec)
```

Reset the device from a `reset_dt_spec`.
This is equivalent to:

```c
reset_line_toggle(spec->dev, spec->id)
```
• spec – Reset controller specification from devicetree

**Returns**

a value from `reset_line_toggle()`

```c
struct reset_dt_spec
    #include <reset.h> Reset controller device configuration.

Public Members

const struct device *dev
    Reset controller device.

uint32_t id
    Reset line.
```

### 7.6.41 Retained Memory

**Overview**

The retained memory driver API provides a way of reading from/writing to memory areas whereby the contents of the memory is retained whilst the device is powered (data may be lost in low power modes).

**Configuration Options**

Related configuration options:

- `CONFIG_RETAINED_MEM`
- `CONFIG_RETAINED_MEM_INIT_PRIORITY`
- `CONFIG_RETAINED_MEM_MUTEX_FORCE_DISABLE`

**Mutex protection**

Mutex protection of retained memory drivers is enabled by default when applications are compiled with multithreading support. This means that different threads can safely call the retained memory functions without clashing with other concurrent thread function usage, but means that retained memory functions cannot be used from ISRs. It is possible to disable mutex protection globally on all retained memory drivers by enabling `CONFIG_RETAINED_MEM_MUTEX_FORCE_DISABLE` - users are then responsible for ensuring that the function calls do not conflict with each other.

**API Reference**

```c
group retained_mem_interface
    Retained memory driver interface.
```
**Typedefs**

```c
typedef ssize_t (*retained_mem_size_api)(const struct device *dev)
    Callback API to get size of retained memory area.
    See retained_mem_size() for argument description.

typedef int (*retained_mem_read_api)(const struct device *dev, off_t offset, uint8_t *buffer, size_t size)
    Callback API to read from retained memory area.
    See retained_mem_read() for argument description.

typedef int (*retained_mem_write_api)(const struct device *dev, off_t offset, const uint8_t *buffer, size_t size)
    Callback API to write to retained memory area.
    See retained_mem_write() for argument description.

typedef int (*retained_mem_clear_api)(const struct device *dev)
    Callback API to clear retained memory area (reset all data to 0x00).
    See retained_mem_clear() for argument description.
```

**Functions**

```c
ssize_t retained_mem_size(const struct device *dev)
    Returns the size of the retained memory area.

Parameters
- dev – Retained memory device to use.

Return values
- Positive – value indicating size in bytes on success, else negative errno code.

int retained_mem_read(const struct device *dev, off_t offset, uint8_t *buffer, size_t size)
    Reads data from the Retained memory area.

Parameters
- dev – Retained memory device to use.
- offset – Offset to read data from.
- buffer – Buffer to store read data in.
- size – Size of data to read.

Return values
- 0 – on success else negative errno code.

int retained_mem_write(const struct device *dev, off_t offset, const uint8_t *buffer, size_t size)
    Writes data to the Retained memory area - underlying data does not need to be cleared prior to writing.

Parameters
- dev – Retained memory device to use.
- offset – Offset to write data to.
```
• **buffer** – Data to write.
• **size** – Size of data to be written.

**Return values**

0 – on success else negative errno code.

```c
int retained_mem_clear(const struct device *dev)
```

Clears data in the retained memory area by setting it to 0x00.

**Parameters**

• **dev** – Retained memory device to use.

**Return values**

0 – on success else negative errno code.

```c
struct retained_mem_driver_api
```

```
#include <retained_mem.h> Retained memory driver API API which can be used by a device to store data in a retained memory area.
```

Retained memory is memory that is retained while the device is powered but is lost when power to the device is lost (note that low power modes in some devices may clear the data also). This may be in a non-initialised RAM region, or in specific registers, but is not reset when a different application begins execution or the device is rebooted (without power loss). It must support byte-level reading and writing without a need to erase data before writing.

Note that drivers must implement all functions, none of the functions are optional.

### 7.6.42 Secure Digital High Capacity (SDHC)

The SDHC api offers a generic interface for interacting with an SD host controller device. It is used by the SD subsystem, and is not intended to be directly used by the application.

**Basic Operation**

**SD Host Controller** An SD host controller is a device capable of sending SD commands to an attached SD card. These commands can be sent using the native SD protocol, or over SPI. Some SD host controllers are also capable of communicating with MMC devices. The SDHC api is designed to provide a generic way to send commands to and interact with attached SD devices.

**Requests** The core of the SDHC api is the `sdhc_request()` api. Requests contain a `sdhc_command` command structure, and an optional `sdhc_data` data structure. The caller may check the return code, or the `response` field of the SD command structure to determine if the SDHC request succeeded. The data structure allows the caller to specify a number of blocks to transfer, and a buffer location to read or write them from. Whether the provided buffer is used for sending or reading data depends on the command opcode provided.

**Host Controller I/O** The `sdhc_set_io()` api allows the user to change I/O settings of the SD host controller, such as clock frequency, I/O voltage, and card power. Not all controllers will support applying all I/O settings. For example, SPI mode controllers typically cannot toggle power to the SD card.

Related configuration options:

- **CONFIG_SDHC**
API Reference

**group sdhc_interface**
SDHC interface.

**SD command timeouts**

SDHC_TIMEOUT_FOREVER

**Defines**

SDHC_NATIVE_RESPONSE_MASK

SDHC_SPI_RESPONSE_TYPE_MASK

**Typedefs**

typedef void (*sdhc_interrupt_cb_t)(const struct device *dev, int reason, const void *user_data)
SDHC card interrupt callback prototype.
Function prototype for SDHC card interrupt callback.

- **Param dev**
  SDHC device that produced interrupt

- **Param reason**
  one of sdhc_interrupt_source values.

- **Param user_data**
  User data, set via sdhc_enable_interrupt

**Enums**

enum sdhc_bus_mode
SD bus mode.
Most controllers will use push/pull, including spi, but SDHC controllers that implement SD host specification can support open drain mode

- **Values:**

  - enumerator SDHC_BUSMODE_OPENDRAIN = 1
  
  - enumerator SDHC_BUSMODE_PUSHPULL = 2
enum sdhc_power

SD host controller power.

Many host controllers can control power to attached SD cards. This enum allows applications to request the host controller power off the SD card.

Values:

enumerator SDHC_POWER_OFF = 1
enumerator SDHC_POWER_ON = 2

enum sdhc_bus_width

SD host controller bus width.

Only relevant in SD mode, SPI does not support bus width. UHS cards will use 4 bit data bus, all cards start in 1 bit mode

Values:

enumerator SDHC_BUS_WIDTH1BIT = 1U
enumerator SDHC_BUS_WIDTH4BIT = 4U
enumerator SDHC_BUS_WIDTH8BIT = 8U

enum sdhc_timing_mode

SD host controller timing mode.

Used by SD host controller to determine the timing of the cards attached to the bus. Cards start with legacy timing, but UHS-II cards can go up to SDR104.

Values:

enumerator SDHC_TIMING_LEGACY = 1U
    Legacy 3.3V Mode.
enumerator SDHC_TIMING_HS = 2U
    Legacy High speed mode (3.3V)
enumerator SDHC_TIMING_SDR12 = 3U
    Identification mode & SDR12.
enumerator SDHC_TIMING_SDR25 = 4U
    High speed mode & SDR25.
enumerator SDHC_TIMING_SDR50 = 5U
    SDR49 mode.
enumerator SDHC_TIMING_SDR104 = 6U
    SDR104 mode.
enumerator SDHC_TIMING_DDR50 = 7U
  DDR50 mode.

enumerator SDHC_TIMING_DDR52 = 8U
  DDR52 mode.

enumerator SDHC_TIMING_HS200 = 9U
  HS200 mode.

enumerator SDHC_TIMING_HS400 = 10U
  HS400 mode.

enum sd_voltage
  SD voltage.
  UHS cards can run with 1.8V signalling for improved power consumption. Legacy cards may support 3.0V signalling, and all cards start at 3.3V. Only relevant for SD controllers, not SPI ones.
  
  Values:

enumerator SD_VOL_3_3_V = 1U
  card operation voltage around 3.3v

enumerator SD_VOL_3_0_V = 2U
  card operation voltage around 3.0v

enumerator SD_VOL_1_8_V = 3U
  card operation voltage around 1.8v

enumerator SD_VOL_1_2_V = 4U
  card operation voltage around 1.2v

enum sdhc_interrupt_source
  SD host controller interrupt sources.
  Interrupt sources for SD host controller.
  Values:

enumerator SDHC_INT_SDIO = BIT(0)
  Card interrupt, used by SDIO cards.

enumerator SDHC_INT_INSERTED = BIT(1)
  Card was inserted into slot.

enumerator SDHC_INT_REMOVED = BIT(2)
  Card was removed from slot.

Functions
int sdhc_hw_reset(const struct device *dev)
reset SDHC controller state

Used when the SDHC has encountered an error. Resetting the SDHC controller should
clear all errors on the SDHC, but does not necessarily reset I/O settings to boot (this can
be done with sdhc_set_io)

Parameters
• dev – SD host controller device

Return values
• 0 – reset succeeded
• -ETIMEDOUT – controller reset timed out
• -EIO – reset failed

int sdhc_request(const struct device *dev, struct sdhc_command *cmd, struct sdhc_data *
data)
Send command to SDHC.
Sends a command to the SD host controller, which will send this command to attached
SD cards.

Parameters
• dev – SDHC device
• cmd – SDHC command
• data – SDHC data. Leave NULL to send SD command without data.

Return values
• 0 – command was sent successfully
• -ETIMEDOUT – command timed out while sending
• -ENOTSUP – host controller does not support command
• -EIO – I/O error

int sdhc_set_io(const struct device *dev, struct sdhc_io *io)
set I/O properties of SDHC

I/O properties should be reconfigured when the card has been sent a command to
change its own SD settings. This function can also be used to toggle power to the SD
card.

Parameters
• dev – SDHC device
• io – I/O properties

Returns
0 I/O was configured correctly

Returns
-ENOTSUP controller does not support these I/O settings

Returns
-EIO controller could not configure I/O settings

int sdhc_card_present(const struct device *dev)
check for SDHC card presence

Checks if card is present on the SD bus. Note that if a controller requires cards be
powered up to detect presence, it should do so in this function.
Parameters

- `dev` – SDHC device

Return values

- 1 – card is present
- 0 – card is not present
- -EIO – I/O error

`int sdhc_execute_tuning(const struct device *dev)`

run SDHC tuning

SD cards require signal tuning for UHS modes SDR104 and SDR50. This function allows an application to request the SD host controller to tune the card.

Parameters

- `dev` – SDHC device

Return values

- 0 – tuning succeeded, card is ready for commands
- -ETIMEDOUT – tuning failed after timeout
- -ENOTSUP – controller does not support tuning
- -EIO – I/O error while tuning

`int sdhc_card_busy(const struct device *dev)`

check if SD card is busy

This check should generally be implemented as checking the line level of the DAT[0:3] lines of the SD bus. No SD commands need to be sent, the controller simply needs to report the status of the SD bus.

Parameters

- `dev` – SDHC device

Return values

- 0 – card is not busy
- 1 – card is busy
- -EIO – I/O error

`int sdhc_get_host_props(const struct device *dev, struct sdhc_host_props *props)`

Get SD host controller properties.

Gets host properties from the host controller. Host controller should initialize all values in the `sdhc_host_props` structure provided.

Parameters

- `dev` – SDHC device
- `props` – property structure to be filled by sdhc driver

Return values

- 0 – function succeeded.
- -ENOTSUP – host controller does not support this call
int sdhc_enable_interrupt(const struct device *dev, sdhc_interrupt_cb_t callback, int sources, void *user_data)

Enable SDHC interrupt sources.

Enables SDHC interrupt sources. Each subsequent call of this function should replace the previous callback set, and leave only the interrupts specified in the “sources” argument enabled.

**Parameters**
- `dev` – SDHC device
- `callback` – Callback called when interrupt occurs
- `sources` – bitmask of `sdhc_interrupt_source` values indicating which interrupts should produce a callback
- `user_data` – parameter that will be passed to callback function

**Return values**
- `0` – interrupts were enabled, and callback was installed
- `-ENOTSUP` – controller does not support this function
- `-EIO` – I/O error

int sdhc_disable_interrupt(const struct device *dev, int sources)

Disable SDHC interrupt sources.

Disables SDHC interrupt sources. If multiple sources are enabled, only the ones specified in “sources” will be masked.

**Parameters**
- `dev` – SDHC device
- `sources` – bitmask of `sdhc_interrupt_source` values indicating which interrupts should be disabled.

**Return values**
- `0` – interrupts were disabled
- `-ENOTSUP` – controller does not support this function
- `-EIO` – I/O error

struct sdhc_command

`#include <sdhc.h>` SD host controller command structure.

This command structure is used to send command requests to an SD host controller, which will be sent to SD devices.

**Public Members**

`uint32_t opcode`

SD Host specification CMD index.

`uint32_t arg`

SD host specification argument.

uint32_t response[4]
SD card response field.

uint32_t response_type
Expected SD response type.

unsigned int retries
Max number of retries.

int timeout_ms
Command timeout in milliseconds.

struct sdhc_data
#include <sdhc.h> SD host controller data structure.
This command structure is used to send data transfer requests to an SD host controller, which will be sent to SD devices.

**Public Members**

unsigned int block_addr
Block to start read from.

unsigned int block_size
Block size.

unsigned int blocks
Number of blocks.

unsigned int bytes_xfered
populated with number of bytes sent by SDHC

void *data
Data to transfer or receive.

int timeout_ms
data timeout in milliseconds

struct sdhc_host_caps
#include <sdhc.h> SD host controller capabilities.
SD host controller capability flags. These flags should be set by the SDHC driver, using the sdhc_get_host_props api.

**Public Members**

unsigned int timeout_clk_freq
Timeout clock frequency.
unsigned int timeout_clk_unit
    Timeout clock unit.

unsigned int sd_base_clk
    SD base clock frequency.

unsigned int max_blk_len
    Max block length.

unsigned int bus_8_bit_support
    8-bit Support for embedded device

unsigned int bus_4_bit_support
    4 bit bus support

unsigned int adma_2_support
    ADMA2 support.

unsigned int high_spd_support
    High speed support.

unsigned int sdma_support
    SDMA support.

unsigned int suspend_res_support
    Suspend/Resume support.

unsigned int vol_330_support
    Voltage support 3.3V.

unsigned int vol_300_support
    Voltage support 3.0V.

unsigned int vol_180_support
    Voltage support 1.8V.

unsigned int address_64_bit_support_v4
    64-bit system address support for V4

unsigned int address_64_bit_support_v3
    64-bit system address support for V3

unsigned int sdio_async_interrupt_support
    Asynchronous interrupt support.

unsigned int slot_type
    Slot type.

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unsigned int sdr50_support
    SDR50 support.

unsigned int sdr104_support
    SDR104 support.

unsigned int ddr50_support
    DDR50 support.

unsigned int uhs_2_support
    UHS-II support.

unsigned int drv_type_a_support
    Driver type A support.

unsigned int drv_type_c_support
    Driver type C support.

unsigned int drv_type_d_support
    Driver type D support.

unsigned int retune_timer_count
    Timer count for re-tuning.

unsigned int sdr50_needs_tuning
    Use tuning for SDR50.

unsigned int retuning_mode
    Re-tuning mode.

unsigned int clk_multiplier
    Clock multiplier.

unsigned int adma3_support
    ADMA3 support.

unsigned int vdd2_180_support
    1.8V VDD2 support

unsigned int hs200_support
    HS200 support.

unsigned int hs400_support
    HS400 support.

struct sdhc_io
    #include <sdhc.h> SD host controller I/O control structure.

    Controls I/O settings for the SDHC. Note that only a subset of these settings apply to host
    controllers in SPI mode. Populate this struct, then call sdhc_set_io to apply I/O settings
Public Members

typedef enum sdhc_clock_speed {clock} Clock rate.

typedef enum sdhc_bus_mode {bus_mode} command output mode

typedef enum sdhc_power {power_mode} SD power supply mode.

typedef enum sdhc_bus_width {bus_width} SD bus width.

typedef enum sdhc_timing_mode {timing} SD bus timing.

typedef enum sd_driver_type {driver_type} SD driver type.

typedef enum sd_voltage {signal_voltage} IO signalling voltage (usually 1.8 or 3.3V)

struct sdhc_host_props

#include <sdhc.h> SD host controller properties.

Populated by the host controller using sdhc_get_host_props api.

Public Members

unsigned int f_max
Max bus frequency.

unsigned int f_min
Min bus frequency.

unsigned int power_delay
Delay to allow SD to power up or down (in ms)

struct sdhc_host_caps {host_caps}
Host capability bitfield.

uint32_t max_current_330
Max current (in mA) at 3.3V.

uint32_t max_current_300
Max current (in mA) at 3.0V.
7.6.43 Sensors

The sensor subsystem exposes an API to uniformly access sensor devices. Common operations are: reading data and executing code when specific conditions are met.

Basic Operation

Channels  Fundamentally, a channel is a quantity that a sensor device can measure.

Sensors can have multiple channels, either to represent different axes of the same physical property (e.g. acceleration); or because they can measure different properties altogether (ambient temperature, pressure and humidity). Complex sensors cover both cases, so a single device can expose three acceleration channels and a temperature one.

It is imperative that all sensors that support a given channel express results in the same unit of measurement. Consult the API Reference for all supported channels, along with their description and units of measurement:

Values  Sensor stable APIs return results as sensor_value. This representation avoids use of floating point values as they may not be supported on certain setups.

A newer experimental (may change) API that can interpret raw sensor data is available in parallel. This new API exposes raw encoded sensor data to the application and provides a separate decoder to convert the data to a Q31 format which is compatible with the Zephyr Digital Signal Processing (DSP). The values represented are in the range of (-1.0, 1.0) and require a shift operation in order to scale them to their SI unit values. See Async Read for more information.

Fetching Values  Getting a reading from a sensor requires two operations. First, an application instructs the driver to fetch a sample of all its channels. Then, individual channels may be read. In the case of channels with multiple axes, they can be read in a single operation by supplying the corresponding _XYZ channel type and a buffer of 3 sensor_value objects. This approach ensures consistency of channels between reads and efficiency of communication by issuing a single transaction on the underlying bus.

Below is an example illustrating the usage of the BME280 sensor, which measures ambient temperature and atmospheric pressure. Note that sensor_sample_fetch() is only called once, as it reads and compensates data for both channels.
const struct device *const dev = DEVICE_DT_GET_ANY(bosch_bme280);

if (dev == NULL) {
    /* No such node, or the node does not have status "okay". */
    printk("Error: no device found.

return NULL;
}

if (!device_is_ready(dev)) {
    printk("Error: Device ""%s" is not ready; "
    "check the driver initialization logs for errors.
    dev->name);
    return NULL;
}

printk("Found device ""%s", getting sensor data

return dev;
}

int main(void)
{
    const struct device *dev = get_bme280_device();

    if (dev == NULL) {
        return 0;
    }

    while (1) {
        struct sensor_value temp, press, humidity;

        sensor_sample_fetch(dev);
        sensor_channel_get(dev, SENSOR_CHAN_AMBIENT_TEMP, &temp);
        sensor_channel_get(dev, SENSOR_CHAN_PRESS, &press);
        sensor_channel_get(dev, SENSOR_CHAN_HUMIDITY, &humidity);

        printk("temp: %d.%06d; press: %d.%06d; humidity: %d.%06d

44 temp.val1, temp.val2, press.val1, press.val2,
        humidity.val1, humidity.val2);

        k_sleep(K_MSEC(1000));
    }

    return 0;
}

Async Read  To enable the async APIs, use CONFIG_SENSOR_ASYNC_API.

Reading the sensors leverages the Real Time I/O (RTIO) subsystem. Applications gain control of
the data processing thread and even memory management. In order to get started with reading
the sensors, an IODev must be created via the SENSOR_DT_READ_IODEV. Next, an RTIO context
must be created. It is strongly suggested that this context is created with a memory pool via
RTIO_DEFINE_WITH_MEMPOOL.

#include <zephyr/device.h>
#include <zephyr/drivers/sensor.h>
#include <zephyr/rtio/rtio.h>

static const struct device *lid_accel = DEVICE_DT_GET(DT_ALIAS(lid_accel));
SENSOR_DT_READ_IODEV(lid_accel_iodev, DT_ALIAS(lid_accel), SENSOR_CHAN_ACCEL_XYZ);
RTIO_DEFINE_WITH_MEMPOOL(sensors_rtio,
To trigger a read, the application simply needs to call `sensor_read()` and pass the relevant IODEV and RTIO context. Getting the result is done like any other RTIO operation, by waiting on a completion queue event (CQE). In order to help reduce some boilerplate code, the helper function `sensor_processing_with_callback()` is provided. When called, the function will block until a CQE becomes available from the provided RTIO context. The appropriate buffers are extracted and the callback is called. Once the callback is done, the memory is reclaimed by the memory-pool. This looks like:

```c
static void sensor_processing_callback(int result, uint8_t *buf,
                                       uint32_t buf_len, void *userdata) {
    // Process the data...
}
static void sensor_processing_thread(void *, void *, void *) {
    while (true) {
        sensor_processing_with_callback(&sensors_rtio, sensor_processing_callback);
    }
}
K_THREAD_DEFINE(sensor_processing_tid, 1024, sensor_processing_thread,
                NULL, NULL, NULL, 0, 0, 0);
```

**Note:** Helper functions to create custom length IODEV nodes and ones that don’t have static bindings will be added soon.

**Processing the Data** Once data collection completes and the processing callback was called, processing the data is done via the `sensor_decoder_api`. The API provides a means for applications to control when to process the data and how many resources to dedicate to the processing. The API is entirely self contained and requires no system calls (even when `CONFIG_USERSPACE` is enabled).

```c
static struct sensor_decoder_api *lid_accel_decoder = SENSOR_DECODER_DT_GET(DT_ALIAS(lid_accel));

static void sensor_processing_callback(int result, uint8_t *buf,
                                        uint32_t buf_len, void *userdata) {

    uint64_t timestamp;
    sensor_frame_iterator_t fit = {0};
    sensor_channel_iterator_t cit = {0};
    enum sensor_channel channels[3];
    q31_t values[3];
    int8_t shift[3];
    lid_accel_decoder->get_timestamp(buf, &timestamp);
    lid_accel_decoder->decode(buf, &fit, &cit, channels, values, 3);

    /* Values are now in q31_t format, we're going to convert them to micro-units */

    /* First, we need to know by how much to shift the values */
    lid_accel_decoder->get_shift(buf, channels[0], &shift[0]);
    lid_accel_decoder->get_shift(buf, channels[1], &shift[1]);

    // Process the data...
}
```
Configuration and Attributes

Setting the communication bus and address is considered the most basic configuration for sensor devices. This setting is done at compile time, via the configuration menu. If the sensor supports interrupts, the interrupt lines and triggering parameters described below are also configured at compile time.

Alongside these communication parameters, sensor chips typically expose multiple parameters that control the accuracy and frequency of measurement. In compliance with Zephyr’s design goals, most of these values are statically configured at compile time.

However, certain parameters could require runtime configuration, for example, threshold values for interrupts. These values are configured via attributes. The example in the following section showcases a sensor with an interrupt line that is triggered when the temperature crosses a threshold. The threshold is configured at runtime using an attribute.

Triggers

Triggers in Zephyr refer to the interrupt lines of the sensor chips. Many sensor chips support one or more triggers. Some examples of triggers include: new data is ready for reading, a channel value has crossed a threshold, or the device has sensed motion.

To configure a trigger, an application needs to supply a `sensor_trigger` and a handler function. The structure contains the trigger type and the channel on which the trigger must be configured.

Because most sensors are connected via SPI or I2C buses, it is not possible to communicate with them from the interrupt execution context. The execution of the trigger handler is deferred to a thread, so that data fetching operations are possible. A driver can spawn its own thread to fetch data, thus ensuring minimum latency. Alternatively, multiple sensor drivers can share a system-wide thread. The shared thread approach increases the latency of handling interrupts but uses less memory. You can configure which approach to follow for each driver. Most drivers can entirely disable triggers resulting in a smaller footprint.

The following example contains a trigger fired whenever temperature crosses the 26 degree Celsius threshold. It also samples the temperature every second. A real application would ideally disable periodic sampling in the interest of saving power. Since the application has direct access to the kernel config symbols, no trigger is registered when triggering was disabled by the driver’s configuration.

```
#define UCEL_PER_CEL 1000000
#define UCEL_PER_MCEL 1000
```
#define TEMP_INITIAL_CEL 25
#define TEMP_WINDOW_HALF_UCEL 500000

static const char *now_str(void)
{
    static char buf[16]; /* ...HH:MM:SS.MMM */
    uint32_t now = k_uptime_get_32();
    unsigned int ms = now % MSEC_PER_SEC;
    unsigned int s;
    unsigned int min;
    unsigned int h;

    now /= MSEC_PER_SEC;
    s = now % 60U;
    now /= 60U;
    min = now % 60U;
    now /= 60U;
    h = now;

    snprintf(buf, sizeof(buf), "%u:%02u:%02u.%03u",
             h, min, s, ms);
    return buf;
}

#ifndef CONFIG_MCP9808_TRIGGER
static struct sensor_trigger sensor_trig;

static int set_window(const struct device *dev,
                       const struct sensor_value *temp)
{
    const int temp_ucel = temp->val1 * UCEL_PER_CEL + temp->val2;
    const int low_ucel = temp_ucel - TEMP_WINDOW_HALF_UCEL;
    const int high_ucel = temp_ucel + TEMP_WINDOW_HALF_UCEL;

    struct sensor_value val = {
        .val1 = low_ucel / UCEL_PER_CEL,
        .val2 = low_ucel % UCEL_PER_CEL,
    };

    int rc = sensor_attr_set(dev, SENSOR_CHAN_AMBIENT_TEMP,
                              SENSOR_ATTR_LOWER_THRESH, &val);
    if (rc == 0) {
        val.val1 = high_ucel / UCEL_PER_CEL,
        val.val2 = high_ucel % UCEL_PER_CEL,
        rc = sensor_attr_set(dev, SENSOR_CHAN_AMBIENT_TEMP,
                              SENSOR_ATTR_UPPER_THRESH, &val);
    }

    if (rc == 0) {
        printf("Alert on temp outside [%d, %d] milli-Celsius\n",
               low_ucel / UCEL_PER_MCEL,
               high_ucel / UCEL_PER_MCEL);
    }
    return rc;
}

static inline int set_window_ucel(const struct device *dev,
                                  int temp_ucel)
{
    struct sensor_value val = {
        .val1 = temp_ucel / UCEL_PER_CEL,
        return rc;
}

static inline int set_window_ucel(const struct device *dev,
                                  int temp_ucel)
{
    struct sensor_value val = {
        .val1 = temp_ucel / UCEL_PER_CEL,

```c
    .val2 = temp_uCel % UCEL_PER_CEL,
};
    return set_window(dev, &val);
}
static void trigger_handler(const struct device *dev,
    const struct sensor_trigger *trig)
{
    struct sensor_value temp;
    static size_t cnt;
    int rc;
    ++cnt;
    rc = sensor_sample_fetch(dev);
    if (rc != 0) {
        printf("sensor_sample_fetch error: %d\n", rc);
        return;
    }
    rc = sensor_channel_get(dev, SENSOR_CHAN_AMBIENT_TEMP, &temp);
    if (rc != 0) {
        printf("sensor_channel_get error: %d\n", rc);
        return;
    }
    printf("trigger fired %u, temp %g deg C\n", cnt,
            sensor_value_to_double(&temp));
    set_window(dev, &temp);
}
#endif

int main(void)
{
    const struct device *const dev = DEVICE_DT_GET_ANY(microchip_mcp9808);
    int rc;
    if (dev == NULL) {
        printf("Device not found.\n");
        return 0;
    }
    if (!device_is_ready(dev)) {
        printf("Device %s is not ready.\n", dev->name);
        return 0;
    }
    #ifdef CONFIG_MCP9808_TRIGGER
    rc = set_window_uCel(dev, TEMP_INITIAL_CEL * UCEL_PER_CEL);
    if (rc == 0) {
        sensor_trig.type = SENSOR_TRIG_THRESHOLD;
        sensor_trig.chan = SENSOR_CHAN_AMBIENT_TEMP;
        rc = sensor_trigger_set(dev, &sensor_trig, trigger_handler);
    }
    if (rc != 0) {
        printf("Trigger set failed: %d\n", rc);
        return 0;
    }
    printf("Trigger set got %d\n", rc);
    #endif
    while (1) {
        (continues on next page)
    }
```

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struct sensor_value temp;

rc = sensor_sample_fetch(dev);
if (rc != 0) {
    printf("sensor_sample_fetch error: %d\n", rc);
    break;
}

crc = sensor_channel_get(dev, SENSOR_CHAN_AMBIENT_TEMP, &temp);
if (rc != 0) {
    printf("sensor_channel_get error: %d\n", rc);
    break;
}

printf("%s: %g C\n", now_str(), sensor_value_to_double(&temp));
    k_sleep(K_SECONDS(2));
}
return 0;

API Reference

Related code samples
LVGL line chart with accelerometer data
Display acceleration data on a real-time chart using LVGL.

X-NUCLEO-53L0A1 shield
Interact with the 7-segment display and VL53L0X ranging sensor of an X-NUCLEO-53L0A1 shield.

X-NUCLEO-IKS01A1 shield
Interact with all the sensors of an X-NUCLEO-IKS01A1 shield.

X-NUCLEO-IKS01A2 shield - SensorHub (Mode 2)
Interact with all the sensors of an X-NUCLEO-IKS01A2 shield using Sensor Hub mode.

X-NUCLEO-IKS01A2 shield - Standard (Mode 1)
Interact with all the sensors of an X-NUCLEO-IKS01A2 shield using Standard Mode.

X-NUCLEO-IKS01A3 shield - SensorHub (Mode 2)
Interact with all the sensors of an X-NUCLEO-IKS01A3 shield using Sensor Hub mode.

X-NUCLEO-IKS01A3 shield - Standard (Mode 1)
Interact with all the sensors of an X-NUCLEO-IKS01A3 shield using Standard mode.

X-NUCLEO-IKS02A1 shield - SensorHub (Mode 2)
Interact with all the sensors of an X-NUCLEO-IKS02A1 shield using Sensor Hub mode.

X-NUCLEO-IKS02A1 shield - Standard (Mode 1)
Interact with all the sensors of an X-NUCLEO-IKS02A1 shield using Standard mode.

group sensor_interface
    Sensor Interface.
Defines

`SENSOR_DECODER_CONTEXT_INIT(decoder_, buffer_, channel_, channel_index_)`

Initialize a `sensor_decode_context`.

`SENSOR_STREAM_TRIGGER_PREP(_trigger, _opt)`

`SENSOR_DT_READ_IODEV(name, dt_node, ...)`

Define a reading instance of a sensor.

Use this macro to generate a `rtio_iodev` for reading specific channels. Example:

```c
SENSOR_DT_READ_IODEV(icm42688_accelgyro, DT_NODELABEL(icm42688),
                      SENSOR_CHAN_ACCEL_XYZ, SENSOR_CHAN_GYRO_XYZ);
int main(void) {
    sensor_read(&icm42688_accelgyro, &rtio);
}
```

`SENSOR_DT_STREAM_IODEV(name, dt_node, ...)`

Define a stream instance of a sensor.

Use this macro to generate a `rtio_iodev` for starting a stream that's triggered by specific interrupts. Example:

```c
SENSOR_DT_STREAM_IODEV(imu_stream, DT_ALIAS(imu),
                        {SENSOR_TRIG_FIFO_WATERMARK, SENSOR_STREAM_DATA_INCLUDE},
                        {SENSOR_TRIG_FIFO_FULL, SENSOR_STREAM_DATA_NOP});
int main(void) {
    struct rtio_sqe *handle;
    sensor_stream(&imu_stream, &rtio, NULL, &handle);
    k_msleep(1000);
    rtio_sqe_cancel(handle);
}
```

`SENSOR_CHANNEL_3_AXIS(chan)`

checks if a given channel is a 3-axis channel

**Parameters**

- chan – **[in]** The channel to check

**Return values**

- true – if chan is any of `SENSOR_CHAN_ACCEL_XYZ`, `SENSOR_CHAN_GYRO_XYZ`, or `SENSOR_CHAN_MAGN_XYZ`
- false – otherwise

`SENSOR_G`

The value of gravitational constant in micro m/s^2.

`SENSOR_PI`

The value of constant PI in micros.

`SENSOR_INFO_DEFINE(name, ...)`

`SENSOR_INFO_DT_DEFINE(node_id)`
SENSOR_DEVICE_DT_DEFINE(node_id, init_fn, pm_device, data_ptr, cfg_ptr, level, prio, 
api_ptr, ...)

Like DEVICE_DT_DEFINE() with sensor specifics.

Defines a device which implements the sensor API. May define an element in the sensor
info iterable section used to enumerate all sensor devices.

**Parameters**

- **node_id** – The devicetree node identifier.
- **init_fn** – Name of the init function of the driver.
- **pm_device** – PM device resources reference (NULL if device does not use PM).
- **data_ptr** – Pointer to the device's private data.
- **cfg_ptr** – The address to the structure containing the configuration in-
information for this instance of the driver.
- **level** – The initialization level. See SYS_INIT() for details.
- **prio** – Priority within the selected initialization level. See SYS_INIT() for
details.
- **api_ptr** – Provides an initial pointer to the API function struct used by
the driver. Can be NULL.

SENSOR_DEVICE_DT_INST_DEFINE(inst, ...)

Like SENSOR_DEVICE_DT_DEFINE() for an instance of a DT_DRV_COMPAT compatible.

**Parameters**

- **inst** – instance number. This is replaced by DT_DRV_COMPAT(inst) in the
call to SENSOR_DEVICE_DT_DEFINE().
- **...** – other parameters as expected by SENSOR_DEVICE_DT_DEFINE().

**Typedefs**

typedef void (*sensor_trigger_handler_t)(const struct device *dev, const struct
sensor_trigger *trigger)

Callback API upon firing of a trigger.

**Param dev**
Pointer to the sensor device

**Param trigger**
The trigger

typedef int (*sensor_attr_set_t)(const struct device *dev, enum sensor_channel chan,
enum sensor_attribute attr, const struct sensor_value *val)

Callback API upon setting a sensor's attributes.

See sensor_attr_set() for argument description

typedef int (*sensor_attr_get_t)(const struct device *dev, enum sensor_channel chan,
enum sensor_attribute attr, struct sensor_value *val)

Callback API upon getting a sensor's attributes.

See sensor_attr_get() for argument description
typedef int (*sensor_trigger_set_t)(const struct device *dev, const struct sensor_trigger *trig, sensor_trigger_handler_t handler)

Callback API for setting a sensor's trigger and handler.
See sensor_trigger_set() for argument description

typedef int (*sensor_sample_fetch_t)(const struct device *dev, enum sensor_channel chan)

Callback API for fetching data from a sensor.
See sensor_sample_fetch() for argument description

typedef int (*sensor_channel_get_t)(const struct device *dev, enum sensor_channel chan, struct sensor_value *val)

Callback API for getting a reading from a sensor.
See sensor_channel_get() for argument description

typedef int (*sensor_get_decoder_t)(const struct device *dev, const struct sensor_decoder_api **api)

Get the decoder associate with the given device.

See also:
sensor_get_decoder for more details

typedef int (*sensor_submit_t)(const struct device *sensor, struct rtio_iodev_sqe *sqe)

typedef void (*sensor_processing_callback_t)(int result, uint8_t *buf, uint32_t buf_len, void *userdata)

Callback function used with the helper processing function.

See also:
sensor_processing_with_callback

**Param result**
  [in] The result code of the read (0 being success)

**Param buf**
  [in] The data buffer holding the sensor data

**Param buf_len**
  [in] The length (in bytes) of the buf

**Param userdata**
  [in] The optional userdata passed to sensor_read()

Enums

defined sensor_channel
  Sensor channels.

Values:

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enumerator SENSOR_CHAN_ACCEL_X
    Acceleration on the X axis, in m/s^2.

enumerator SENSOR_CHAN_ACCEL_Y
    Acceleration on the Y axis, in m/s^2.

enumerator SENSOR_CHAN_ACCEL_Z
    Acceleration on the Z axis, in m/s^2.

enumerator SENSOR_CHAN_ACCEL_XYZ
    Acceleration on the X, Y and Z axes.

enumerator SENSOR_CHAN_GYRO_X
    Angular velocity around the X axis, in radians/s.

enumerator SENSOR_CHAN_GYRO_Y
    Angular velocity around the Y axis, in radians/s.

enumerator SENSOR_CHAN_GYRO_Z
    Angular velocity around the Z axis, in radians/s.

enumerator SENSOR_CHAN_GYRO_XYZ
    Angular velocity around the X, Y and Z axes.

enumerator SENSOR_CHAN_MAGN_X
    Magnetic field on the X axis, in Gauss.

enumerator SENSOR_CHAN_MAGN_Y
    Magnetic field on the Y axis, in Gauss.

enumerator SENSOR_CHAN_MAGN_Z
    Magnetic field on the Z axis, in Gauss.

enumerator SENSOR_CHAN_MAGN_XYZ
    Magnetic field on the X, Y and Z axes.

enumerator SENSOR_CHAN_DIE_TEMP
    Device die temperature in degrees Celsius.

enumerator SENSOR_CHAN_AMBIENT_TEMP
    Ambient temperature in degrees Celsius.

enumerator SENSOR_CHAN_PRESS
    Pressure in kilopascal.

enumerator SENSOR_CHAN_PROX
    Proximity.
    Adimensional. A value of 1 indicates that an object is close.
enumerator SENSOR_CHAN_HUMIDITY
   Humidity, in percent.

enumerator SENSOR_CHAN_LIGHT
   Illuminance in visible spectrum, in lux.

enumerator SENSOR_CHAN_IR
   Illuminance in infra-red spectrum, in lux.

enumerator SENSOR_CHAN_RED
   Illuminance in red spectrum, in lux.

enumerator SENSOR_CHAN_GREEN
   Illuminance in green spectrum, in lux.

enumerator SENSOR_CHAN_BLUE
   Illuminance in blue spectrum, in lux.

enumerator SENSOR_CHAN_ALTITUDE
   Altitude, in meters.

enumerator SENSOR_CHAN_PM_1_0
   1.0 micro-meters Particulate Matter, in ug/m^3

enumerator SENSOR_CHAN_PM_2_5
   2.5 micro-meters Particulate Matter, in ug/m^3

enumerator SENSOR_CHAN_PM_10
   10 micro-meters Particulate Matter, in ug/m^3

enumerator SENSOR_CHAN_DISTANCE
   Distance.
   From sensor to target, in meters

enumerator SENSOR_CHAN_CO2
   CO2 level, in parts per million (ppm)

enumerator SENSOR_CHAN_VOC
   VOC level, in parts per billion (ppb)

enumerator SENSOR_CHAN_GAS_RES
   Gas sensor resistance in ohms.

enumerator SENSOR_CHAN_VOLTAGE
   Voltage, in volts.

enumerator SENSOR_CHAN_VSHUNT
   Current Shunt Voltage in milli-volts.
enumerator SENSOR_CHAN_CURRENT
Current, in amps.

enumerator SENSOR_CHAN_POWER
Power in watts.

enumerator SENSOR_CHAN_RESISTANCE
Resistance, in Ohm.

enumerator SENSOR_CHAN_ROTATION
Angular rotation, in degrees.

enumerator SENSOR_CHAN_POS_DX
Position change on the X axis, in points.

enumerator SENSOR_CHAN_POS_DY
Position change on the Y axis, in points.

enumerator SENSOR_CHAN_POS_DZ
Position change on the Z axis, in points.

enumerator SENSOR_CHAN_RPM
Revolutions per minute, in RPM.

enumerator SENSOR_CHAN_GAUGE_VOLTAGE
Voltage, in volts.

enumerator SENSOR_CHAN_GAUGE_AVG_CURRENT
Average current, in amps.

enumerator SENSOR_CHAN_GAUGE_STDBY_CURRENT
Standby current, in amps.

enumerator SENSOR_CHAN_GAUGE_MAX_LOAD_CURRENT
Max load current, in amps.

enumerator SENSOR_CHAN_GAUGE_TEMP
Gauge temperature

enumerator SENSOR_CHAN_GAUGE_STATE_OF_CHARGE
State of charge measurement in %.

enumerator SENSOR_CHAN_GAUGE_FULL_CHARGE_CAPACITY
Full Charge Capacity in mAh.

enumerator SENSOR_CHAN_GAUGE_REMAINING_CHARGE_CAPACITY
Remaining Charge Capacity in mAh.
enumerator SENSOR_CHAN_GAUGE_NOM_AVAIL_CAPACITY
Nominal Available Capacity in mAh.

denumerator SENSOR_CHAN_GAUGE_FULL_AVAIL_CAPACITY
Full Available Capacity in mAh.

denumerator SENSOR_CHAN_GAUGE_AVG_POWER
Average power in mW.

denumerator SENSOR_CHAN_GAUGE_STATE_OF_HEALTH
State of health measurement in %.

denumerator SENSOR_CHAN_GAUGE_TIME_TO_EMPTY
Time to empty in minutes.

denumerator SENSOR_CHAN_GAUGE_TIME_TO_FULL
Time to full in minutes.

denumerator SENSOR_CHAN_GAUGE_CYCLE_COUNT
Cycle count (total number of charge/discharge cycles)

denumerator SENSOR_CHAN_GAUGE_DESIGN_VOLTAGE
Design voltage of cell in V (max voltage)

denumerator SENSOR_CHAN_GAUGE_DESIRED_VOLTAGE
Desired voltage of cell in V (nominal voltage)

denumerator SENSOR_CHAN_GAUGE_DESIRED_CHARGING_CURRENT
Desired charging current in mA.

denumerator SENSOR_CHAN_ALL
All channels.

denumerator SENSOR_CHAN_COMMON_COUNT
Number of all common sensor channels.

denumerator SENSOR_CHAN_PRIV_START = SENSOR_CHAN_COMMON_COUNT
This and higher values are sensor specific.
Refer to the sensor header file.

denumerator SENSOR_CHAN_MAX = INT16_MAX
Maximum value describing a sensor channel type.

e enum sensor_trigger_type
  Sensor trigger types.

  Values:
enumerator SENSOR_TRIG_TIMER
    Timer-based trigger, useful when the sensor does not have an interrupt line.

eenumerator SENSOR_TRIG_DATA_READY
    Trigger fires whenever new data is ready.

eenumerator SENSOR_TRIG_DELTA
    Trigger fires when the selected channel varies significantly.
    This includes any-motion detection when the channel is acceleration or gyro. If detection is based on slope between successive channel readings, the slope threshold is configured via the SENSOR_ATTR_SLOPE_TH and SENSOR_ATTR_SLOPE_DUR attributes.

eenumerator SENSOR_TRIG_NEAR_FAR
    Trigger fires when a near/far event is detected.

eenumerator SENSOR_TRIG_THRESHOLD
    Trigger fires when channel reading transitions configured thresholds.
    The thresholds are configured via the SENSOR_ATTR_LOWER_THRESH, SENSOR_ATTR_UPPER_THRESH, and SENSOR_ATTR_HYSTERESIS attributes.

eenumerator SENSOR_TRIG_TAP
    Trigger fires when a single tap is detected.

eenumerator SENSOR_TRIG_DOUBLE_TAP
    Trigger fires when a double tap is detected.

eenumerator SENSOR_TRIG_FREEFALL
    Trigger fires when a free fall is detected.

eenumerator SENSOR_TRIG_MOTION
    Trigger fires when motion is detected.

eenumerator SENSOR_TRIG_STATIONARY
    Trigger fires when no motion has been detected for a while.

eenumerator SENSOR_TRIG_FIFO_WATERMARK
    Trigger fires when the FIFO watermark has been reached.

eenumerator SENSOR_TRIG_FIFO_FULL
    Trigger fires when the FIFO becomes full.

eenumerator SENSOR_TRIG_COMMON_COUNT
    Number of all common sensor triggers.

eenumerator SENSOR_TRIG_PRIV_START = SENSOR_TRIG_COMMON_COUNT
    This and higher values are sensor specific.
    Refer to the sensor header file.
enumerator SENSOR_TRIG_MAX = INT16_MAX
   Maximum value describing a sensor trigger type.

defined sensor_attribute
   Sensor attribute types.
   Values:

   enumerator SENSOR_ATTR_SAMPLING_FREQUENCY
      Sensor sampling frequency, i.e.
      how many times a second the sensor takes a measurement.

   enumerator SENSOR_ATTR_LOWER_THRESH
      Lower threshold for trigger.

   enumerator SENSOR_ATTR_UPPER_THRESH
      Upper threshold for trigger.

   enumerator SENSOR_ATTR_SLOPE_TH
      Threshold for any-motion (slope) trigger.

   enumerator SENSOR_ATTR_SLOPE_DUR
      Duration for which the slope values needs to be outside the threshold for the trig-
      ger to fire.

   enumerator SENSOR_ATTR_HYSTERESIS

   enumerator SENSOR_ATTR_OVERSAMPLING
      Oversampling factor.

   enumerator SENSOR_ATTR_FULL_SCALE
      Sensor range, in SI units.

   enumerator SENSOR_ATTR_OFFSET
      The sensor value returned will be altered by the amount indicated by offset: fi-
      nal_value = sensor_value + offset.

   enumerator SENSOR_ATTR_CALIB_TARGET
      Calibration target.
      This will be used by the internal chip's algorithms to calibrate itself on a certain
      axis, or all of them.

   enumerator SENSOR_ATTR_CONFIGURATION
      Configure the operating modes of a sensor.

   enumerator SENSOR_ATTR_CALIBRATION
      Set a calibration value needed by a sensor.
enumerator SENSOR_ATTR_FEATURE_MASK
   Enable/disable sensor features.

enumerator SENSOR_ATTR_ALERT
   Alert threshold or alert enable/disable.

enumerator SENSOR_ATTR_FF_DUR
   Free-fall duration represented in milliseconds.
   If the sampling frequency is changed during runtime, this attribute should be set
to adjust freefall duration to the new sampling frequency.

enumerator SENSOR_ATTR_BATCH_DURATION
   Hardware batch duration in ticks.

enumerator SENSOR_ATTR_COMMON_COUNT
   Number of all common sensor attributes.

enumerator SENSOR_ATTR_PRIV_START = SENSOR_ATTR_COMMON_COUNT
   This and higher values are sensor specific.
   Refer to the sensor header file.

enumerator SENSOR_ATTR_MAX = INT16_MAX
   Maximum value describing a sensor attribute type.

enum sensor_stream_data_opt
   Options for what to do with the associated data when a trigger is consumed.
   Values:

enumerator SENSOR_STREAM_DATA_INCLUDE = 0
   Include whatever data is associated with the trigger.

enumerator SENSOR_STREAM_DATA_NOP = 1
   Do nothing with the associated trigger data, it may be consumed later.

enumerator SENSOR_STREAM_DATA_DROP = 2
   Flush/clear whatever data is associated with the trigger.

Functions

static inline int sensor_decode(struct sensor_decode_context *ctx, void *out, uint16_t max_count)
   Decode N frames using a sensor_decode_context.

Parameters

• ctx – [inout] The context to use for decoding
• out – [out] The output buffer
• max_count – [in] Maximum number of frames to decode
Returns
The decode result from `sensor_decoder_api`'s decode function

```c
int sensor_natively_supported_channel_size_info(enum sensor_channel channel,
    size_t *base_size, size_t *
    *frame_size)
```

Set an attribute for a sensor:

```c
int sensor_attr_set(const struct device *dev, enum sensor_channel chan, enum
    sensor_attribute attr, const struct sensor_value *val)
```

Parameters
- **dev** – Pointer to the sensor device
- **chan** – The channel the attribute belongs to, if any. Some attributes may only be set for all channels of a device, depending on device capabilities.
- **attr** – The attribute to set
- **val** – The value to set the attribute to

Returns
0 if successful, negative errno code if failure.

```c
int sensor_attr_get(const struct device *dev, enum sensor_channel chan, enum
    sensor_attribute attr, struct sensor_value *val)
```

Get an attribute for a sensor:

Parameters
- **dev** – Pointer to the sensor device
- **chan** – The channel the attribute belongs to, if any. Some attributes may only be set for all channels of a device, depending on device capabilities.
- **attr** – The attribute to get
- **val** – Pointer to where to store the attribute

Returns
0 if successful, negative errno code if failure.

```c
static inline int sensor_trigger_set(const struct device *dev, const struct
    sensor_trigger *trig, sensor_trigger_handler_t handler)
```

Activate a sensor's trigger and set the trigger handler.

The handler will be called from a thread, so I2C or SPI operations are safe. However, the thread's stack is limited and defined by the driver. It is currently up to the caller to ensure that the handler does not overflow the stack.

The user-allocated trigger will be stored by the driver as a pointer, rather than a copy, and passed back to the handler. This enables the handler to use CONTAINER_OF to retrieve a context pointer when the trigger is embedded in a larger struct and requires that the trigger is not allocated on the stack.

Function properties (list may not be complete)

**supervisor**

```c
Parameters
- **dev** – Pointer to the sensor device
- **trig** – The trigger to activate
- **handler** – The function that should be called when the trigger fires
```

7.6. Peripherals
Returns
0 if successful, negative errno code if failure.

int sensor_sample_fetch(const struct device *dev)
Fetch a sample from the sensor and store it in an internal driver buffer.
Read all of a sensor's active channels and, if necessary, perform any additional operations necessary to make the values useful. The user may then get individual channel values by calling sensor_channel_get.
The function blocks until the fetch operation is complete.
Since the function communicates with the sensor device, it is unsafe to call it in an ISR if the device is connected via I2C or SPI.

Parameters
• dev – Pointer to the sensor device

Returns
0 if successful, negative errno code if failure.

int sensor_sample_fetch_chan(const struct device *dev, enum sensor_channel type)
Fetch a sample from the sensor and store it in an internal driver buffer.
Read and compute compensation for one type of sensor data (magnetometer, accelerometer, etc). The user may then get individual channel values by calling sensor_channel_get.
This is mostly implemented by multi function devices enabling reading at different sampling rates.
The function blocks until the fetch operation is complete.
Since the function communicates with the sensor device, it is unsafe to call it in an ISR if the device is connected via I2C or SPI.

Parameters
• dev – Pointer to the sensor device
• type – The channel that needs updated

Returns
0 if successful, negative errno code if failure.

int sensor_channel_get(const struct device *dev, enum sensor_channel chan, struct sensor_value *val)
Get a reading from a sensor device.
Return a useful value for a particular channel, from the driver's internal data. Before calling this function, a sample must be obtained by calling sensor_sample_fetch or sensor_sample_fetch_chan. It is guaranteed that two subsequent calls of this function for the same channels will yield the same value, if sensor_sample_fetch or sensor_sample_fetch_chan has not been called in the meantime.
For vectorial data samples you can request all axes in just one call by passing the specific channel with _XYZ suffix. The sample will be returned at val[0], val[1] and val[2] (X, Y and Z in that order).

Parameters
• dev – Pointer to the sensor device
• chan – The channel to read
• val – Where to store the value
Returns
0 if successful, negative errno code if failure.

int sensor_get_decoder(const struct device *dev, const struct sensor_decoder_api **decoder)

Get the sensor's decoder API.

Parameters
• dev – [in] The sensor device
• decoder – [in] Pointer to the decoder which will be set upon success

Returns
0 on success

Returns
< 0 on error

int sensor_reconfigure_read_iodev(struct rtio_iodev *iodev, const struct device *sensor, const enum sensor_channel *channels, size_t num_channels)

Reconfigure a reading iodev.

Allows a reconfiguration of the iodev associated with reading a sample from a sensor.

Important: If the iodev is currently servicing a read operation, the data will likely be invalid. Please be sure the flush or wait for all pending operations to complete before using the data after a configuration change.

It is also important that the data field of the iodev is a sensor_read_config.

Parameters
• iodev – [in] The iodev to reconfigure
• sensor – [in] The sensor to read from
• channels – [in] One or more channels to read
• num_channels – [in] The number of channels in channels

Returns
0 on success

Returns
< 0 on error

static inline int sensor_stream(struct rtio_iodev *iodev, struct rtio *ctx, void *userdata, struct rtio_sqe **handle)

static inline int sensor_read(struct rtio_iodev *iodev, struct rtio *ctx, void *userdata)

Read data from a sensor.

Using cfg, read one snapshot of data from the device by using the provided RTIO context ctx. This call will generate a rtio_sqe that will leverage the RTIO's internal mem-pool when the time comes to service the read.

Parameters
• iodev – [in] The iodev created by SENSOR_DT_READ_IODEV
• ctx – [in] The RTIO context to service the read
• userdata – [in] Optional userdata that will be available when the read is complete

Returns
0 on success
Returns
< 0 on error

void sensor_processing_with_callback(struct rtio *ctx, sensor_processing_callback_t cb)
Helper function for common processing of sensor data.

This function can be called in a blocking manner after sensor_read() or in a standalone thread dedicated to processing. It will wait for a cqe from the RTIO context, once received, it will decode the userdata and call the cb. Once the cb returns, the buffer will be released back into ctx’s mempool if available.

Parameters
- ctx [in] The RTIO context to wait on
- cb [in] Callback to call when data is ready for processing

static inline int32_t sensor_ms2_to_g(const struct sensor_value *ms2)
Helper function to convert acceleration from m/s^2 to Gs.

Parameters
- ms2 [in] A pointer to a sensor_value struct holding the acceleration, in m/s^2.

Returns
The converted value, in Gs.

static inline void sensor_g_to_ms2(int32_t g, struct sensor_value *ms2)
Helper function to convert acceleration from Gs to m/s^2.

Parameters
- g [in] The G value to be converted.
- ms2 [out] A pointer to a sensor_value struct, where the result is stored.

static inline int32_t sensor_ms2_to_ug(const struct sensor_value *ms2)
Helper function to convert acceleration from m/s^2 to micro Gs.

Parameters
- ms2 [in] A pointer to a sensor_value struct holding the acceleration, in m/s^2.

Returns
The converted value, in micro Gs.

static inline void sensor_ug_to_ms2(int32_t ug, struct sensor_value *ms2)
Helper function to convert acceleration from micro Gs to m/s^2.

Parameters
- ug [in] The micro G value to be converted.
- ms2 [out] A pointer to a sensor_value struct, where the result is stored.

static inline int32_t sensor_rad_to_degrees(const struct sensor_value *rad)
Helper function for converting radians to degrees.

Parameters
- rad [in] A pointer to a sensor_value struct, holding the value in radians.

Returns
The converted value, in degrees.

static inline void sensor_degrees_to_rad(int32_t d, struct sensor_value *rad)
Helper function for converting degrees to radians.

Parameters
• d – The value (in degrees) to be converted.
• rad – A pointer to a sensor_value struct, where the result is stored.

static inline int32_t sensor_rad_to_10udegrees(const struct sensor_value *rad)
Helper function for converting radians to 10 micro degrees.
When the unit is 1 micro degree, the range that the int32_t can represent is +/-2147483 degrees. In order to increase this range, here we use 10 micro degrees as the unit.

Parameters
• rad – A pointer to a sensor_value struct, holding the value in radians.

Returns
The converted value, in 10 micro degrees.

static inline void sensor_10udegrees_to_rad(int32_t d, struct sensor_value *rad)
Helper function for converting 10 micro degrees to radians.

Parameters
• d – The value (in 10 micro degrees) to be converted.
• rad – A pointer to a sensor_value struct, where the result is stored.

static inline double sensor_value_to_double(const struct sensor_value *val)
Helper function for converting struct sensor_value to double.

Parameters
• val – A pointer to a sensor_value struct.

Returns
The converted value.

static inline float sensor_value_to_float(const struct sensor_value *val)
Helper function for converting struct sensor_value to float.

Parameters
• val – A pointer to a sensor_value struct.

Returns
The converted value.

static inline int sensor_value_from_double(struct sensor_value *val, double inp)
Helper function for converting double to struct sensor_value.

Parameters
• val – A pointer to a sensor_value struct.
• inp – The converted value.

Returns
0 if successful, negative errno code if failure.

static inline int sensor_value_from_float(struct sensor_value *val, float inp)
Helper function for converting float to struct sensor_value.

Parameters
• val – A pointer to a sensor_value struct.
• inp – The converted value.

Returns
0 if successful, negative errno code if failure.
static inline int64_t sensor_value_to_milli(const struct sensor_value *val)
  Helper function for converting struct sensor_value to integer milli units.

  Parameters
  • val – A pointer to a sensor_value struct.

  Returns
  The converted value.

static inline int64_t sensor_value_to_micro(const struct sensor_value *val)
  Helper function for converting struct sensor_value to integer micro units.

  Parameters
  • val – A pointer to a sensor_value struct.

  Returns
  The converted value.

static inline int sensor_value_from_milli(struct sensor_value *val, int64_t milli)
  Helper function for converting integer milli units to struct sensor_value.

  Parameters
  • val – A pointer to a sensor_value struct.
  • milli – The converted value.

  Returns
  0 if successful, negative errno code if failure.

static inline int sensor_value_from_micro(struct sensor_value *val, int64_t micro)
  Helper function for converting integer micro units to struct sensor_value.

  Parameters
  • val – A pointer to a sensor_value struct.
  • micro – The converted value.

  Returns
  0 if successful, negative errno code if failure.

struct sensor_value
  #include <sensor.h> Representation of a sensor readout value.

  The value is represented as having an integer and a fractional part, and can be ob-
  tained using the formula val1 + val2 * 10^-6. Negative values also adhere to the above
  formula, but may need special attention. Here are some examples of the value repre-
  sentation:

<table>
<thead>
<tr>
<th>Value</th>
<th>val1</th>
<th>val2</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.5</td>
<td>0</td>
<td>500000</td>
</tr>
<tr>
<td>-0.5</td>
<td>0</td>
<td>-500000</td>
</tr>
<tr>
<td>-1.0</td>
<td>-1</td>
<td>0</td>
</tr>
<tr>
<td>-1.5</td>
<td>-1</td>
<td>-500000</td>
</tr>
</tbody>
</table>

  Public Members

  int32_t val1
    Integer part of the value.
int32_t val2
  Fractional part of the value (in one-millionth parts).

struct sensor_trigger
  #include <sensor.h> Sensor trigger spec.

Public Members

enum sensor_trigger_type type
  Trigger type.

enum sensor_channel chan
  Channel the trigger is set on.

struct sensor_decoder_api
  #include <sensor.h> Decodes a single raw data buffer.
  Data buffers are provided on the RTIO context that's supplied to sensor_read.

Public Members

int (*get_frame_count)(const uint8_t *buffer, enum sensor_channel channel, size_t channel_idx, uint16_t *frame_count)
  Get the number of frames in the current buffer.
  Param buffer  
    [in] The buffer provided on the RTIO context.
  Param channel  
    [in] The channel to get the count for
  Param channel_idx  
    [in] The index of the channel
  Param frame_count  
    [out] The number of frames on the buffer (at least 1)
  Return  
    0 on success
  Return  
    -ENOTSUP if the channel/channel_idx aren’t found

int (*get_size_info)(enum sensor_channel channel, size_t *base_size, size_t *frame_size)
  Get the size required to decode a given channel.
  When decoding a single frame, use base_size. For every additional frame, add another frame_size. As an example, to decode 3 frames use: ‘base_size + 2 * frame_size’.
  Param channel  
    [in] The channel to query
  Param base_size  
    [out] The size of decoding the first frame
  Param frame_size  
    [out] The additional size of every additional frame
  Return  
    0 on success
int (*decode)(const uint8_t *buffer, enum sensor_channel channel, size_t channel_idx, uint32_t *fit, uint16_t max_count, void *data_out)

Decode up to max_count samples from the buffer.

Decode samples of channel sensor_channel across multiple frames. If there exist multiple instances of the same channel, channel_index is used to differentiate them. As an example, assume a sensor provides 2 distance measurements:

```c
// Decode the first channel instance of 'distance'
decoder->decode(buffer, SENSOR_CHAN_DISTANCE, 0, &fit, 5, out);
...

// Decode the second channel instance of 'distance'
decoder->decode(buffer, SENSOR_CHAN_DISTANCE, 1, &fit, 5, out);
```

Param buffer
[in] The buffer provided on the RTIO context

Param channel
[in] The channel to decode

Param channel_idx
[in] The index of the channel

Param fit
[inout] The current frame iterator

Param max_count
[in] The maximum number of channels to decode.

Param data_out
[out] The decoded data

Return
0 no more samples to decode

Return
>0 the number of decoded frames

Return
<0 on error

bool (*has_trigger)(const uint8_t *buffer, enum sensor_trigger_type trigger)

Check if the given trigger type is present.

Param buffer
[in] The buffer provided on the RTIO context

Param trigger
[in] The trigger type in question

Return
Whether the trigger is present in the buffer

struct sensor_decode_context
```
#include <sensor.h> Used for iterating over the data frames via the sensor_decoder_api.
```

Example usage:
```
(c)
   struct sensor_decode_context ctx = SENSOR_DECODECONTEXT_INIT(
       decoder, buffer, SENSOR_CHAN_ACCEL_XYZ, 0);

   while (true) {
       struct sensor_three_axis_data accel_out_data;
       ```
num_decoded_channels = sensor_decode(ctx, &accel_out_data, 1);
if (num_decoded_channels <= 0) {
    printk("Done decoding buffer\n");
    break;
}
printk("Decoded (%" PRId32 ", %" PRId32 ", %" PRId32 ")\n", accel_out_data.readings[0].x, accel_out_data.readings[0].y, accel_out_data.readings[0].z);

structure sensor_stream_trigger
#include <sensor.h>

structure sensor_read_config
#include <sensor.h>

structure sensor_driver_api
#include <sensor.h>

structure sensor_data_generic_header
#include <sensor.h>

Group sensor_emulator_backend
Sensor emulator backend API.

Functions

static inline bool emul_sensor_backend_is_supported(const struct emul *target)
    Check if a given sensor emulator supports the backend API.

    Parameters
    • target – Pointer to emulator instance to query

    Returns
    True if supported, false if unsupported or if target is NULL.

static inline int emul_sensor_backend_set_channel(const struct emul *target, enum sensor_channel ch, const q31_t *value, int8_t shift)
    Set an expected value for a given channel on a given sensor emulator.

    Parameters
    • target – Pointer to emulator instance to operate on
    • ch – Sensor channel to set expected value for
    • value – Expected value in fixed-point format using standard SI unit for sensor type
    • shift – Shift value (scaling factor) applied to value

    Returns
    0 if successful
Returns
-ENOTSUP if no backend API or if channel not supported by emul

Returns
-ERANGE if provided value is not in the sensor's supported range

static inline int emul_sensor_backend_get_sample_range(const struct emul *target, enum sensor_channel ch, q31_t *lower, q31_t *upper, q31_t *epsilon, int8_t *shift)

Query an emulator for a channel's supported sample value range and tolerance.

Parameters
- target – Pointer to emulator instance to operate on
- ch – The channel to request info for. If ch is unsupported, return -ENOTSUP
- lower – [out] Minimum supported sample value in SI units, fixed-point format
- upper – [out] Maximum supported sample value in SI units, fixed-point format
- epsilon – [out] Tolerance to use comparing expected and actual values to account for rounding and sensor precision issues. This can usually be set to the minimum sample value step size. Uses SI units and fixed-point format.
- shift – [out] The shift value (scaling factor) associated with lower, upper, and epsilon.

Returns
0 if successful

Returns
-ENOTSUP if no backend API or if channel not supported by emul

static inline int emul_sensor_backend_set_attribute(const struct emul *target, enum sensor_channel ch, enum sensor_attribute attribute, const void *value)

Set the emulator's attribute values.

Parameters
- target – [in] Pointer to emulator instance to operate on
- ch – [in] The channel to request info for. If ch is unsupported, return -ENOTSUP
- attribute – [in] The attribute to set
- value – [in] the value to use (cast according to the channel/attribute pair)

Returns
0 is successful

Returns
< 0 on error

static inline int emul_sensor_backend_get_attribute_metadata(const struct emul *target, enum sensor_channel ch, enum sensor_attribute attribute, q31_t *min, q31_t *max, q31_t *increment, int8_t *shift)
Get metadata about an attribute.

Information provided by this function includes the minimum/maximum values of the attribute as well as the increment (value per LSB) which can be used as an epsilon when comparing results.

**Parameters**

- **target** – [in] Pointer to emulator instance to operate on
- **ch** – [in] The channel to request info for. If ch is unsupported, return ‘-ENOTSUP’
- **attribute** – [in] The attribute to request info for. If attribute is unsupported, return ‘-ENOTSUP’
- **min** – [out] The minimum value the attribute can be set to
- **max** – [out] The maximum value the attribute can be set to
- **increment** – [out] The value that the attribute increases by for every LSB
- **shift** – [out] The shift for min, max, and increment

**Returns**

0 on SUCCESS

< 0 on error

7.6.44 Serial Peripheral Interface (SPI) Bus

**Overview**

**API Reference**

**Related code samples**

**Enhanced Serial Peripheral Interface (eSPI)**

Use eSPI to connect to a slave device and exchange virtual wire packets.

**SPI bitbang**

Use the bitbang SPI driver for communicating with a slave.

```c
#include <spi.h>

int spi_open(int channel)
{
    // Open SPI using the channel
    return 0; // Success
}

int spi_setmode(int channel, int sopm)
{
    // Set SPI mode
    return 0; // Success
}

int spi_transfer(int channel, uint8_t *txdata, uint8_t *rxdata, int size)
{
    // Transfer data
    return 0; // Success
}
```

7.6. Peripherals
**SPI Polarity & Phase Modes**

**SPI_MODE_CPOL**
Clock Polarity: if set, clock idle state will be 1 and active state will be 0.
If untouched, the inverse will be true which is the default.

**SPI_MODE_CPHA**
Clock Phase: this dictates when is the data captured, and depends clock’s polarity.
When SPI_MODE_CPOL is set and this bit as well, capture will occur on low to high transition and high to low if this bit is not set (default). This is fully reversed if CPOL is not set.

**SPI_MODE_LOOP**
Whatever data is transmitted is looped-back to the receiving buffer of the controller.
This is fully controller dependent as some may not support this, and can be used for testing purposes only.

**SPI_MODE_GET(_mode_)**
Get SPI polarity and phase mode bits.

**SPI Transfer modes (host controller dependent)**

**SPI_TRANSFER_MSB**
Most significant bit first.

**SPI_TRANSFER_LSB**
Least significant bit first.

**SPI word size**

**SPI_Word_SIZE_GET(_operation_)**
Get SPI word size.

**SPI_Word_SET(_word_size_)**
Set SPI word size.

**Specific SPI devices control bits**

**SPI_HOLD_ON_CS**
Requests - if possible - to keep CS asserted after the transaction.

**SPI_LOCK_ON**
Keep the device locked after the transaction for the current config.
Use this with extreme caution (see *spi_release()* below) as it will prevent other callers to access the SPI device until *spi_release()* is properly called.
**SPI_CS_ACTIVE_HIGH**

Active high logic on CS.

Usually, and by default, CS logic is active low. However, some devices may require the reverse logic: active high. This bit will request the controller to use that logic. Note that not all controllers are able to handle that natively. In this case deferring the CS control to a gpio line through struct `spi_cs_control` would be the solution.

**SPI MISO lines**

Some controllers support dual, quad or octal MISO lines connected to slaves. Default is single, which is the case most of the time. Without `CONFIG_SPI_EXTENDED_MODES` being enabled, single is the only supported one.

- **SPI_LINES_SINGLE**
  Single line.

- **SPI_LINES_DUAL**
  Dual lines.

- **SPI_LINES QUAD**
  Quad lines.

- **SPI_LINES_OCTAL**
  Octal lines.

- **SPI_LINES_MASK**
  Mask for MISO lines in `spi_operation_t`.

**SPI duplex mode**

Some controllers support half duplex transfer, which results in 3-wire usage. By default, full duplex will prevail.

- **SPI_FULL_DUPLEX**

- **SPI_HALF_DUPLEX**

**SPI Frame Format**

2 frame formats are exposed: Motorola and TI.

The main difference is the behavior of the CS line. In Motorola it stays active the whole transfer. In TI, it's active only one serial clock period prior to actually make the transfer, it is thus inactive during the transfer, which ends when the clocks ends as well. By default, as it is the most commonly used, the Motorola frame format will prevail.

- **SPI_FRAME_FORMAT_MOTOROLA**

- **SPI_FRAME_FORMAT_TI**
Defines

SPI_CS_GPIOS_DT_SPEC_GET(spi_dev)
Get a struct gpio_dt_spec for a SPI device's chip select pin.

Example devicetree fragment:

```plaintext
gpio1: gpio@abcd0001 { ... };
gpio2: gpio@abcd0002 { ... };
spi@abcd0003 {
    compatible = "vnd,spi";
    cs-gpios = <&gpio1 10 \n        GPIO_ACTIVE_LOW>,
              <&gpio2 20 \n        GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };

    b: spi-dev-b@1 {
        reg = <1>;
    };
};
```

Example usage:

```c
SPI_CS_GPIOS_DT_SPEC_GET(DT_NODELABEL(a)) \n// { DEVICE_DT_GET(DT_NODELABEL(gpio1)), 10, GPIO_ACTIVE_LOW }
SPI_CS_GPIOS_DT_SPEC_GET(DT_NODELABEL(b)) \n// { DEVICE_DT_GET(DT_NODELABEL(gpio2)), 20, GPIO_ACTIVE_LOW }
```

Parameters
- spi_dev – a SPI device node identifier

Returns
- gpio_dt_spec struct corresponding with spi_dev's chip select

SPI_CS_GPIOS_DT_SPEC_INST_GET(inst)
Get a struct gpio_dt_spec for a SPI device's chip select pin.

This is equivalent to SPI_CS_GPIOS_DT_SPEC_GET(DT_DRV_INST(inst)).

Parameters
- inst – Devicetree instance number

Returns
- gpio_dt_spec struct corresponding with spi_dev's chip select

SPI_CS_CONTROL_INIT(node_id, delay_)
Initialize and get a pointer to a spi_cs_control from a devicetree node identifier.

This helper is useful for initializing a device on a SPI bus. It initializes a struct spi_cs_control and returns a pointer to it. Here, node_id is a node identifier for a SPI device, not a SPI controller.

Example devicetree fragment:

```plaintext
spi@abcd0001 {
    cs-gpios = <&gpio0 1 \n        GPIO_ACTIVE_LOW>;
    spidev: spi-device@0 { ... };
};
```
Example usage:

```c
struct spi_cs_control ctrl =
    SPI_CS_CONTROL_INIT(DT_NODELABEL(spidev), 2);
```

This example is equivalent to:

```c
struct spi_cs_control ctrl = {
    .gpio = SPI_CS_GPIOS_DT_SPEC_GET(DT_NODELABEL(spidev)),
    .delay = 2,
};
```

**Parameters**

- `node_id` – Devicetree node identifier for a device on a SPI bus
- `delay_` – The delay field to set in the `spi_cs_control`

**Returns**

a pointer to the `spi_cs_control` structure

`SPI_CS_CONTROL_INIT_INST(inst, delay_)`

Get a pointer to a `spi_cs_control` from a devicetree node.

This is equivalent to `SPI_CS_CONTROL_INIT(DT_DRV_INST(inst), delay)`.

Therefore, `DT_DRV_COMPAT` must already be defined before using this macro.

**Parameters**

- `inst` – Devicetree node instance number
- `delay_` – The delay field to set in the `spi_cs_control`

**Returns**

a pointer to the `spi_cs_control` structure

`SPI_CONFIG_DT(node_id, operation_, delay_)`

Structure initializer for `spi_config` from devicetree.

This helper macro expands to a static initializer for a struct `spi_config` by reading the relevant frequency, slave, and cs data from the devicetree.

**Parameters**

- `node_id` – Devicetree node identifier for the SPI device whose struct `spi_config` to create an initializer for
- `operation_` – the desired operation field in the struct `spi_config`
- `delay_` – the desired delay field in the struct `spi_config`’s `spi_cs_control`, if there is one

`SPI_CONFIG_DT_INST(inst, operation_, delay_)`

Structure initializer for `spi_config` from devicetree instance.

This is equivalent to `SPI_CONFIG_DT(DT_DRV_INST(inst), operation_, delay_)`.

**Parameters**

- `inst` – Devicetree instance number
- `operation_` – the desired operation field in the struct `spi_config`
- `delay_` – the desired delay field in the struct `spi_config`’s `spi_cs_control`, if there is one
SPI_DT_SPEC_GET(node_id, operation_, delay_)
Structure initializer for spi_dt_spec from devicetree.
This helper macro expands to a static initializer for a struct spi_dt_spec by reading the relevant bus, frequency, slave, and cs data from the devicetree.
Important: multiple fields are automatically constructed by this macro which must be checked before use. spi_is_ready performs the required device_is_ready checks.

Deprecated:
Use spi_is_ready_dt instead.

Parameters
- node_id – Devicetree node identifier for the SPI device whose struct spi_dt_spec to create an initializer for
- operation_ – the desired operation field in the struct spi_config
- delay_ – the desired delay field in the struct spi_config’s spi_cs_control, if there is one

SPI_DT_SPEC_INST_GET(inst, operation_, delay_)
Structure initializer for spi_dt_spec from devicetree instance.
This is equivalent to SPI_DT_SPEC_GET(DT_DRV_INST(inst), operation_, delay_).

Parameters
- inst – Devicetree instance number
- operation_ – the desired operation field in the struct spi_config
- delay_ – the desired delay field in the struct spi_config’s spi_cs_control, if there is one

SPI_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, level, prio, api, ...)

SPI_STATS_RX_BYTES_INC(dev_)
SPI_STATS_TX_BYTES_INC(dev_)
SPI_STATS_TRANSFER_ERROR_INC(dev_)
spi_transceive_stats(dev, error, tx_bufs, rx_bufs)

SPI_DT_IODEV_DEFINE(name, node_id, operation_, delay_)
Define an iodev for a given dt node on the bus.
These do not need to be shared globally but doing so will save a small amount of memory.

Parameters
- name – Symbolic name to use for defining the iodev
- node_id – Devicetree node identifier
- operation_ – SPI operational mode
- delay_ – Chip select delay in microseconds
Typedefs

typedef uint16_t spi_operation_t
    Opaque type to hold the SPI operation flags.

typedef int (*spi_api_io)(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs)
    Callback API for I/O See spi_transceive() for argument descriptions.
    Callback API for asynchronous I/O See spi_transceive_async() for argument descriptions.

typedef void (*spi_callback_t)(const struct device *dev, int result, void *data)
    SPI callback for asynchronous transfer requests.

    \textbf{Param dev}  
    SPI device which is notifying of transfer completion or error

    \textbf{Param result}  
    Result code of the transfer request. 0 is success, -errno for failure.

    \textbf{Param data}  
    Transfer requester supplied data which is passed along to the callback.

typedef int (*spi_api_io_async)(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs, spi_callback_t cb, void *userdata)

typedef int (*spi_api_release)(const struct device *dev, const struct spi_config *config)
    Callback API for unlocking SPI device.
    See spi_release() for argument descriptions

Functions

static inline bool spi_cs_is_gpio(const struct spi_config *config)
    Check if SPI CS is controlled using a GPIO.

    \textbf{Parameters}  
    \begin{itemize}
        \item config – SPI configuration.
    \end{itemize}

    \textbf{Returns}  
    true If CS is controlled using a GPIO.

    \textbf{Returns}  
    false If CS is controlled by hardware or any other means.

static inline bool spi_cs_is_gpio_dt(const struct spi_dt_spec *spec)
    Check if SPI CS in spi_dt_spec is controlled using a GPIO.

    \textbf{Parameters}  
    \begin{itemize}
        \item spec – SPI specification from devicetree.
    \end{itemize}

    \textbf{Returns}  
    true If CS is controlled using a GPIO.

    \textbf{Returns}  
    false If CS is controlled by hardware or any other means.
static inline bool spi_is_ready(const struct spi_dt_spec *spec)

Validate that SPI bus is ready.

**Parameters**

- **spec** – SPI specification from devicetree

**Return values**

- **true** – if the SPI bus is ready for use.
- **false** – if the SPI bus is not ready for use.

static inline bool spi_is_ready_dt(const struct spi_dt_spec *spec)

Validate that SPI bus (and CS gpio if defined) is ready.

**Parameters**

- **spec** – SPI specification from devicetree

**Return values**

- **true** – if the SPI bus is ready for use.
- **false** – if the SPI bus (or the CS gpio defined) is not ready for use.

int spi_transceive(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs)

Read/write the specified amount of data from the SPI driver.

**Note:** This function is synchronous.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance
- **config** – Pointer to a valid `spi_config` structure instance. Pointer-comparison may be used to detect changes from previous operations.
- **tx_bufs** – Buffer array where data to be sent originates from, or NULL if none.
- **rx_bufs** – Buffer array where data to be read will be written to, or NULL if none.

**Return values**

- **frames** – Positive number of frames received in slave mode.
- **0** – If successful in master mode.
- **-errno** – Negative errno code on failure.

static inline int spi_transceive_dt(const struct spi_dt_spec *spec, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs)

Read/write data from an SPI bus specified in `spi_dt_spec`.

This is equivalent to:

```c
spi_transceive(spec->bus, &spec->config, tx_bufs, rx_bufs);
```

**Parameters**

- **spec** – SPI specification from devicetree
- **tx_bufs** – Buffer array where data to be sent originates from, or NULL if none.
• **rx_bufs** – Buffer array where data to be read will be written to, or NULL if none.

**Returns**
a value from `spi_transceive()`.

```c
static inline int spi_read(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *rx_bufs)
```

Read the specified amount of data from the SPI driver.

**Note:** This function is synchronous.

**Note:** This function is a helper function calling `spi_transceive`.

**Parameters**
- **dev** – Pointer to the device structure for the driver instance
- **config** – Pointer to a valid `spi_config` structure instance. Pointer-comparison may be used to detect changes from previous operations.
- **rx_bufs** – Buffer array where data to be read will be written to.

**Return values**
- **frames** – Positive number of frames received in slave mode.
- **0** – If successful.
- **-errno** – Negative errno code on failure.

```c
static inline int spi_read_dt(const struct spi_dt_spec *spec, const struct spi_buf_set *rx_bufs)
```

Read data from a SPI bus specified in `spi_dt_spec`.

This is equivalent to:

```c
spi_read(spec->bus, &spec->config, rx_bufs);
```

**Parameters**
- **spec** – SPI specification from devicetree
- **rx_bufs** – Buffer array where data to be read will be written to.

**Returns**
a value from `spi_read()`.

```c
static inline int spi_write(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs)
```

Write the specified amount of data from the SPI driver.

**Note:** This function is synchronous.

**Note:** This function is a helper function calling `spi_transceive`.

**Parameters**
• **dev** – Pointer to the device structure for the driver instance

• **config** – Pointer to a valid `spi_config` structure instance. Pointer-comparison may be used to detect changes from previous operations.

• **tx_bufs** – Buffer array where data to be sent originates from.

**Return values**

• **0** – If successful.

• **-errno** – Negative errno code on failure.

```c
static inline int spi_write_dt(const struct spi_dt_spec *spec, const struct spi_buf_set *tx_bufs)
```

Write data to a SPI bus specified in `spi_dt_spec`.

This is equivalent to:

```c
spi_write(spec->bus, &spec->config, tx_bufs);
```

**Parameters**

• **spec** – SPI specification from devicetree

• **tx_bufs** – Buffer array where data to be sent originates from.

**Returns**

a value from `spi_write()`.

```c
static inline int spi_transceive_cb(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs, spi_callback_t callback, void *userdata)
```

Read/write the specified amount of data from the SPI driver.

**Note:** This function is asynchronous.

**Note:** This function is available only if `CONFIG_SPI_ASYNC` is selected.

**Parameters**

• **dev** – Pointer to the device structure for the driver instance

• **config** – Pointer to a valid `spi_config` structure instance. Pointer-comparison may be used to detect changes from previous operations.

• **tx_bufs** – Buffer array where data to be sent originates from, or NULL if none.

• **rx_bufs** – Buffer array where data to be read will be written to, or NULL if none.

• **callback** – Function pointer to completion callback. (Note: if NULL this function will not notify the end of the transaction, and whether it went successfully or not).

• **userdata** – Userdata passed to callback

**Return values**

• **frames** – Positive number of frames received in slave mode.
• 0 – If successful in master mode.
• -errno – Negative errno code on failure.

static inline int spi_transceive_signal(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs, struct k_poll_signal *sig)

Read/write the specified amount of data from the SPI driver.

**Note:** This function is asynchronous.

**Note:** This function is available only if CONFIG_SPI_ASYNC and CONFIG_POLL are selected.

### Parameters

- **dev** – Pointer to the device structure for the driver instance
- **config** – Pointer to a valid spi_config structure instance. Pointer-comparison may be used to detect changes from previous operations.
- **tx_bufs** – Buffer array where data to be sent originates from, or NULL if none.
- **rx_bufs** – Buffer array where data to be read will be written to, or NULL if none.
- **sig** – A pointer to a valid and ready to be signaled struct k_poll_signal. (Note: if NULL this function will not notify the end of the transaction, and whether it went successfully or not).

### Return values

- **frames** – Positive number of frames received in slave mode.
- 0 – If successful in master mode.
- -errno – Negative errno code on failure.

static inline int spi_transceive_async(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs, struct k_poll_signal *sig)

Alias for spi_transceive_signal for backwards compatibility.

**Deprecated:**
Use spi_transceive_signal instead.

static inline int spi_read_signal(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, struct k_poll_signal *sig)

Read the specified amount of data from the SPI driver.

**Note:** This function is asynchronous.
Note: This function is a helper function calling spi_transceive_signal.

Note: This function is available only if CONFIG_SPI_ASYNC and CONFIG_POLL are selected.

Parameters

- dev – Pointer to the device structure for the driver instance
- config – Pointer to a valid spi_config structure instance. Pointer-comparison may be used to detect changes from previous operations.
- rx_bufs – Buffer array where data to be read will be written to.
- sig – A pointer to a valid and ready to be signaled struct k_poll_signal. (Note: if NULL this function will not notify the end of the transaction, and whether it went successfully or not).

Return values

- frames – Positive number of frames received in slave mode.
- 0 – If successful
- -errno – Negative errno code on failure.

static inline int spi_read_async(const struct device *dev, const struct spi_config *config,
const struct spi_buf_set *rx_bufs, struct k_poll_signal *sig)

Alias for spi_read_signal for backwards compatibility.

Deprecated:
Use spi_read_signal instead.

static inline int spi_write_signal(const struct device *dev, const struct spi_config *config,
const struct spi_buf_set *tx_bufs, struct k_poll_signal *sig)

Write the specified amount of data from the SPI driver.

Note: This function is asynchronous.

Note: This function is a helper function calling spi_transceive_async.

Note: This function is available only if CONFIG_SPI_ASYNC and CONFIG_POLL are selected.

Parameters

- dev – Pointer to the device structure for the driver instance
- config – Pointer to a valid spi_config structure instance. Pointer-comparison may be used to detect changes from previous operations.
- tx_bufs – Buffer array where data to be sent originates from.
• sig – A pointer to a valid and ready to be signaled struct k_poll_signal. (Note: if NULL this function will not notify the end of the transaction, and whether it went successfully or not).

**Return values**
• \(0\) – If successful.
• \(-\text{errno}\) – Negative errno code on failure.

```c
static inline int spi_write_async(const struct device *dev, const struct spi_config *config,
                                  const struct spi_buf_set *tx_bufs, struct k_poll_signal *sig)
```

Alias for spi_write_signal for backwards compatibility.

**Deprecated:**
Use `spi_write_signal` instead.

```c
static inline void spi_iodev_submit(struct rtio_iodev_sqe *iodev_sqe)
```

Submit a SPI device with a request.

**Parameters**
• iodev_sqe – Prepared submissions queue entry connected to an iodev defined by SPI_IODEV_DEFINE. Must live as long as the request is in flight.

```c
static inline bool spi_is_ready_iodev(const struct rtio_iodev *spi_iodev)
```

Validate that SPI bus (and CS gpio if defined) is ready.

**Parameters**
• spi_iodev – SPI iodev defined with SPI_DT_IODEV_DEFINE

**Return values**
• true – if the SPI bus is ready for use.
• false – if the SPI bus (or the CS gpio defined) is not ready for use.

```c
static inline int spi_rtio_copy(struct rtio *r, struct rtio_iodev *iodev, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs,
                                struct rtio_sqe **last_sqe)
```

Copy the tx_bufs and rx_bufs into a set of RTIO requests.

**Parameters**
• r – [in] rtio context
• iodev – [in] iodev to transceive with
• tx_bufs – [in] transmit buffer set
• rx_bufs – [in] receive buffer set
• last_sqe – [out] last sqe submitted, NULL if not enough memory

**Return values**
• Number – of submission queue entries
• -ENOMEM – out of memory

```c
int spi_release(const struct device *dev, const struct spi_config *config)
```

Release the SPI device locked on and/or the CS by the current config.

**Note:** This synchronous function is used to release either the lock on the SPI device and/or the CS line that was kept if, and if only, given config parameter was the last
one to be used (in any of the above functions) and if it has the SPI\_LOCK\_ON bit set and/or the SPI\_HOLD\_ON\_CS bit set into its operation bits field. This can be used if the caller needs to keep its hand on the SPI device for consecutive transactions and/or if it needs the device to stay selected. Usually both bits will be used along each other, so the device is locked and stays on until another operation is necessary or until it gets released with the present function.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance
- **config** – Pointer to a valid `spi_config` structure instance.

**Return values**

- **0** – If successful.
- **-errno** – Negative errno code on failure.

static inline int _SPI\_release\_dt(const struct spi\_dt\_spec *spec)

Release the SPI device specified in `spi\_dt\_spec`.

This is equivalent to:

```
spi_release(spec->bus, &spec->config);
```

**Parameters**

- **spec** – SPI specification from devicetree

**Returns**

a value from `spi_release()`.

**Variables**

const struct rtio\_iodev\_api spi\_iodev\_api

struct spi\_cs\_control

```
#include <spi.h> SPI Chip Select control structure.
```

This can be used to control a CS line via a GPIO line, instead of using the controller inner CS logic.

**Public Members**

struct gpio\_dt\_spec gpio

GPIO devicetree specification of CS GPIO.

The device pointer can be set to NULL to fully inhibit CS control if necessary. The GPIO flags GPIO\_ACTIVE\_LOW/_GPIO\_ACTIVE\_HIGH should be equivalent to SPI\_CS\_ACTIVE\_HIGH/SPI\_CS\_ACTIVE\_LOW options in struct `spi\_config`.

```
#include <spi.h> SPI controller configuration structure.
```

```
uint32\_t delay
```

Delay in microseconds to wait before starting the transmission and before releasing the CS line.

struct spi\_config

```
Public Members

uint32_t frequency
   Bus frequency in Hertz.

spi_operation_t operation
   Operation flags.
   It is a bit field with the following parts:

   • 0: Master or slave.
   • 1..3: Polarity, phase and loop mode.
   • 4: LSB or MSB first.
   • 5..10: Size of a data frame in bits.
   • 11: Full/half duplex.
   • 12: Hold on the CS line if possible.
   • 13: Keep resource locked for the caller.
   • 14: Active high CS logic.
   • 15: Motorola or TI frame format (optional).
   If CONFIG_SPI_EXTENDED_MODES is enabled:

   • 16..17: MISO lines (Single/Dual/Quad/Octal).
   • 18..31: Reserved for future use.

uint16_t slave
   Slave number from 0 to host controller slave limit.

struct spi_cs_control cs
   GPIO chip-select line (optional, must be initialized to zero if not used).

struct spi_dt_spec
   #include <spi.h> Complete SPI DT information.

Public Members

const struct device *bus
   SPI bus.

struct spi_config config
   Slave specific configuration.

struct spi_buf
   #include <spi.h> SPI buffer structure.

Public Members

void *buf
   Valid pointer to a data buffer, or NULL otherwise.
size_t len
Length of the buffer buf.
If buf is NULL, length which as to be sent as dummy bytes (as TX buffer) or the
length of bytes that should be skipped (as RX buffer).

struct spi_buf_set
#include <spi.h> SPI buffer array structure.

Public Members

const struct spi_buf *buffers
Pointer to an array of spi_buf, or NULL.

size_t count
Length of the array pointed by buffers.

struct spi_driver_api
#include <spi.h> SPI driver API This is the mandatory API any SPI driver needs to ex-
pose.

7.6.45 System Management Bus (SMBus)

Overview
System Management Bus (SMBus) is derived from I2C for communication with devices on the
motherboard. A system may use SMBus to communicate with the peripherals on the mother-
board without using dedicated control lines. SMBus peripherals can provide various manufac-
turer information, report errors, accept control parameters, etc.

Devices on the bus can operate in three roles: as a Controller that initiates transactions and
controls the clock, a Peripheral that responds to transaction commands, or a Host, which is a
specialized Controller, that provides the main interface to the system's CPU. Zephyr has API for
the Controller role.

SMBus peripheral devices can initiate communication with Controller with two methods:

- **Host Notify protocol:** Peripheral device that supports the Host Notify protocol behaves as
  a Controller to perform the notification. It writes a three-bytes message to a special address
  “SMBus Host (0x08)” with own address and two bytes of relevant data.

- **SMBALERT# signal:** Peripheral device uses special signal SMBALERT# to request attention
  from the Controller. The Controller needs to read one byte from the special “SMBus Alert
  Response Address (ARA) (0x0c)”. The peripheral device responds with a data byte contain-
  ing its own address.
Currently, the API is based on SMBus Specification version 2.0

Note: See Rule A.2: Inclusive Language for information about the terminology used in this API.

SMBus Controller API

Zephyr's SMBus controller API is used when an SMBus device controls the bus, particularly the start and stop conditions and the clock. This is the most common mode used to interact with SMBus peripherals.

Configuration Options

Related configuration options:

- CONFIG_SMBUS

API Reference

Related code samples

SMBus shell

Interact with SMBus peripherals using shell commands.

```c
group smbus_interface

SMBus Interface.

SMBus read / write direction

enum smbus_direction
    SMBus read / write direction.
    Values:

   enumerator SMBUS_MSG_WRITE = 0
    Write a message to SMBus peripheral.

   enumerator SMBUS_MSG_READ = 1
    Read a message from SMBus peripheral.

SMBus Protocol commands

SMBus Specification defines the following SMBus protocols operations
```
SMBUS_CMD_QUICK

SMBus Quick protocol is a very simple command with no data sent or received. Peripheral may denote only R/W bit, which can still be used for the peripheral management, for example to switch peripheral On/Off. Quick protocol can also be used for peripheral devices scanning.

SMBUS_CMD_BYTE

SMBus Byte protocol can send or receive one byte of data.

SMBUS_CMD_BYTE_DATA

SMBus Byte Data protocol sends the first byte (command) followed by read or write one byte.

SMBUS_CMD_WORD_DATA

SMBus Word Data protocol sends the first byte (command) followed by read or write two bytes.
Word Data Write

0 1 2 3 4 5 6 7 8 9 0 1 2 3 4 5 6 7
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+
|S| Periph Addr |W|A| Command code |A| Data Write Low|A|
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+
| Data Write Hi |A|P|
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+

Word Data Read

0 1 2 3 4 5 6 7 8 9 0 1 2 3 4 5 6 7
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+
|S| Periph Addr |W|A| Command code |A|S| Periph Addr |R|
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+
|A| Data Read Low |A| Data Read Hi |N|P|
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+

**SMBUS_CMD_PROC_CALL**

SMBus Process Call protocol is Write Word followed by Read Word.

It is named so because the command sends data and waits for the peripheral to return a reply.

SMBus Block protocol reads or writes a block of data up to 32 bytes.

The Count byte specifies the amount of data.

**SMBUS_CMD_BLOCK**

SMBus Block Write

0 1 2 3 4 5 6 7 8 9 0 1 2 3 4 5 6 7
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+
|S| Periph Addr |W|A| Command code |A| Send Count=N |A|
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+
| Data Write 1 |A| ... |A| Data Write N |A|P|
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+

SMBus Block Read

0 1 2 3 4 5 6 7 8 9 0 1 2 3 4 5 6 7
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+
|S| Periph Addr |W|A| Command code |A|S| Periph Addr |R|
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+
|A| Recv Count=N |A| Data Read 1 |A| ... |A|
+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+-+

(continues on next page)
SMBUS_CMD_BLOCK_PROC

SMBus Block Write - Block Read Process Call protocol is Block Write followed by Block Read.

<table>
<thead>
<tr>
<th>Data Read N</th>
<th>N</th>
<th>P</th>
</tr>
</thead>
</table>

SMBus device functionality

The following parameters describe the functionality of the SMBus device

**SMBUS_MODE_CONTROLLER**

Peripheral to act as Controller.

**SMBUS_MODE_PEC**


**SMBUS_MODE_HOST_NOTIFY**

Support Host Notify functionality.

**SMBUS_MODE_SMBALERT**

Support SMBALERT signal functionality.

SMBus special reserved addresses

The following addresses are reserved by SMBus specification

**SMBUS_ADDRESS_ARA**

Alert Response Address (ARA)

A broadcast address used by the system host as part of the Alert Response Protocol.

Defines

**SMBUS_BLOCK_BYTES_MAX**

Maximum number of bytes in SMBus Block protocol.
Zephyr Project Documentation, Release 3.6.0-rc3

SMBUS_DT_SPEC_GET(node_id)
Structure initializer for `smbus_dt_spec` from devicetree.

This helper macro expands to a static initializer for a `struct smbus_dt_spec` by reading
the relevant bus and address data from the devicetree.

**Parameters**
- **node_id** – Devicetree node identifier for the SMBus device whose `smbus_dt_spec` to create an initializer for

SMBUS_DT_SPEC_INST_GET(inst)
Structure initializer for `smbus_dt_spec` from devicetree instance.

This is equivalent to `SMBUS_DT_SPEC_GET(DT_DRV_INST(inst))`.

**Parameters**
- **inst** – Devicetree instance number

SMBUS_DEVICE_DT_DEFINE(node_id, init_fn, pm_device, data_ptr, cfg_ptr, level, prio, api_ptr, ...
Like `DEVICE_DT_DEFINE()` with SMBus specifics.

Defines a device which implements the SMBus API. May generate a custom `device_state` container struct and init_fn wrapper when needed depending on SMBus `CONFIG_SMBUS_STATS`.

**Parameters**
- **node_id** – The devicetree node identifier.
- **init_fn** – Name of the init function of the driver.
- **pm_device** – PM device resources reference (NULL if device does not use PM).
- **data_ptr** – Pointer to the device’s private data.
- **cfg_ptr** – The address to the structure containing the configuration information for this instance of the driver.
- **level** – The initialization level. See SYS_INIT() for details.
- **prio** – Priority within the selected initialization level. See SYS_INIT() for details.
- **api_ptr** – Provides an initial pointer to the API function struct used by the driver. Can be NULL.

SMBUS_DEVICE_DT_INST_DEFINE(inst, ...
Like `SMBUS_DEVICE_DT_DEFINE()` for an instance of a DT_DRV_COMPAT compatible.

**Parameters**
- **inst** – instance number. This is replaced by `DT_DRV_COMPAT(inst)` in the call to `SMBUS_DEVICE_DT_DEFINE()`.
- **...** – other parameters as expected by `SMBUS_DEVICE_DT_DEFINE()`.

**Typedefs**

typedef void (*smbus_callback_handler_t)(const struct `device *dev, struct smbus_callback *cb, uint8_t addr)
Define SMBus callback handler function signature.
**Param dev**  
Pointer to the device structure for the SMBus driver instance.

**Param cb**  
Structure `smbus_callback` owning this handler.

**Param addr**  
Address of the SMBus peripheral device.

### Functions

```c
static inline void smbus_xfer_stats(const struct device *dev, uint8_t sent, uint8_t recv)  
Updates the SMBus stats.
```

**Parameters**

- `dev` – Pointer to the device structure for the SMBus driver instance to update stats for.
- `sent` – Number of bytes sent
- `recv` – Number of bytes received

```c
int smbus_configure(const struct device *dev, uint32_t dev_config)  
Configure operation of a SMBus host controller.
```

**Parameters**

- `dev` – Pointer to the device structure for the SMBus driver instance.
- `dev_config` – Bit-packed 32-bit value to the device runtime configuration for the SMBus controller.

**Return values**

- `0` – If successful.
- `-EIO` – General input / output error.

```c
int smbus_get_config(const struct device *dev, uint32_t *dev_config)  
Get configuration of a SMBus host controller.
```

This routine provides a way to get current configuration. It is allowed to call the function before `smbus_configure`, because some SMBus ports can be configured during init process. However, if the SMBus port is not configured, `smbus_get_config` returns an error.

`smbus_get_config` can return cached config or probe hardware, but it has to be up to date with current configuration.

**Parameters**

- `dev` – Pointer to the device structure for the SMBus driver instance.
- `dev_config` – Pointer to return bit-packed 32-bit value of the SMBus controller configuration.

**Return values**

- `0` – If successful.
- `-EIO` – General input / output error.
- `-ENOSYS` – If function `smbus_get_config()` is not implemented by the driver.
static inline int smbus_smbalert_set_cb(const struct device *dev, struct smbus_callback *cb)

Add SMBUSALERT callback for a SMBus host controller.

**Parameters**

- `dev` – Pointer to the device structure for the SMBus driver instance.
- `cb` – Pointer to a callback structure.

**Return values**

- `0` – If successful.
- `EIO` – General input / output error.
- `ENOSYS` – If function `smbus_smbalert_set_cb()` is not implemented by the driver.

int smbus_smbalert_remove_cb(const struct device *dev, struct smbus_callback *cb)

Remove SMBUSALERT callback from a SMBus host controller.

**Parameters**

- `dev` – Pointer to the device structure for the SMBus driver instance.
- `cb` – Pointer to a callback structure.

**Return values**

- `0` – If successful.
- `EIO` – General input / output error.
- `ENOSYS` – If function `smbus_smbalert_remove_cb()` is not implemented by the driver.

static inline int smbus_host_notify_set_cb(const struct device *dev, struct smbus_callback *cb)

Add Host Notify callback for a SMBus host controller.

**Parameters**

- `dev` – Pointer to the device structure for the SMBus driver instance.
- `cb` – Pointer to a callback structure.

**Return values**

- `0` – If successful.
- `EIO` – General input / output error.
- `ENOSYS` – If function `smbus_host_notify_set_cb()` is not implemented by the driver.

int smbus_host_notify_remove_cb(const struct device *dev, struct smbus_callback *cb)

Remove Host Notify callback from a SMBus host controller.

**Parameters**

- `dev` – Pointer to the device structure for the SMBus driver instance.
- `cb` – Pointer to a callback structure.

**Return values**

- `0` – If successful.
- `EIO` – General input / output error.
- `ENOSYS` – If function `smbus_host_notify_remove_cb()` is not implemented by the driver.
int smbus_quick(const struct device *dev, uint16_t addr, enum smbus_direction direction)

Perform SMBus Quick operation.

This routine provides a generic interface to perform SMBus Quick operation.

**Parameters**

- **dev** – Pointer to the device structure for the SMBus driver instance. Driver configured in controller mode.
- **addr** – Address of the SMBus peripheral device.
- **direction** – Direction Read or Write.

**Return values**

- **0** – If successful.
- **-EIO** – General input / output error.
- **-ENOSYS** – If function `smbus_quick()` is not implemented by the driver.

int smbus_byte_write(const struct device *dev, uint16_t addr, uint8_t byte)

Perform SMBus Byte Write operation.

This routine provides a generic interface to perform SMBus Byte Write operation.

**Parameters**

- **dev** – Pointer to the device structure for the SMBus driver instance.
- **addr** – Address of the SMBus peripheral device.
- **byte** – Byte to be sent to the peripheral device.

**Return values**

- **0** – If successful.
- **-EIO** – General input / output error.
- **-ENOSYS** – If function `smbus_byte_write()` is not implemented by the driver.

int smbus_byte_read(const struct device *dev, uint16_t addr, uint8_t *byte)

Perform SMBus Byte Read operation.

This routine provides a generic interface to perform SMBus Byte Read operation.

**Parameters**

- **dev** – Pointer to the device structure for the SMBus driver instance.
- **addr** – Address of the SMBus peripheral device.
- **byte** – Byte received from the peripheral device.

**Return values**

- **0** – If successful.
- **-EIO** – General input / output error.
- **-ENOSYS** – If function `smbus_byte_read()` is not implemented by the driver.

int smbus_byte_data_write(const struct device *dev, uint16_t addr, uint8_t cmd, uint8_t byte)

Perform SMBus Byte Data Write operation.

This routine provides a generic interface to perform SMBus Byte Data Write operation.

**Parameters**

- **dev** – Pointer to the device structure for the SMBus driver instance.
• `addr` – Address of the SMBus peripheral device.
• `cmd` – Command byte which is sent to peripheral device first.
• `byte` – Byte to be sent to the peripheral device.

**Return values**
• `0` – If successful.
• `-EIO` – General input / output error.
• `-ENOSYS` – If function `smbus_byte_data_write()` is not implemented by the driver.

```c
int smbus_byte_data_read(const struct device *dev, uint16_t addr, uint8_t cmd, uint8_t *byte)
```

Perform SMBus Byte Data Read operation.

This routine provides a generic interface to perform SMBus Byte Data Read operation.

**Parameters**
• `dev` – Pointer to the device structure for the SMBus driver instance.
• `addr` – Address of the SMBus peripheral device.
• `cmd` – Command byte which is sent to peripheral device first.
• `byte` – Byte received from the peripheral device.

**Return values**
• `0` – If successful.
• `-EIO` – General input / output error.
• `-ENOSYS` – If function `smbus_byte_data_read()` is not implemented by the driver.

```c
int smbus_word_data_write(const struct device *dev, uint16_t addr, uint8_t cmd, uint16_t word)
```

Perform SMBus Word Data Write operation.

This routine provides a generic interface to perform SMBus Word Data Write operation.

**Parameters**
• `dev` – Pointer to the device structure for the SMBus driver instance.
• `addr` – Address of the SMBus peripheral device.
• `cmd` – Command byte which is sent to peripheral device first.
• `word` – Word (16-bit) to be sent to the peripheral device.

**Return values**
• `0` – If successful.
• `-EIO` – General input / output error.
• `-ENOSYS` – If function `smbus_word_data_write()` is not implemented by the driver.

```c
int smbus_word_data_read(const struct device *dev, uint16_t addr, uint8_t cmd, uint16_t *word)
```

Perform SMBus Word Data Read operation.

This routine provides a generic interface to perform SMBus Word Data Read operation.

**Parameters**
• dev – Pointer to the device structure for the SMBus driver instance.
• addr – Address of the SMBus peripheral device.
• cmd – Command byte which is sent to peripheral device first.
• word – Word (16-bit) received from the peripheral device.

Return values
• 0 – If successful.
• -EIO – General input / output error.
• -ENOSYS – If function smbus_word_data_read() is not implemented by the driver.

int smbus_pcall(const struct device *dev, uint16_t addr, uint8_t cmd, uint16_t send_word, uint16_t *recv_word)

Perform SMBus Process Call operation.

This routine provides a generic interface to perform SMBus Process Call operation, which means Write 2 bytes following by Read 2 bytes.

Parameters
• dev – Pointer to the device structure for the SMBus driver instance.
• addr – Address of the SMBus peripheral device.
• cmd – Command byte which is sent to peripheral device first.
• send_word – Word (16-bit) to be sent to the peripheral device.
• recv_word – Word (16-bit) received from the peripheral device.

Return values
• 0 – If successful.
• -EIO – General input / output error.
• -ENOSYS – If function smbus_pcall() is not implemented by the driver.

int smbus_block_write(const struct device *dev, uint16_t addr, uint8_t cmd, uint8_t count, uint8_t *buf)

Perform SMBus Block Write operation.

This routine provides a generic interface to perform SMBus Block Write operation.

Parameters
• dev – Pointer to the device structure for the SMBus driver instance.
• addr – Address of the SMBus peripheral device.
• cmd – Command byte which is sent to peripheral device first.
• count – Size of the data block buffer. Maximum 32 bytes.
• buf – Data block buffer to be sent to the peripheral device.

Return values
• 0 – If successful.
• -EIO – General input / output error.
• -ENOSYS – If function smbus_block_write() is not implemented by the driver.
int smbus_block_read(const struct device *dev, uint16_t addr, uint8_t cmd, uint8_t *count, uint8_t *buf)

Perform SMBus Block Read operation.

This routine provides a generic interface to perform SMBus Block Read operation.

**Parameters**

- **dev** – Pointer to the device structure for the SMBus driver instance.
- **addr** – Address of the SMBus peripheral device.
- **cmd** – Command byte which is sent to peripheral device first.
- **count** – Size of the data peripheral sent. Maximum 32 bytes.
- **buf** – Data block buffer received from the peripheral device.

**Return values**

- 0 – If successful.
- -EIO – General input / output error.
- -ENOSYS – If function `smbus_block_read()` is not implemented by the driver.

int smbus_block_pcall(const struct device *dev, uint16_t addr, uint8_t cmd, uint8_t snd_count, uint8_t *snd_buf, uint8_t *rcv_count, uint8_t *rcv_buf)

Perform SMBus Block Process Call operation.

This routine provides a generic interface to perform SMBus Block Process Call operation. This operation is basically Block Write followed by Block Read.

**Parameters**

- **dev** – Pointer to the device structure for the SMBus driver instance.
- **addr** – Address of the SMBus peripheral device.
- **cmd** – Command byte which is sent to peripheral device first.
- **snd_count** – Size of the data block buffer to send.
- **snd_buf** – Data block buffer send to the peripheral device.
- **rcv_count** – Size of the data peripheral sent.
- **rcv_buf** – Data block buffer received from the peripheral device.

**Return values**

- 0 – If successful.
- -EIO – General input / output error.
- -ENOSYS – If function `smbus_block_pcall()` is not implemented by the driver.

**Note:** Such struct should not be allocated on stack.
Public Members

sys_snodet node
This should be used in driver for a callback list management.

smbus_callback_handler_t handler
Actual callback function being called when relevant.

uint8_t addr
Peripheral device address.

struct smbus_dt_spec
#include <smbus.h> Complete SMBus DT information.

Public Members

const struct device *bus
SMBus bus.

uint16_t addr
Address of the SMBus peripheral device.

7.6.46 Universal Asynchronous Receiver-Transmitter (UART)

Overview

Zephyr provides three different ways to access the UART peripheral. Depending on the method, different API functions are used according to below sections:

1. Polling API
2. Interrupt-driven API
3. Asynchronous API using Direct Memory Access (DMA)

Polling is the most basic method to access the UART peripheral. The reading function, uart_poll_in, is a non-blocking function and returns a character or -1 when no valid data is available. The writing function, uart_poll_out, is a blocking function and the thread waits until the given character is sent.

With the Interrupt-driven API, possibly slow communication can happen in the background while the thread continues with other tasks. The Kernel's Data Passing features can be used to communicate between the thread and the UART driver.

The Asynchronous API allows to read and write data in the background using DMA without interrupting the MCU at all. However, the setup is more complex than the other methods.

Warning: Interrupt-driven API and the Asynchronous API should NOT be used at the same time for the same hardware peripheral, since both APIs require hardware interrupts to function properly. Using the callbacks for both APIs would result in interference between each other. CONFIG_UART_EXCLUSIVE_API_CALLBACKS is enabled by default so that only the callbacks associated with one API is active at a time.
**Configuration Options**

Most importantly, the Kconfig options define whether the polling API (default), the interrupt-driven API or the asynchronous API can be used. Only enable the features you need in order to minimize memory footprint.

Related configuration options:

- `CONFIG_SERIAL`
- `CONFIG_UART_INTERRUPT_DRIVEN`
- `CONFIG_UART_ASYNC_API`
- `CONFIG_UART_WIDE_DATA`
- `CONFIG_UART_USE_RUNTIME_CONFIGURE`
- `CONFIG_UART_LINE_CTRL`
- `CONFIG_UART_DRV_CMD`

**API Reference**

**Related code samples**

**802.15.4 "serial-radio"**
Implement a slip-radio device for Contiki-based border routers.

**Console over USB CDC ACM**
Output "Hello World!" to the console over USB CDC ACM.

**Native TTY UART**
Use native TTY driver to send and receive data between two UART-to-USB bridge dongles.

**STM32 single-wire UART**
Use single-wire/half-duplex UART functionality of STM32 devices.

**UART Passthrough**
Pass data directly between the console and another UART interface.

**UART echo**
Read data from the console and echo it back.

---

**group uart_interface**
UART Interface.

**Enums**

enum uart_line_ctrl
    Line control signals.
    Values:
    
    enumerator UART_LINE_CTRL_BAUD_RATE = BIT(0)
    Baud rate.
enumerator UART_LINE_CTRL_RTS = BIT(1)
    Request To Send (RTS)

enumerator UART_LINE_CTRL_DTR = BIT(2)
    Data Terminal Ready (DTR)

enumerator UART_LINE_CTRL_DCD = BIT(3)
    Data Carrier Detect (DCD)

enumerator UART_LINE_CTRL_DSR = BIT(4)
    Data Set Ready (DSR)

enum uart_rx_stop_reason
    Reception stop reasons.
    Values that correspond to events or errors responsible for stopping receiving.
    Values:

enumerator UART_ERROR_OVERRUN = (1 « 0)
    Overrun error.

enumerator UART_ERROR_PARITY = (1 « 1)
    Parity error.

enumerator UART_ERROR_FRAMING = (1 « 2)
    Framing error.

enumerator UART_BREAK = (1 « 3)
    Break interrupt.
    A break interrupt was received. This happens when the serial input is held at a logic '0' state for longer than the sum of start time + data bits + parity + stop bits.

enumerator UART_ERROR_COLLISION = (1 « 4)
    Collision error.
    This error is raised when transmitted data does not match received data. Typically this is useful in scenarios where the TX and RX lines maybe connected together such as RS-485 half-duplex. This error is only valid on UARTs that support collision checking.

enumerator UART_ERROR_NOISE = (1 « 5)
    Noise error.

eenum uart_config_parity
    Parity modes.
    Values:

enumerator UART_CFG_PARITY_NONE
    No parity.
enumerator UART_CFG_PARITY_ODD
   Odd parity.

enumerator UART_CFG_PARITY_EVEN
   Even parity.

enumerator UART_CFG_PARITY_MARK
   Mark parity.

enumerator UART_CFG_PARITY_SPACE
   Space parity.

enum uart_config_stop_bits
   Number of stop bits.
   Values:

   enumerator UART_CFG_STOP_BITS_0_5
      0.5 stop bit

   enumerator UART_CFG_STOP_BITS_1
      1 stop bit

   enumerator UART_CFG_STOP_BITS_1_5
      1.5 stop bits

   enumerator UART_CFG_STOP_BITS_2
      2 stop bits

enum uart_config_data_bits
   Number of data bits.
   Values:

   enumerator UART_CFG_DATA_BITS_5
      5 data bits

   enumerator UART_CFG_DATA_BITS_6
      6 data bits

   enumerator UART_CFG_DATA_BITS_7
      7 data bits

   enumerator UART_CFG_DATA_BITS_8
      8 data bits

   enumerator UART_CFG_DATA_BITS_9
      9 data bits
enum uart_config_flow_control

Hardware flow control options.

With flow control set to none, any operations related to flow control signals can be managed by user with uart_line_ctrl functions. In other cases, flow control is managed by hardware/driver.

Values:

enumerator UART_CFG_FLOW_CTRL_NONE
    No flow control.

enumerator UART_CFG_FLOW_CTRL_RTS_CTS
    RTS/CTS flow control.

enumerator UART_CFG_FLOW_CTRL_DTR_DSR
    DTR/DSR flow control.

enumerator UART_CFG_FLOW_CTRL_RS485
    RS485 flow control.

Functions

int uart_err_check(const struct device *dev)

Check whether an error was detected.

Parameters

• dev – UART device instance.

Return values

• 0 – If no error was detected.
• err – Error flags as defined in uart_rx_stop_reason
• -ENOSYS – If not implemented.

int uart_configure(const struct device *dev, const struct uart_config *cfg)

Set UART configuration.

Sets UART configuration using data from *cfg.

Parameters

• dev – UART device instance.
• cfg – UART configuration structure.

Return values

• 0 – If successful.
• -errno – Negative errno code in case of failure.
• -ENOSYS – If configuration is not supported by device or driver does not support setting configuration in runtime.
• -ENOTSUP – If API is not enabled.
int uart_config_get(const struct device *dev, struct uart_config *cfg)
Get UART configuration.
Stores current UART configuration to *cfg, can be used to retrieve initial configuration after device was initialized using data from DTS.

Parameters
• dev – UART device instance.
• cfg – UART configuration structure.

Return values
• 0 – If successful.
• -errno – Negative errno code in case of failure.
• -ENOSYS – If driver does not support getting current configuration.
• -ENOTSUP – If API is not enabled.

int uart_line_ctrl_set(const struct device *dev, uint32_t ctrl, uint32_t val)
Manipulate line control for UART.

Parameters
• dev – UART device instance.
• ctrl – The line control to manipulate (see enum uart_line_ctrl).
• val – Value to set to the line control.

Return values
• 0 – If successful.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.
• -errno – Other negative errno value in case of failure.

int uart_line_ctrl_get(const struct device *dev, uint32_t ctrl, uint32_t *val)
Retrieve line control for UART.

Parameters
• dev – UART device instance.
• ctrl – The line control to retrieve (see enum uart_line_ctrl).
• val – Pointer to variable where to store the line control value.

Return values
• 0 – If successful.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.
• -errno – Other negative errno value in case of failure.

int uart_drv_cmd(const struct device *dev, uint32_t cmd, uint32_t p)
Send extra command to driver.
Implementation and accepted commands are driver specific. Refer to the drivers for more information.

Parameters
• dev – UART device instance.
- cmd – Command to driver.
- p – Parameter to the command.

**Return values**
- 0 – If successful.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.
- -errno – Other negative errno value in case of failure.

```c
#include <uart.h> UART controller configuration structure.

**Public Members**

```c
uint32_t baudrate
    Baudrate setting in bps.

uint8_t parity
    Parity bit, use uart_config_parity.

uint8_t stop_bits
    Stop bits, use uart_config_stop_bits.

uint8_t data_bits
    Data bits, use uart_config_data_bits.

uint8_t flow_ctrl
    Flow control setting, use uart_config_flow_control.
```

**Polling API**

```c
struct uart_config

group uart_polling
```

**Functions**

```c
int uart_poll_in(const struct device *dev, unsigned char *p_char)
    Read a character from the device for input.

This routine checks if the receiver has valid data. When the receiver has valid data, it reads a character from the device, stores to the location pointed to by p_char, and returns 0 to the calling thread. It returns -1, otherwise. This function is a non-blocking call.

**Parameters**
- dev – UART device instance.
- p_char – Pointer to character.

**Return values**
- 0 – If a character arrived.
• -1 – If no character was available to read (i.e. the UART input buffer was empty).
• -ENOSYS – If the operation is not implemented.
• -EBUSY – If async reception was enabled using `uart_rx_enable`

```c
int uart_poll_in_u16(const struct device *dev, uint16_t *p_u16)
```

Read a 16-bit datum from the device for input.

This routine checks if the receiver has valid data. When the receiver has valid data, it reads a 16-bit datum from the device, stores to the location pointed to by `p_u16`, and returns 0 to the calling thread. It returns -1, otherwise. This function is a non-blocking call.

**Parameters**

- `dev` – UART device instance.
- `p_u16` – Pointer to 16-bit data.

**Return values**

- 0 – If data arrived.
- -1 – If no data was available to read (i.e., the UART input buffer was empty).
- -ENOTSUP – If API is not enabled.
- -ENOSYS – If the function is not implemented.
- -EBUSY – If async reception was enabled using `uart_rx_enable`

```c
void uart_poll_out(const struct device *dev, unsigned char out_char)
```

Write a character to the device for output.

This routine checks if the transmitter is full. When the transmitter is not full, it writes a character to the data register. It waits and blocks the calling thread, otherwise. This function is a blocking call.

To send a character when hardware flow control is enabled, the handshake signal CTS must be asserted.

**Parameters**

- `dev` – UART device instance.
- `out_char` – Character to send.

```c
void uart_poll_out_u16(const struct device *dev, uint16_t out_u16)
```

Write a 16-bit datum to the device for output.

This routine checks if the transmitter is full. When the transmitter is not full, it writes a 16-bit datum to the data register. It waits and blocks the calling thread, otherwise. This function is a blocking call.

To send a datum when hardware flow control is enabled, the handshake signal CTS must be asserted.

**Parameters**

- `dev` – UART device instance.
- `out_u16` – Wide data to send.

**Interrupt-driven API**

**group uart_interrupt**
**Typedefs**

typedef void (*uart_irq_callback_user_data_t)(const struct device *dev, void *user_data)

Define the application callback function signature for `uart_irq_callback_user_data_set()` function.

**Param dev**
UART device instance.

**Param user_data**
Arbitrary user data.

typedef void (*uart_irq_config_func_t)(const struct device *dev)

For configuring IRQ on each individual UART device.

**Param dev**
UART device instance.

**Functions**

static inline int uart_fifo_fill(const struct device *dev, const uint8_t *tx_data, int size)

Fill FIFO with data.

This function is expected to be called from UART interrupt handler (ISR), if `uart_irq_tx_ready()` returns true. Result of calling this function not from an ISR is undefined (hardware-dependent). Likewise, *not* calling this function from an ISR if `uart_irq_tx_ready()` returns true may lead to undefined behavior, e.g. infinite interrupt loops. It's mandatory to test return value of this function, as different hardware has different FIFO depth (oftentimes just 1).

**Parameters**

- `dev` – UART device instance.
- `tx_data` – Data to transmit.
- `size` – Number of bytes to send.

**Return values**

- `-ENOSYS` – if this function is not supported
- `-ENOTSUP` – If API is not enabled.

**Returns**
Number of bytes sent.

static inline int uart_fifo_fill_u16(const struct device *dev, const uint16_t *tx_data, int size)

Fill FIFO with wide data.

This function is expected to be called from UART interrupt handler (ISR), if `uart_irq_tx_ready()` returns true. Result of calling this function not from an ISR is undefined (hardware-dependent). Likewise, *not* calling this function from an ISR if `uart_irq_tx_ready()` returns true may lead to undefined behavior, e.g. infinite interrupt loops. It's mandatory to test return value of this function, as different hardware has different FIFO depth (oftentimes just 1).

**Parameters**

- `dev` – UART device instance.
- `tx_data` – Wide data to transmit.
• size – Number of datum to send.

**Return values**

• -ENOSYS – If this function is not implemented
• -ENOTSUP – If API is not enabled.

**Returns**

Number of datum sent.

```c
static inline int uart_fifo_read(const struct device *dev, uint8_t *rx_data, const int size)
```

Read data from FIFO.

This function is expected to be called from UART interrupt handler (ISR), if `uart_irq_rx_ready()` returns true. Result of calling this function not from an ISR is undefined (hardware-dependent). It’s unspecified whether “RX ready” condition as returned by `uart_irq_rx_ready()` is level- or edge- triggered. That means that once `uart_irq_rx_ready()` is detected, `uart_fifo_read()` must be called until it reads all available data in the FIFO (i.e. until it returns less data than was requested).

**Parameters**

• dev – UART device instance.
• rx_data – Data container.
• size – Container size.

**Return values**

• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.

**Returns**

Number of bytes read.

```c
static inline int uart_fifo_read_u16(const struct device *dev, uint16_t *rx_data, const int size)
```

Read wide data from FIFO.

This function is expected to be called from UART interrupt handler (ISR), if `uart_irq_rx_ready()` returns true. Result of calling this function not from an ISR is undefined (hardware-dependent). It’s unspecified whether “RX ready” condition as returned by `uart_irq_rx_ready()` is level- or edge- triggered. That means that once `uart_irq_rx_ready()` is detected, `uart_fifo_read()` must be called until it reads all available data in the FIFO (i.e. until it returns less data than was requested).

**Parameters**

• dev – UART device instance.
• rx_data – Wide data container.
• size – Container size.

**Return values**

• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.

**Returns**

Number of datum read.

```c
void uart_irq_tx_enable(const struct device *dev)
```

Enable TX interrupt in IER.

**Parameters**
• dev – UART device instance.

void uart_irq_tx_disable(const struct device *dev)
Disable TX interrupt in IER.

Parameters
• dev – UART device instance.

static inline int uart_irq_tx_ready(const struct device *dev)
Check if UART TX buffer can accept a new char.
Check if UART TX buffer can accept at least one character for transmission (i.e. uart_fifo_fill() will succeed and return non-zero). This function must be called in a UART interrupt handler, or its result is undefined. Before calling this function in the interrupt handler, uart_irq_update() must be called once per the handler invocation.

Parameters
• dev – UART device instance.

Return values
• 1 – If TX interrupt is enabled and at least one char can be written to UART.
• 0 – If device is not ready to write a new byte.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.

void uart_irq_rx_enable(const struct device *dev)
Enable RX interrupt.

Parameters
• dev – UART device instance.

void uart_irq_rx_disable(const struct device *dev)
Disable RX interrupt.

Parameters
• dev – UART device instance.

static inline int uart_irq_tx_complete(const struct device *dev)
Check if UART TX block finished transmission.
Check if any outgoing data buffered in UART TX block was fully transmitted and TX block is idle. When this condition is true, UART device (or whole system) can be power off. Note that this function is not useful to check if UART TX can accept more data, use uart_irq_tx_ready() for that. This function must be called in a UART interrupt handler, or its result is undefined. Before calling this function in the interrupt handler, uart_irq_update() must be called once per the handler invocation.

Parameters
• dev – UART device instance.

Return values
• 1 – If nothing remains to be transmitted.
• 0 – If transmission is not completed.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.
static inline int uart_irq_rx_ready(const struct device *dev)
Check if UART RX buffer has a received char.

Check if UART RX buffer has at least one pending character (i.e. uart_fifo_read() will succeed and return non-zero). This function must be called in a UART interrupt handler, or its result is undefined. Before calling this function in the interrupt handler, uart_irq_update() must be called once per the handler invocation. It’s unspecified whether condition as returned by this function is level- or edge- triggered (i.e. if this function returns true when RX FIFO is non-empty, or when a new char was received since last call to it). See description of uart_fifo_read() for implication of this.

Parameters
- dev – UART device instance.

Return values
- 1 – If a received char is ready.
- 0 – If a received char is not ready.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.

void uart_irq_err_enable(const struct device *dev)
Enable error interrupt.

Parameters
- dev – UART device instance.

void uart_irq_err_disable(const struct device *dev)
Disable error interrupt.

Parameters
- dev – UART device instance.

int uart_irq_is_pending(const struct device *dev)
Check if any IRQs is pending.

Parameters
- dev – UART device instance.

Return values
- 1 – If an IRQ is pending.
- 0 – If an IRQ is not pending.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.

int uart_irq_update(const struct device *dev)
Start processing interrupts in ISR.

This function should be called the first thing in the ISR. Calling uart_irq_rx_ready(), uart_irq_tx_ready(), uart_irq_tx_complete() allowed only after this.

The purpose of this function is:

- For devices with auto-acknowledge of interrupt status on register read to cache the value of this register (rx_ready, etc. then use this case).
- For devices with explicit acknowledgment of interrupts, to ack any pending interrupts and likewise to cache the original value.

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• For devices with implicit acknowledgment, this function will be empty. But the ISR must perform the actions needed to ack the interrupts (usually, call `uart_fifo_read()` on `rx_ready`, and `uart_fifo_fill()` on `tx_ready`).

**Parameters**

• `dev` – UART device instance.

**Return values**

• 1 – On success.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.

```c
static inline int uart_irq_callback_user_data_set(const struct device *dev, uart_irq_callback_user_data_t cb, void *user_data)
```

Set the IRQ callback function pointer.

This sets up the callback for IRQ. When an IRQ is triggered, the specified function will be called with specified user data. See description of `uart_irq_update()` for the requirements on ISR.

**Parameters**

• `dev` – UART device instance.
• `cb` – Pointer to the callback function.
• `user_data` – Data to pass to callback function.

**Return values**

• 0 – On success.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.

```c
static inline int uart_irq_callback_set(const struct device *dev, uart_irq_callback_user_data_t cb)
```

Set the IRQ callback function pointer (legacy).

This sets up the callback for IRQ. When an IRQ is triggered, the specified function will be called with the device pointer.

**Parameters**

• `dev` – UART device instance.
• `cb` – Pointer to the callback function.

**Return values**

• 0 – On success.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.

```c
Asynchronous API
group uart_async
```
**Typedefs**

```c
typedef void (*uart_callback_t)(const struct device *dev, struct uart_event *evt, void *user_data)
```

Define the application callback function signature for `uart_callback_set()` function.

**Param dev**
UART device instance.

**Param evt**
Pointer to `uart_event` instance.

**Param user_data**
Pointer to data specified by user.

** Enums**

```c
enum uart_event_type
```

Types of events passed to callback in UART_ASYNC_API.

**Receiving:**

a. To start receiving, `uart_rx_enable` has to be called with first buffer

b. When receiving starts to current buffer, `UART_RX_BUF_REQUEST` will be generated, in response to that user can either:
   
   i. Provide second buffer using `uart_rx_buf_rsp`, when first buffer is filled, receiving will automatically start to second buffer.
   
   ii. Ignore the event, this way when current buffer is filled `UART_RX_RDY` event will be generated and receiving will be stopped.

c. If some data was received and timeout occurred `UART_RX_RDY` event will be generated. It can happen multiples times for the same buffer. RX timeout is counted from last byte received i.e. if no data was received, there won’t be any timeout event.

d. `UART_RX_BUF_RELEASED` event will be generated when the current buffer is no longer used by the driver. It will immediately follow `UART_RX_RDY` event. Depending on the implementation buffer may be released when it is completely or partially filled.

e. If there was second buffer provided, it will become current buffer and we start again at point 2. If no second buffer was specified receiving is stopped and `UART_RX_DISABLED` event is generated. After that whole process can be repeated.

Any time during reception `UART_RX_STOPPED` event can occur. if there is any data received, `UART_RX_RDY` event will be generated. It will be followed by `UART_RX_BUF_RELEASED` event for every buffer currently passed to driver and finally by `UART_RX_DISABLED` event.

Receiving can be disabled using `uart_rx_disable`, after calling that function, if there is any data received, `UART_RX_RDY` event will be generated. `UART_RX_BUF_RELEASED` event will be generated for every buffer currently passed to driver and finally `UART_RX_DISABLED` event will occur.

**Transmitting:**

a. Transmitting starts by `uart_tx` function.

b. If whole buffer was transmitted `UART_TX_DONE` is generated. If timeout occurred `UART_TX_ABORTED` will be generated.
Transmitting can be aborted using `uart_tx_abort`, after calling that function `UART_TX_ABORTED` event will be generated.

**Values:**

enum UART_TX_DONE
  Whole TX buffer was transmitted.

enum UART_TX_ABORTED
  Transmitting aborted due to timeout or `uart_tx_abort` call.

When flow control is enabled, there is a possibility that TX transfer won’t finish in the allotted time. Some data may have been transferred, information about it can be found in event data.

enum UART_RX_RDY
  Received data is ready for processing.

This event is generated in the following cases:
- When RX timeout occurred, and data was stored in provided buffer. This can happen multiple times in the same buffer.
- When provided buffer is full.
- After `uart_rx_disable()`.
- After stopping due to external event (`UART_RX_STOPPED`).

enum UART_RX_BUF_REQUEST
  Driver requests next buffer for continuous reception.

This event is triggered when receiving has started for a new buffer, i.e. it’s time to provide a next buffer for a seamless switchover to it. For continuous reliable receiving, user should provide another RX buffer in response to this event, using `uart_rx_buf_rsp` function.

If `uart_rx_buf_rsp` is not called before current buffer is filled up, receiving will stop.

enum UART_RX_BUF_RELEASED
  Buffer is no longer used by UART driver.

enum UART_RX_DISABLED
  RX has been disabled and can be reenabled.

This event is generated whenever receiver has been stopped, disabled or finished its operation and can be enabled again using `uart_rx_enable`

enum UART_RX_STOPPED
  RX has stopped due to external event.

Reason is one of `uart_rx_stop_reason`.

**Functions**

```c
static inline int uart_callback_set(const struct device *dev, uart_callback_t callback, void *user_data)
```

Set event handler function.

Since it is mandatory to set callback to use other asynchronous functions, it can be used to detect if the device supports asynchronous API. Remaining API does not have that detection.
Parameters

- `dev` – UART device instance.
- `callback` – Event handler.
- `user_data` – Data to pass to event handler function.

Return values

- `0` – If successful.
- `-ENOSYS` – If not supported by the device.
- `-ENOTSUP` – If API not enabled.

```c
int uart_tx(const struct device *dev, const uint8_t *buf, size_t len, int32_t timeout)
```

Send given number of bytes from buffer through UART.

Function returns immediately and event handler, set using `uart_callback_set`, is called after transfer is finished.

Parameters

- `dev` – UART device instance.
- `buf` – Pointer to transmit buffer.
- `len` – Length of transmit buffer.
- `timeout` – Timeout in microseconds. Valid only if flow control is enabled. `SYS_FOREVER_US` disables timeout.

Return values

- `0` – If successful.
- `-ENOTSUP` – If API is not enabled.
- `-EBUSY` – If there is already an ongoing transfer.
- `-errno` – Other negative `errno` value in case of failure.

```c
int uart_tx_u16(const struct device *dev, const uint16_t *buf, size_t len, int32_t timeout)
```

Send given number of datum from buffer through UART.

Function returns immediately and event handler, set using `uart_callback_set`, is called after transfer is finished.

Parameters

- `dev` – UART device instance.
- `buf` – Pointer to wide data transmit buffer.
- `len` – Length of wide data transmit buffer.
- `timeout` – Timeout in milliseconds. Valid only if flow control is enabled. `SYS_FOREVER_MS` disables timeout.

Return values

- `0` – If successful.
- `-ENOTSUP` – If API is not enabled.
- `-EBUSY` – If there is already an ongoing transfer.
- `-errno` – Other negative `errno` value in case of failure.
int uart_tx_abort(const struct device *dev)
Abort current TX transmission.

UART_TX_DONE event will be generated with amount of data sent.

Parameters
• dev – UART device instance.

Return values
• 0 – If successful.
• -ENOTSUP – If API is not enabled.
• -EFAULT – There is no active transmission.
• -errno – Other negative errno value in case of failure.

int uart_rx_enable(const struct device *dev, uint8_t *buf, size_t len, int32_t timeout)
Start receiving data through UART.

Function sets given buffer as first buffer for receiving and returns immediately. After that event handler, set using uart_callback_set, is called with UART_RX_RDY or UART_RX_BUF_REQUEST events.

Parameters
• dev – UART device instance.
• buf – Pointer to receive buffer.
• len – Buffer length.
• timeout – Inactivity period after receiving at least a byte which triggers UART_RX_RDY event. Given in microseconds. SYS_FOREVER_US disables timeout. See uart_event_type for details.

Return values
• 0 – If successful.
• -ENOTSUP – If API is not enabled.
• -EBUSY – RX already in progress.
• -errno – Other negative errno value in case of failure.

int uart_rx_enable_u16(const struct device *dev, uint16_t *buf, size_t len, int32_t timeout)
Start receiving wide data through UART.

Function sets given buffer as first buffer for receiving and returns immediately. After that event handler, set using uart_callback_set, is called with UART_RX_RDY or UART_RX_BUF_REQUEST events.

Parameters
• dev – UART device instance.
• buf – Pointer to wide data receive buffer.
• len – Buffer length.
• timeout – Inactivity period after receiving at least a byte which triggers UART_RX_RDY event. Given in milliseconds. SYS_FOREVER_MS disables timeout. See uart_event_type for details.

Return values
• 0 – If successful.
• -ENOTSUP – If API is not enabled.
-EBUSY – RX already in progress.
-errno – Other negative errno value in case of failure.

static inline int uart_rx_buf_rsp(const struct device *dev, uint8_t *buf, size_t len)
Provide receive buffer in response to UART_RX_BUF_REQUEST event.
Provide pointer to RX buffer, which will be used when current buffer is filled.

Note: Providing buffer that is already in usage by driver leads to undefined behavior. Buffer can be reused when it has been released by driver.

Parameters
- dev – UART device instance.
- buf – Pointer to receive buffer.
- len – Buffer length.

Return values
- 0 – If successful.
-ENOTSUP – If API is not enabled.
-EBUSY – Next buffer already set.
-EACCES – Receiver is already disabled (function called too late?).
-errno – Other negative errno value in case of failure.

static inline int uart_rx_buf_rsp_u16(const struct device *dev, uint16_t *buf, size_t len)
Provide wide data receive buffer in response to UART_RX_BUF_REQUEST event.
Provide pointer to RX buffer, which will be used when current buffer is filled.

Note: Providing buffer that is already in usage by driver leads to undefined behavior. Buffer can be reused when it has been released by driver.

Parameters
- dev – UART device instance.
- buf – Pointer to wide data receive buffer.
- len – Buffer length.

Return values
- 0 – If successful.
-ENOTSUP – If API is not enabled.
-EBUSY – Next buffer already set.
-EACCES – Receiver is already disabled (function called too late?).
-errno – Other negative errno value in case of failure.
int uart_rx_disable(const struct device *dev)
    Disable RX.

    UART_RX_BUFReleased event will be generated for every buffer scheduled, after that UART_RX_DISABLED event will be generated. Additionally, if there is any pending received data, the UART_RX_RDY event for that data will be generated before the UART_RX_BUFReleased events.

Parameters
- dev – UART device instance.

Return values
- 0 – If successful.
- -ENOTSUP – If API is not enabled.
- -EFAULT – There is no active reception.
- -errno – Other negative errno value in case of failure.

struct uart_event_tx

    #include <uart.h> UART TX event data.

    Public Members

    const uint8_t *buf
    Pointer to current buffer.

    size_t len
    Number of bytes sent.

struct uart_event_rx

    #include <uart.h> UART RX event data.

    The data represented by the event is stored in rx.buf[rx.offset] to rx.buf[rx.offset+rx.len]. That is, the length is relative to the offset.

    Public Members

    uint8_t *buf
    Pointer to current buffer.

    size_t offset
    Currently received data offset in bytes.

    size_t len
    Number of new bytes received.

struct uart_event_rx_buf

    #include <uart.h> UART RX buffer released event data.
Public Members

uint8_t *buf
    Pointer to buffer that is no longer in use.

struct uart_event_rx_stop
#include <uart.h> UART RX stopped data.

Public Members

elem uart_rx_stop_reason reason
    Reason why receiving stopped.

struct uart_event_rx data
    Last received data.

struct uart_event
#include <uart.h> Structure containing information about current event.

Public Members

elem uart_event_type type
    Type of event.

union uart_event_data
    #include <uart.h> Event data.

Public Members

struct uart_event_tx tx
    UART_TX_DONE and UART_TX_ABORTED events data.

struct uart_event_rx rx
    UART_RX_RDY event data.

struct uart_event_rx_buf rx_buf
    UART_RX_BUF_RELEASED event data.

struct uart_event_rx_stop rx_stop
    UART_RX_STOPPED event data.
7.6.47  USB-C VBUS

Overview

USB-C VBUS is the line in a USB Type-C connection that delivers power from a Source to a Sink device.

USB-C VBUS API  The USB-C VBUS device driver presents an API that's used to control and measure VBUS.

Configuration Options

Related configuration options:

• CONFIG_USBC_VBUS_DRIVER

API Reference

group usbc_vbus_api

USB-C VBUS API.

Functions

static inline bool usbc_vbus_check_level(const struct device *dev, enum tc_vbus_level level)

Checks if VBUS is at a particular level.

Parameters

• dev – Runtime device structure
• level – The level voltage to check against

Return values

• true – if VBUS is at the level voltage
• false – if VBUS is not at that level voltage

static inline int usbc_vbus_measure(const struct device *dev, int *meas)

Reads and returns VBUS measured in mV.

Parameters

• dev – Runtime device structure
• meas – pointer where the measured VBUS voltage is stored

Return values

• 0 – on success
• -EIO – on failure

static inline int usbc_vbus_discharge(const struct device *dev, bool enable)

Controls a pin that discharges VBUS.

Parameters

• dev – Runtime device structure
• **enable** – Discharge VBUS when true

### Return values

- 0 – on success
- -EIO – on failure
- -ENOENT – if discharge pin isn’t defined

```c
static inline int usbc_vbus_enable(const struct device *dev, bool enable)
```

Controls a pin that enables VBUS measurements.

### Parameters

- `dev` – Runtime device structure
- `enable` – enable VBUS measurements when true

### Return values

- 0 – on success
- -EIO – on failure
- -ENOENT – if enable pin isn’t defined

```c
struct usbc_vbus_driver_api
#include <usbc_vbus.h>
```

#### 7.6.48 USB Type-C Port Controller (TCPC)

### Overview

**TCPC (USB Type-C Port Controller)** The TCPC is a device used to simplify the implementation of a USB-C system by providing the following three function:

- VBUS and VCONN control **USB Type-C**: The TCPC may provide a Source device, the mechanism to control VBUS sourcing, and a Sink device, the mechanism to control VBUS sinking. A similar mechanism is provided for the control of VCONN.
- CC control and sensing: The TCPC implements logic for controlling the CC pin pull-up and pull-down resistors. It also provides a way to sense and report what resistors are present on the CC pin.
- Power Delivery message reception and transmission **USB Power Delivery**: The TCPC sends and receives messages constructed in the TCPM and places them on the CC lines.

**TCPC API** The TCPC device driver functions as the liaison between the TCPC device and the application software; this is accomplished by the Zephyr’s API provided by the device driver that’s used to communicate with and control the TCPC device.

### Configuration Options

Related configuration options:

- CONFIG_USBC_TCPC_DRIVER
API Reference

group usb_type_c

USB Type-C.

Defines

TC_V_SINK_DISCONNECT_MIN_MV
VBUS minimum for a sink disconnect detection.
See Table 4-3 VBUS Sink Characteristics

TC_V_SINK_DISCONNECT_MAX_MV
VBUS maximum for a sink disconnect detection.
See Table 4-3 VBUS Sink Characteristics

TC_T_VBUS_ON_MAX_MS
From entry to Attached.SRC until VBUS reaches the minimum vSafe5V threshold as measured at the source's receptacle See Table 4-29 VBUS and VCONN Timing Parameters.

TC_T_VBUS_OFF_MAX_MS
From the time the Sink is detached until the Source removes VBUS and reaches vSafe0V (See USB PD).
See Table 4-29 VBUS and VCONN Timing Parameters

TC_T_VCONN_ON_MAX_MS
From the time the Source supplied VBUS in the Attached.SRC state.
See Table 4-29 VBUS and VCONN Timing Parameters

TC_T_VCONN_ON_PA_MAX_MS
From the time a Sink with accessory support enters the PoweredAccessory state until the Sink sources minimum VCONN voltage (see Table 4-5) See Table 4-29 VBUS and VCONN Timing Parameters.

TC_T_VCONN_OFF_MAX_MS
From the time that a Sink is detached or as directed until the VCONN supply is disconnected.
See Table 4-29 VBUS and VCONN Timing Parameters

TC_T_SINK_ADJ_MAX_MS
Response time for a Sink to adjust its current consumption to be in the specified range due to a change in USB Type-C Current advertisement See Table 4-29 VBUS and VCONN Timing Parameters.

TC_T_DRP_MIN_MS
The minimum period a DRP shall complete a Source to Sink and back advertisement See Table 4-30 DRP Timing Parameters.
**TC_T_DRP_MAX_MS**

The maximum period a DRP shall complete a Source to Sink and back advertisement. See Table 4-30 DRP Timing Parameters.

**TC_T_DRP_TRANSITION_MIN_MS**

The minimum time a DRP shall complete transitions between Source and Sink roles during role resolution. See Table 4-30 DRP Timing Parameters.

**TC_T_DRP_TRANSITION_MAX_MS**

The maximum time a DRP shall complete transitions between Source and Sink roles during role resolution. See Table 4-30 DRP Timing Parameters.

**TC_T_DRP_TRY_MIN_MS**

Minimum wait time associated with the Try.SRC state. See Table 4-30 DRP Timing Parameters.

**TC_T_DRP_TRY_MAX_MS**

Maximum wait time associated with the Try.SRC state. See Table 4-30 DRP Timing Parameters.

**TC_T_DRP_TRY_WAIT_MIN_MS**

Minimum wait time associated with the Try.SNK state. See Table 4-30 DRP Timing Parameters.

**TC_T_DRP_TRY_WAIT_MAX_MS**

Maximum wait time associated with the Try.SNK state. See Table 4-30 DRP Timing Parameters.

**TC_T_TRY_TIMEOUT_MIN_MS**

Minimum timeout for transition from Try.SRC to TryWait.SNK. See Table 4-30 DRP Timing Parameters.

**TC_T_TRY_TIMEOUT_MAX_MS**

Maximum timeout for transition from Try.SRC to TryWait.SNK. See Table 4-30 DRP Timing Parameters.

**TC_T_VPD_DETACH_MIN_MS**

Minimum Time for a DRP to detect that the connected Charge-Through VCONNPowered USB Device has been detached, after VBUS has been removed. See Table 4-30 DRP Timing Parameters.

**TC_T_VPD_DETACH_MAX_MS**

Maximum Time for a DRP to detect that the connected Charge-Through VCONNPowered USB Device has been detached, after VBUS has been removed. See Table 4-30 DRP Timing Parameters.
TC_T_CC_DEBOUNCE_MIN_MS
Minimum time a port shall wait before it can determine it is attached. See Table 4-31 CC Timing.

TC_T_CC_DEBOUNCE_MAX_MS
Maximum time a port shall wait before it can determine it is attached. See Table 4-31 CC Timing.

TC_T_PD_DEBOUNCE_MIN_MS
Minimum time a sink port shall wait before it can determine it is detached due to the potential for USB PD signaling on CC as described in the state definitions. See Table 4-31 CC Timing.

TC_T_PD_DEBOUNCE_MAX_MS
Maximum time a sink port shall wait before it can determine it is detached due to the potential for USB PD signaling on CC as described in the state definitions. See Table 4-31 CC Timing.

TC_T_TRY_CC_DEBOUNCE_MIN_MS
Minimum Time a port shall wait before it can determine it is re-attached during the try-wait process. See Table 4-31 CC Timing.

TC_T_TRY_CC_DEBOUNCE_MAX_MS
Maximum Time a port shall wait before it can determine it is re-attached during the try-wait process. See Table 4-31 CC Timing.

TC_T_ERROR_RECOVERY_SELFPOWERED_MIN_MS
Minimum time a self-powered port shall remain in the ErrorRecovery state. See Table 4-31 CC Timing.

TC_T_ERROR_RECOVERY_SOURCE_MIN_MS
Minimum time a source shall remain in the ErrorRecovery state if it was sourcing VCONN in the previous state. See Table 4-31 CC Timing.

TC_T_RP_VALUE_CHANGE_MIN_MS
Minimum time a sink port shall wait before it can determine there has been a change in Rp where CC is not BMC Idle or the port is unable to detect BMC Idle. See Table 4-31 CC Timing.

TC_T_RP_VALUE_CHANGE_MAX_MS
Maximum time a sink port shall wait before it can determine there has been a change in Rp where CC is not BMC Idle or the port is unable to detect BMC Idle. See Table 4-31 CC Timing.
TC_T_SRC_DISCONNECT_MIN_MS
Minimum time a Source shall detect the SRC.Open state.
The Source should detect the SRC.Open state as quickly as practical. See Table 4-31 CC Timing

TC_T_SRC_DISCONNECT_MAX_MS
Maximum time a Source shall detect the SRC.Open state.
The Source should detect the SRC.Open state as quickly as practical. See Table 4-31 CC Timing

TC_T_NO_TOGGLE_CONNECT_MIN_MS
Minimum time to detect connection when neither Port Partner is toggling.
See Table 4-31 CC Timing

TC_T_NO_TOGGLE_CONNECT_MAX_MS
Maximum time to detect connection when neither Port Partner is toggling.
See Table 4-31 CC Timing

TC_T_ONE_PORT_TOGGLE_CONNECT_MIN_MS
Minimum time to detect connection when one Port Partner is toggling 0ms ... dc-SRC.DRP max * tDRP max + 2 * tNoToggleConnect).
See Table 4-31 CC Timing

TC_T_ONE_PORT_TOGGLE_CONNECT_MAX_MS
Maximum time to detect connection when one Port Partner is toggling 0ms ... dc-SRC.DRP max * tDRP max + 2 * tNoToggleConnect).
See Table 4-31 CC Timing

TC_T_TWO_PORT_TOGGLE_CONNECT_MIN_MS
Minimum time to detect connection when both Port Partners are toggling (0ms ... 5 * tDRP max + 2 * tNoToggleConnect).
See Table 4-31 CC Timing

TC_T_TWO_PORT_TOGGLE_CONNECT_MAX_MS
Maximum time to detect connection when both Port Partners are toggling (0ms ... 5 * tDRP max + 2 * tNoToggleConnect).
See Table 4-31 CC Timing

TC_T_VPDCTDD_MIN_US
Minimum time for a Charge-Through VCONN-Powered USB Device to detect that the Charge-Through source has disconnected from CC after VBUS has been removed, transition to CTUnattached.VPD, and re-apply its Rp termination advertising 3.0 A on the host port CC.
See Table 4-31 CC Timing

TC_T_VPDCTDD_MAX_MS
Maximum time for a Charge-Through VCONN-Powered USB Device to detect that the
Charge-Through source has disconnected from CC after VBUS has been removed, transition to CTUnattached.VPD, and re-apply its Rp termination advertising 3.0 A on the host port CC.

See Table 4-31 CC Timing

**TC_T_VPDDISABLE_MIN_MS**
Minimum time for a Charge-Through VCONN-Powered USB Device shall remain in CT-Disabled.VPD state.

See Table 4-31 CC Timing

**Enums**

**enum tc_cc_voltage_state**
CC Voltage status.

*Values:*

- **enumerator TC_CC_VOLT_OPEN = 0**
  No port partner connection.

- **enumerator TC_CC_VOLT_RA = 1**
  Port partner is applying Ra.

- **enumerator TC_CC_VOLT_RD = 2**
  Port partner is applying Rd.

- **enumerator TC_CC_VOLT_RP_DEF = 5**
  Port partner is applying Rp (0.5A)

- **enumerator TC_CC_VOLT_RP_1A5 = 6**

- **enumerator TC_CC_VOLT_RP_3A0 = 7**
  Port partner is applying Rp (3.0A)

**enum tc_vbus_level**
VBUS level voltages.

*Values:*

- **enumerator TC_VBUS_SAFE0V = 0**
  VBUS is less than vSafe0V max.

- **enumerator TC_VBUS_PRESENT = 1**
  VBUS is at least vSafe5V min.

- **enumerator TC_VBUS_REMOVED = 2**
  VBUS is less than vSinkDisconnect max.
enum tc_rp_value
    Pull-Up resistor values.
    Values:

    enumerator TC_RP_USB = 0
        Pull-Up resistor for a current of 900mA.

    enumerator TC_RP_1A5 = 1
        Pull-Up resistor for a current of 1.5A.

    enumerator TC_RP_3A0 = 2
        Pull-Up resistor for a current of 3.0A.

    enumerator TC_RP_RESERVED = 3
        No Pull-Up resistor is applied.

denum tc_cc_pull
    CC pull resistors.
    Values:

    enumerator TC_CC_RA = 0
        Ra Pull-Down resistor.

    enumerator TC_CC_RP = 1
        Rp Pull-Up resistor.

    enumerator TC_CC_RD = 2
        Rd Pull-Down resistor.

    enumerator TC_CC_OPEN = 3
        No CC resistor.

    enumerator TC_RA_RD = 4
        Ra and Rd Pull-Down resistor.

denum tc_cable_plug
    Cable plug.
    See 6.2.1.1.7 Cable Plug. Only applies to SOP’ and SOP”. Replaced by pd_power_role for
    SOP packets.
    Values:

    enumerator PD_PLUG_FROM_DFP_UFP = 0

    enumerator PD_PLUG_FROM_CABLE_VPD = 1

denum tc_power_role
    Power Delivery Power Role.
    Values:
enumerator TC_ROLE_SINK = 0
Power role is a sink.

enumerator TC_ROLE_SOURCE = 1
Power role is a source.

enum tc_data_role
Power Delivery Data Role.
Values:

enumerator TC_ROLE_UFP = 0
Data role is an Upstream Facing Port.

enumerator TC_ROLE_DFP = 1
Data role is a Downstream Facing Port.

enumerator TC_ROLE_DISCONNECTED = 2
Port is disconnected.

enum tc_cc_polarity
Polarity of the CC lines.
Values:

enumerator TC_POLARITY_CC1 = 0
Use CC1 IO for Power Delivery communication.

enumerator TC_POLARITY_CC2 = 1
Use CC2 IO for Power Delivery communication.

enum tc_cc_states
Possible port partner connections based on CC line states.
Values:

enumerator TC_CC_NONE = 0
No port partner attached.

enumerator TC_CC_UFP_NONE = 1
From DFP perspective.
No UFP accessory connected

enumerator TC_CC_UFP_AUDIO_ACC = 2
UFP Audio accessory connected.

enumerator TC_CC_UFP_DEBUG_ACC = 3
UFP Debug accessory connected.

enumerator TC_CC_UFP_ATTACHED = 4
Plain UFP attached.
enumerator TC_CC_DFP_ATTACHED = 5
    From UFP perspective.
    Plain DFP attached

enumerator TC_CC_DFP_DEBUG_ACC = 6
    DFP debug accessory connected.

**group** usb_type_c_port_controller_api
    USB Type-C Port Controller API.

**typedefs**

typedef int (*tcpc_vconn_control_cb_t)(const struct device *dev, enum tc_cc_polarity pol, bool enable)

typedef int (*tcpc_vconn_discharge_cb_t)(const struct device *dev, enum tc_cc_polarity pol, bool enable)

typedef void (*tcpc_alert_handler_cb_t)(const struct device *dev, void *data, enum tcpc_alert alert)

**enums**

enum tcpc_alert
    TCPC Alert bits.
    **Values:**

    enumerator TCPC_ALERT_CC_STATUS
        CC status changed.

    enumerator TCPC_ALERT_POWER_STATUS
        Power status changed.

    enumerator TCPC_ALERT_MSG_STATUS
        Receive Buffer register changed.

    enumerator TCPC_ALERT_HARD_RESET_RECEIVED
        Received Hard Reset message.

    enumerator TCPC_ALERT_TRANSMIT_MSG_FAILED
        SOP* message transmission not successful.

    enumerator TCPC_ALERT_TRANSMIT_MSG_DISCARDED
        Reset or SOP* message transmission not sent due to an incoming receive message.
enumerator TCPC_ALERT_TRANSMIT_MSG_SUCCESS
  Reset or SOP* message transmission successful.

enumerator TCPC_ALERT_VBUS_ALARM_HI
  A high-voltage alarm has occurred.

enumerator TCPC_ALERT_VBUS_ALARM_LO
  A low-voltage alarm has occurred.

enumerator TCPC_ALERT_FAULT_STATUS
  A fault has occurred.
  Read the FAULT_STATUS register

enumerator TCPC_ALERT_RX_BUFFER_OVERFLOW
  TCPC RX buffer has overflowed.

enumerator TCPC_ALERT_VBUS_SNK_DISCONNECT
  The TCPC in Attached.SNK state has detected a sink disconnect.

enumerator TCPC_ALERT_BEGINNING_MSG_STATUS
  Receive buffer register changed.

enumerator TCPC_ALERT_EXTENDED_STATUS
  Extended status changed.

enumerator TCPC_ALERT_EXTENDED
  An extended interrupt event has occurred.
  Read the alert_extended register

enumerator TCPC_ALERT_VENDOR_DEFINED
  A vendor defined alert has been detected.

enum tcpc_status_reg
  TCPC Status register.
  Values:

  enumerator TCPC_CC_STATUS
    The CC Status register.

  enumerator TCPC_POWER_STATUS
    The Power Status register.

  enumerator TCPC_FAULT_STATUS
    The Fault Status register.

  enumerator TCPC_EXTENDED_STATUS
    The Extended Status register.
enumerator TCPC_EXTENDED_ALERT_STATUS
The Extended Alert Status register.

enumerator TCPC_VENDOR_DEFINED_STATUS
The Vendor Defined Status register.

Functions

static inline int tcpc_is_cc_rp(enum tc_cc_voltage_state cc)
    Returns whether the sink has detected a Rp resistor on the other side.

static inline int tcpc_is_cc_open(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)
    Returns true if both CC lines are completely open.

static inline int tcpc_is_cc_snk_dbg_acc(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)
    Returns true if we detect the port partner is a snk debug accessory.

static inline int tcpc_is_cc_src_dbg_acc(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)
    Returns true if we detect the port partner is a src debug accessory.

static inline int tcpc_is_cc_audio_acc(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)
    Returns true if the port partner is an audio accessory.

static inline int tcpc_is_cc_at_least_one_rd(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)
    Returns true if the port partner is presenting at least one Rd.

static inline int tcpc_is_cc_only_one_rd(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)
    Returns true if the port partner is presenting Rd on only one CC line.

static inline int tcpc_init(const struct device *dev)
    Initializes the TCPC.

    Parameters
    • dev – Runtime device structure

    Return values
    • 0 – on success
    • -EIO – on failure
    • -EAGAIN – if initialization should be postponed

static inline int tcpc_get_cc(const struct device *dev, enum tc_cc_voltage_state *cc1, enum tc_cc_voltage_state *cc2)
    Reads the status of the CC lines.

    Parameters
    • dev – Runtime device structure
    • cc1 – A pointer where the CC1 status is written
    • cc2 – A pointer where the CC2 status is written
Return values

• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_select_rp_value(const struct device *dev, enum tc_rp_value rp)
Sets the value of CC pull up resistor used when operating as a Source.

Parameters

• dev – Runtime device structure
• rp – Value of the Pull-Up Resistor.

Return values

• 0 – on success
• -ENOSYS –
• -EIO – on failure

static inline int tcpc_get_rp_value(const struct device *dev, enum tc_rp_value *rp)
Gets the value of the CC pull up resistor used when operating as a Source.

Parameters

• dev – Runtime device structure
• rp – pointer where the value of the Pull-Up Resistor is stored

Return values

• 0 – on success
• -ENOSYS –
• -EIO – on failure

static inline int tcpc_set_cc(const struct device *dev, enum tc_cc_pull pull)
Sets the CC pull resistor and sets the role as either Source or Sink.

Parameters

• dev – Runtime device structure
• pull – The pull resistor to set

Return values

• 0 – on success
• -EIO – on failure

static inline void tcpc_set_vconn_cb(const struct device *dev, tcpc_vconn_control_cb_t vconn_cb)
Sets a callback that can enable or disable VCONN if the TCPC is unable to or the system is configured in a way that does not use the VCONN control capabilities of the TCPC.

The callback is called in the tcpc_set_vconn function if vconn_cb isn't NULL

Parameters

• dev – Runtime device structure
• vconn_cb – pointer to the callback function that controls vconn
static inline void tcpc_set_vconn_discharge_cb(const struct device *dev, tcpc_vconn_discharge_cb_t cb)

Sets a callback that can enable or discharge VCONN if the TCPC is unable to or the system is configured in a way that does not use the VCONN control capabilities of the TCPC.

The callback is called in the tcpc_vconn_discharge function if cb isn’t NULL.

**Parameters**

- `dev` – Runtime device structure
- `cb` – pointer to the callback function that discharges vconn

static inline int tcpc_vconn_discharge(const struct device *dev, bool enable)

Discharges VCONN.

This function uses the TCPC to discharge VCONN if possible or calls the callback function set by tcpc_set_vconn_cb.

**Parameters**

- `dev` – Runtime device structure
- `enable` – VCONN discharge is enabled when true, it's disabled

**Return values**

- `0` – on success
- `-EIO` – on failure
- `-ENOSYS` – if not implemented

static inline int tcpc_set_vconn(const struct device *dev, bool enable)

Enables or disables VCONN.

This function uses the TCPC to measure VCONN if possible or calls the callback function set by tcpc_set_vconn_cb.

**Parameters**

- `dev` – Runtime device structure
- `enable` – VCONN is enabled when true, it's disabled

**Return values**

- `0` – on success
- `-EIO` – on failure
- `-ENOSYS` – if not implemented

static inline int tcpc_set_roles(const struct device *dev, enum tc_power_role power_role, enum tc_data_role data_role)

Sets the Power and Data Role of the PD message header.

This function only needs to be called once per data / power role change.

**Parameters**

- `dev` – Runtime device structure
- `power_role` – current power role
- `data_role` – current data role

**Return values**

- `0` – on success
static inline int tcpc_get_rx_pending_msg(const struct device *dev, struct pd_msg *buf)

Retrieves the Power Delivery message from the TCPC.

If buf is NULL, then only the status is returned, where 0 means there is a message pending and -ENODATA means there is no pending message.

Parameters
• dev – Runtime device structure
• buf – pointer where the pd_buf pointer is written, NULL if only checking the status

Return values
• Greater – or equal to 0 is the number of bytes received if buf parameter is provided
• 0 – if there is a message pending and buf parameter is NULL
• -EIO – on failure
• -ENODATA – if no message is pending

static inline int tcpc_set_rx_enable(const struct device *dev, bool enable)

Enables the reception of SOP* message types.

Parameters
• dev – Runtime device structure
• enable – Enable Power Delivery when true, else it’s disabled

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_set_cc_polarity(const struct device *dev, enum tc_cc_polarity polarity)

Sets the polarity of the CC lines.

Parameters
• dev – Runtime device structure
• polarity – Polarity of the cc line

Return values
• 0 – on success
• -EIO – on failure

static inline int tcpc_transmit_data(const struct device *dev, struct pd_msg *msg)

Transmits a Power Delivery message.

Parameters
• dev – Runtime device structure
• msg – Power Delivery message to transmit

Return values
• 0 – on success
static inline int tcpc_dump_std_reg(const struct device *dev)
    Dump a set of TCPC registers.

Parameters

• dev – Runtime device structure

Return values

• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_set_alert_handler_cb(const struct device *dev,
                                          tcpc_alert_handler_cb_t handler, void *data)

Sets the alert function that’s called when an interrupt is triggered due to an alert bit.
Calling this function enables the particular alert bit

Parameters

• dev – Runtime device structure
• handler – The callback function called when the bit is set
• data – user data passed to the callback

Return values

• 0 – on success
• -EINVAL – on failure

static inline int tcpc_get_status_register(const struct device *dev, enum tcpc_status_reg reg, int32_t *status)

Gets a status register.

Parameters

• dev – Runtime device structure
• reg – The status register to read
• status – Pointer where the status is stored

Return values

• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_clear_status_register(const struct device *dev, enum tcpc_status_reg reg, uint32_t mask)

Clears a TCPC status register.

Parameters

• dev – Runtime device structure
• reg – The status register to read
• mask – A bit mask of the status register to clear. A status bit is cleared when it’s set to 1.

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_mask_status_register(const struct device *dev, enum tcpc_status_reg reg, uint32_t mask)

Sets the mask of a TCPC status register.

Parameters
• dev – Runtime device structure
• reg – The status register to read
• mask – A bit mask of the status register to mask. The status bit is masked if it's 0, else it's unmasked.

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_set_debug_accessory(const struct device *dev, bool enable)

Manual control of TCPC DebugAccessory control.

Parameters
• dev – Runtime device structure
• enable – Enable Debug Accessory when true, else it's disabled

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_set_debug_detach(const struct device *dev)

Detach from a debug connection.

Parameters
• dev – Runtime device structure

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_set_drp_toggle(const struct device *dev, bool enable)

Enable TCPC auto dual role toggle.

Parameters
• dev – Runtime device structure
• enable – Auto dual role toggle is active when true, else it's disabled

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_get_snk_ctrl(const struct device *dev)
Queries the current sinking state of the TCPC.

Parameters
• dev – Runtime device structure

Return values
• true – if sinking power
• false – if not sinking power
• -ENOSYS – if not implemented

static inline int tcpc_get_src_ctrl(const struct device *dev)
Queries the current sourcing state of the TCPC.

Parameters
• dev – Runtime device structure

Return values
• true – if sourcing power
• false – if not sourcing power
• -ENOSYS – if not implemented

static inline int tcpc_set_bist_test_mode(const struct device *dev, bool enable)
Controls the BIST Mode of the TCPC.
It disables RX alerts while the mode is active.

Parameters
• dev – Runtime device structure
• enable – The TCPC enters BIST TEST Mode when true

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_get_chip_info(const struct device *dev, struct tcpc_chip_info *chip_info)
Gets the TCPC firmware version.

Parameters
• dev – Runtime device structure
• chip_info – Pointer to TCPC chip info where the version is stored

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented
static inline int tcpc_set_low_power_mode(const struct device *dev, bool enable)
Instructs the TCPC to enter or exit low power mode.

Parameters
• dev – Runtime device structure
• enable – The TCPC enters low power mode when true, else it exits it

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_sop_prime_enable(const struct device *dev, bool enable)
Enables the reception of SOP Prime messages.

Parameters
• dev – Runtime device structure
• enable – Can receive SOP Prime messages when true, else it can not

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

struct tcpc_chip_info
#include <usbc_tcpc.h> TCPC Chip Information.

Public Members

uint16_t vendor_id
Vendor Id.

uint16_t product_id
Product Id.

uint16_t device_id
Device Id.

uint64_t fw_version_number
Firmware version number.

uint8_t min_req_fw_version_string[8]
Minimum Required firmware version string.

uint64_t min_req_fw_version_number
Minimum Required firmware version number.

struct tcpc_driver_api
#include <usbc_tcpc.h>
group usb_power_delivery
  USB Power Delivery.

**USB PD 3.1 Rev 1.6, Table 6-70 Counter Parameters**

**PD\_N\_CAPS\_COUNT**
  The CapsCounter is used to count the number of Source Capabilities Messages which
  have been sent by a Source at power up or after a Hard Reset.
  Parameter Name: nCapsCounter

**PD\_N\_HARD\_RESET\_COUNT**
  The HardResetCounter is used to retry the Hard Reset whenever there is no response
  from the remote device (see Section 6.6.6) Parameter Name: nHardResetCounter.

**USB PD 3.1 Rev 1.6, Table 6-68 Time Values**

**PD\_T\_NO\_RESPONSE\_MIN\_MS**
  The NoResponseTimer is used by the Policy Engine in a Source to determine that its
  Port Partner is not responding after a Hard Reset.
  Parameter Name: tNoResponseTimer

**PD\_T\_NO\_RESPONSE\_MAX\_MS**
  The NoResponseTimer is used by the Policy Engine in a Source to determine that its
  Port Partner is not responding after a Hard Reset.
  Parameter Name: tNoResponseTimer

**PD\_T\_PS\_HARD\_RESET\_MIN\_MS**
  Min time the Source waits to ensure that the Sink has had sufficient time to process
  Hard Reset Signaling before turning off its power supply to VBUS Parameter Name:
  tPSHardReset.

**PD\_T\_PS\_HARD\_RESET\_MAX\_MS**
  Max time the Source waits to ensure that the Sink has had sufficient time to process
  Hard Reset Signaling before turning off its power supply to VBUS Parameter Name:
  tPSHardReset.

**PD\_T\_SINK\_TX\_MIN\_MS**
  Minimum time a Source waits after changing Rp from SinkTxOk to SinkTxNG before
  initiating an AMS by sending a Message.
  Parameter Name: tSinkTx

**PD\_T\_SINK\_TX\_MAX\_MS**
  Maximum time a Source waits after changing Rp from SinkTxOk to SinkTxNG before
  initiating an AMS by sending a Message.
  Parameter Name: tSinkTx
**PD_T_TYPEC_SEND_SOURCE_CAP_MIN_MS**
Minimum time a source shall wait before sending a Source_Capabilities message while the following is true: 1) The Port is Attached.
2) The Source is not in an active connection with a PD Sink Port. Parameter Name: tTypeCSendSourceCap

**PD_T_TYPEC_SEND_SOURCE_CAP_MAX_MS**
Maximum time a source shall wait before sending a Source_Capabilities message while the following is true: 1) The Port is Attached.
2) The Source is not in an active connection with a PD Sink Port. Parameter Name: tTypeCSendSourceCap

**Defines**

**PD_MAX_EXTENDED_MSG_LEGACY_LEN**
Maximum length of a non-Extended Message in bytes.
See Table 6-75 Value Parameters Parameter Name: MaxExtendedMsgLegacyLen

**PD_MAX_EXTENDED_MSG_LEN**
Maximum length of an Extended Message in bytes.
See Table 6-75 Value Parameters Parameter Name: MaxExtendedMsgLen

**PD_MAX_EXTENDED_MSG_CHUNK_LEN**
Maximum length of a Chunked Message in bytes.
When one of both Port Partners do not support Extended Messages of Data Size greater than PD_MAX_EXTENDED_MSG_LEGACY_LEN then the Protocol Layer supports a Chunking mechanism to break larger Messages into smaller Chunks of size PD_MAX_EXTENDED_MSG_CHUNK_LEN. See Table 6-75 Value Parameters Parameter Name: MaxExtendedMsgChunkLen

**PD_T_TYPEC_SINK_WAIT_CAP_MIN_MS**
Minimum time a sink shall wait for a Source_Capabilities message before sending a Hard Reset See Table 6-61 Time Values Parameter Name: tTypeCSinkWaitCap.

**PD_T_TYPEC_SINK_WAIT_CAP_MAX_MS**
Minimum time a sink shall wait for a Source_Capabilities message before sending a Hard Reset See Table 6-61 Time Values Parameter Name: tTypeCSinkWaitCap.

**PD_V_SAFE_0V_MAX_MV**
VBUS maximum safe operating voltage at “zero volts”.
See Table 7-24 Common Source/Sink Electrical Parameters Parameter Name: vSafe0V

**PD_V_SAFE_5V_MIN_MV**
VBUS minimum safe operating voltage at 5V.
See Table 7-24 Common Source/Sink Electrical Parameters Parameter Name: vSafe5V
PD_T_SAFE_0V_MAX_MS
Time to reach PD_V_SAFE_0V_MV max in milliseconds.
See Table 7-24 Common Source/Sink Electrical Parameters Parameter Name: tSafe0V

PD_T_SAFE_5V_MAX_MS
Time to reach PD_V_SAFE_5V_MV max in milliseconds.
See Table 7-24 Common Source/Sink Electrical Parameters Parameter Name: tSafe5V

PD_T_TX_TIMEOUT_MS
Time to wait for TCPC to complete transmit.

PD_T_HARD_RESET_COMPLETE_MIN_MS
Minimum time a Hard Reset must complete.
See Table 6-68 Time Values

PD_T_HARD_RESET_COMPLETE_MAX_MS
Maximum time a Hard Reset must complete.
See Table 6-68 Time Values

PD_T_SENDER_RESPONSE_MIN_MS
Minimum time a response must be sent from a Port Partner See Table 6-68 Time Values.

PD_T_SENDER_RESPONSE_NOM_MS
Nominal time a response must be sent from a Port Partner See Table 6-68 Time Values.

PD_T_SENDER_RESPONSE_MAX_MS
Maximum time a response must be sent from a Port Partner See Table 6-68 Time Values.

PD_T_SPR_PS_TRANSITION_MIN_MS
Minimum SPR Mode time for a power supply to transition to a new level See Table 6-68 Time Values.

PD_T_SPR_PS_TRANSITION_NOM_MS
Nominal SPR Mode time for a power supply to transition to a new level See Table 6-68 Time Values.

PD_T_SPR_PS_TRANSITION_MAX_MS
Maximum SPR Mode time for a power supply to transition to a new level See Table 6-68 Time Values.

PD_T_EPR_PS_TRANSITION_MIN_MS
Minimum EPR Mode time for a power supply to transition to a new level See Table 6-68 Time Values.

PD_T_EPR_PS_TRANSITION_NOM_MS
Nominal EPR Mode time for a power supply to transition to a new level See Table 6-68 Time Values.
PD_T_EPR_PS_TRANSITION_MAX_MS
Maximum EPR Mode time for a power supply to transition to a new level. See Table 6-68 Time Values.

PD_T_SINK_REQUEST_MIN_MS
Minimum time to wait before sending another request after receiving a Wait message. See Table 6-68 Time Values.

PD_T_CHUNKING_NOT_SUPPORTED_MIN_MS
Minimum time to wait before sending a Not_Supported message after receiving a Chunked message. See Table 6-68 Time Values.

PD_T_CHUNKING_NOT_SUPPORTED_NOM_MS
Nominal time to wait before sending a Not_Supported message after receiving a Chunked message. See Table 6-68 Time Values.

PD_T_CHUNKING_NOT_SUPPORTED_MAX_MS
Maximum time to wait before sending a Not_Supported message after receiving a Chunked message. See Table 6-68 Time Values.

PD_CONVERT_BYTES_TO_PD_HEADER_COUNT(c)
Convert bytes to PD Header data object count, where a data object is 4-bytes.

Parameters
• c – number of bytes to convert

PD_CONVERT_PD_HEADER_COUNT_TO_BYTES(c)
Convert PD Header data object count to bytes.

Parameters
• c – number of PD Header data objects

SINK_TX_OK
Collision avoidance Rp values in REV 3.0 Sink Transmit “OK”.

SINK_TX_NG
Collision avoidance Rp values in REV 3.0 Sink Transmit “NO GO”.

PD_GET_EXT_HEADER(c)
Used to get extended header from the first 32-bit word of the message.

Parameters
• c – first 32-bit word of the message

PDO_MAX_DATA_OBJECTS
PDO - Power Data Object RDO - Request Data Object.
Maximum number of 32-bit data objects sent in a single request.

PD_CONVERT_MA_TO_FIXED_PDO_CURRENT(c)
Convert milliamps to Fixed PDO Current in 10mA units.

Parameters
• c – Current in milliamps
PD_CONVERT_MV_TO_FIXED_PDO_VOLTAGE(v)
Convert millivolts to Fixed PDO Voltage in 50mV units.

Parameters
• v – Voltage in millivolts

PD_CONVERT_FIXED_PDO_CURRENT_TO_MA(c)
Convert a Fixed PDO Current from 10mA units to milliamps.

Parameters
• c – Fixed PDO current in 10mA units.

PD_CONVERT_FIXED_PDO_VOLTAGE_TO_MV(v)
Convert a Fixed PDO Voltage from 50mV units to millivolts.
Used for converting `pd_fixed_supply pdo_source.voltage` and `pd_fixed_supply pdo_sink.voltage`

Parameters
• v – Fixed PDO voltage in 50mV units.

PD_CONVERT_MA_TO_VARIABLE_PDO_CURRENT(c)
Convert milliamps to Variable PDO Current in 10ma units.

Parameters
• c – Current in milliamps

PD_CONVERT_MV_TO_VARIABLE_PDO_VOLTAGE(v)
Convert millivolts to Variable PDO Voltage in 50mV units.

Parameters
• v – Voltage in millivolts

PD_CONVERT_VARIABLE_PDO_CURRENT_TO_MA(c)
Convert a Variable PDO Current from 10mA units to milliamps.

Parameters
• c – Variable PDO current in 10mA units.

PD_CONVERT_VARIABLE_PDO_VOLTAGE_TO_MV(v)
Convert a Variable PDO Voltage from 50mV units to millivolts.

Parameters
• v – Variable PDO voltage in 50mV units.

PD_CONVERT_MW_TO_BATTERY_PDO_POWER(c)
Convert milliwatts to Battery PDO Power in 250mW units.

Parameters
• c – Power in milliwatts

PD_CONVERT_MV_TO_BATTERY_PDO_VOLTAGE(v)
Convert milliwatts to Battery PDO Voltage in 50mV units.

Parameters
• v – Voltage in millivolts
PD_CONVERT_BATTERY(PDO_POWER_TO_MW(c))
Convert a Battery PDO Power from 250mW units to milliwatts.

**Parameters**
- c – Power in 250mW units.

PD_CONVERT_BATTERY(PDO_VOLTAGE_TO_MV(v))
Convert a Battery PDO Voltage from 50mV units to millivolts.

**Parameters**
- v – Voltage in 50mV units.

PD_CONVERT_MA_TO_AUGMENTED_PDO_CURRENT(c)
Convert milliamps to Augmented PDO Current in 50mA units.

**Parameters**
- c – Current in milliamps

PD_CONVERT_MV_TO_AUGMENTED_PDO_VOLTAGE(v)
Convert millivolts to Augmented PDO Voltage in 100mV units.

**Parameters**
- v – Voltage in millivolts

PD_CONVERT_AUGMENTED_PDO_CURRENT_TO_MA(c)
Convert an Augmented PDO Current from 50mA units to milliamps.

**Parameters**
- c – Augmented PDO current in 50mA units.

PD_CONVERT_AUGMENTED_PDO_VOLTAGE_TO_MV(v)
Convert an Augmented PDO Voltage from 100mV units to millivolts.

**Parameters**
- v – Augmented PDO voltage in 100mV units.

**NUM_SOP_STAR_TYPES**
Number of valid Transmit Types.

** Enums **

enum pdo_type
Power Data Object Type Table 6-7 Power Data Object.

**Values:**

enumerator PDO_FIXED = 0
Fixed supply (Vmin = Vmax)

enumerator PDO_BATTERY = 1
Battery.

enumerator PDO_VARIABLE = 2
Variable Supply (non-Battery)
enumerator PDO_AUGMENTED = 3
    Augmented Power Data Object (APDO)

denum pd_frs_type
    Fast Role Swap Required for USB Type-C current.
    Values:

    enumerator FRS_NOT_SUPPORTED
        Fast Swap not supported.

    enumerator FRS_DEFAULT_USB_POWER
        Default USB Power.

    enumerator FRS_1P5A_5V
        1.5A @ 5V

    enumerator FRS_3P0A_5V
        3.0A @ 5V

denum pd_rev_type
    Protocol revision.
    Values:

    enumerator PD_REV10 = 0
        PD revision 1.0.

    enumerator PD_REV20 = 1
        PD revision 2.0.

    enumerator PD_REV30 = 2
        PD revision 3.0.

denum pd_packet_type
    Power Delivery packet type See USB Type-C Port Controller Interface Specification, Revision 2.0, Version 1.2, Table 4-38 TRANSMIT Register Definition.
    Values:

    enumerator PD_PACKET_SOP = 0
        Port Partner message.

    enumerator PD_PACKET_SOP_PRIME = 1
        Cable Plug message.

    enumerator PD_PACKET_PRIME_PRIME = 2
        Cable Plug message far end.

    enumerator PD_PACKET_DEBUG_PRIME = 3
        Currently undefined in the PD specification.
enumerator PD_PACKET_DEBUG_PRIME_PRIME = 4
Currently undefined in the PD specification.

enumerator PD_PACKET_TX_HARD_RESET = 5
Hard Reset message to the Port Partner.

enumerator PD_PACKET_CABLE_RESET = 6
Cable Reset message to the Cable.

enumerator PD_PACKET_TX_BIST_MODE_2 = 7
BIST_MODE_2 message to the Port Partner.

enumerator PD_PACKET_MSG_INVALID = 0xf
USED ONLY FOR RECEPTION OF UNKNOWN MSG TYPES.

enum pd_ctrl_msg_type
Control Message type See Table 6-5 Control Message Types.

Values:

enumerator PD_CTRL_GOOD_CRC = 1
  0 Reserved
  GoodCRC Message

enumerator PD_CTRL_GOTO_MIN = 2
  GotoMin Message.

enumerator PD_CTRL_ACCEPT = 3
  Accept Message.

enumerator PD_CTRL_REJECT = 4
  Reject Message.

enumerator PD_CTRL_PING = 5
  Ping Message.

enumerator PD_CTRL_PS_RDY = 6
  PS_RDY Message.

enumerator PD_CTRL_GET_SOURCE_CAP = 7
  Get_Source_Cap Message.

enumerator PD_CTRL_GET_SINK_CAP = 8
  Get_Sink_Cap Message.

enumerator PD_CTRL_DR_SWAP = 9
  DR_Swap Message.
enumerator PD_CTRL_PR_SWAP = 10
    PR_Swap Message.

descriptor PD_CTRL_VCONN_SWAP = 11
    VCONN_Swap Message.

descriptor PD_CTRL_WAIT = 12
    Wait Message.

descriptor PD_CTRL_SOFT_RESET = 13
    Soft Reset Message.

descriptor PD_CTRL_DATA_RESET = 14
    Used for REV 3.0.
    Data_Reset Message.

descriptor PD_CTRL_DATA_RESET_COMPLETE = 15
    Data_Reset_Complete Message.

descriptor PD_CTRL_NOT_SUPPORTED = 16
    Not_Supported Message.

descriptor PD_CTRL_GET_SOURCE_CAP_EXT = 17
    Get_Source_Cap_Extended Message.

descriptor PD_CTRL_GET_STATUS = 18
    Get_Status Message.

descriptor PD_CTRL_FR_SWAP = 19
    FR_Swap Message.

descriptor PD_CTRL_GET_PPS_STATUS = 20
    Get_PPS_Status Message.

descriptor PD_CTRL_GET_COUNTRY_CODES = 21
    Get_Country_Codes Message.

descriptor PD_CTRL_GET_SINK_CAP_EXT = 22
    Get_Sink_Cap_Extended Message.

enum pd_data_msg_type
    Data message type See Table 6-6 Data Message Types.
    Values:
        enumerator PD_DATA_SOURCE_CAP = 1
            0 Reserved
            SourceCapabilities Message
enumerator PD_DATA_REQUEST = 2
    Request Message.

enumerator PD_DATA_BIST = 3
    BIST Message.

enumerator PD_DATA_SINK_CAP = 4
    Sink Capabilities Message.

enumerator PD_DATA_BATTERY_STATUS = 5
    5-14 Reserved for REV 2.0

enumerator PD_DATA_ALERT = 6
    Alert Message.

enumerator PD_DATA_GET_COUNTRY_INFO = 7
    Get Country Info Message.

enumerator PD_DATA_ENTER_USB = 8
    8-14 Reserved for REV 3.0
    Enter USB message

enumerator PD_DATA_VENDOR_DEF = 15
    Vendor Defined Message.

enum pd_ext_msg_type
    Extended message type for REV 3.0 See Table 6-48 Extended Message Types.

    Values:

enumerator PD_EXT_SOURCE_CAP = 1
    0 Reserved
    Source_Capabilities_Extended Message

enumerator PD_EXT_STATUS = 2
    Status Message.

enumerator PD_EXT_GET_BATTERY_CAP = 3
    Get_Battery_Cap Message.

enumerator PD_EXT_GET_BATTERY_STATUS = 4
    Get_Battery_Status Message.

enumerator PD_EXT_BATTERY_CAP = 5
    Battery_Capabilities Message.

enumerator PD_EXT_GET_MANUFACTURER_INFO = 6
    Get.Manufacturer_Info Message.
enumerator PD_EXT_MANUFACTURER_INFO = 7
  Manufacturer_Info Message.

enumerator PD_EXT_SECURITY_REQUEST = 8
  Security_Request Message.

enumerator PD_EXT_SECURITY_RESPONSE = 9
  Security_Response Message.

enumerator PD_EXT_FIRMWARE_UPDATE_REQUEST = 10
  Firmware_Update_Request Message.

enumerator PD_EXT_FIRMWARE_UPDATE_RESPONSE = 11
  Firmware_Update_Response Message.

enumerator PD_EXT_PPS_STATUS = 12
  PPS_Status Message.

enumerator PD_EXT_COUNTRY_INFO = 13
  Country_Codes Message.

enumerator PD_EXT_COUNTRY_CODES = 14
  Country_Info Message.

enum usbpd_cc_pin
  Active PD CC pin.

  Values:

  enumerator USBPD_CC_PIN_1 = 0
    PD is active on CC1.

  enumerator USBPD_CC_PIN_2 = 1
    PD is active on CC2.

union pd_header
  #include <usbc_pd.h> Build a PD message header See Table 6-1 Message Header.

Public Members

uint16_t message_type
  Type of message.

uint16_t port_data_role
  Port Data role.

uint16_t specification_revision
  Specification Revision.
uint16_t port_power_role
    Port Power Role.

uint16_t message_id
    Message ID.

uint16_t number_of_data_objects
    Number of Data Objects.

uint16_t extended
    Extended Message.

struct pd_header

uint16_t raw_value

union pd_ext_header
    #include <usbc_pd.h> Build an extended message header See Table 6-3 Extended Message Header.

Public Members

uint16_t data_size
    Number of total bytes in data block.

uint16_t reserved0
    Reserved.

uint16_t request_chunk
    1 for a chunked message, else 0

uint16_t chunk_number
    Chunk number when chkd = 1, else 0.

uint16_t chunked
    1 for chunked messages

struct pd_ext_header

uint16_t raw_value
    Raw PD Ext Header value.

union pd_fixed_supply_pdo_source
    #include <usbc_pd.h> Create a Fixed Supply PDO Source value See Table 6-9 Fixed Supply PDO - Source.
Public Members

```c
uint32_t max_current
   Maximum Current in 10mA units.

uint32_t voltage
   Voltage in 50mV units.

uint32_t peak_current
   Peak Current.

uint32_t reserved0
   Reserved – Shall be set to zero.

uint32_t unchunked_ext_msg_supported
   Unchunked Extended Messages Supported.

uint32_t dual_role_data
   Dual-Role Data.

uint32_t usb_comms_capable
   USB Communications Capable.

uint32_t unconstrained_power
   Unconstrained Power.

uint32_t usb_suspend_supported
   USB Suspend Supported.

uint32_t dual_role_power
   Dual-Role Power.
```

```c
enum pdo_type
   Fixed supply.
   SET TO PDO_FIXED

struct pd_fixed_supply_pdo_source

  uint32_t raw_value
     Raw PDO value.

union pd_fixed_supply_pdo_sink
   #include <usbc_pd.h> Create a Fixed Supply PDO Sink value See Table 6-14 Fixed Supply PDO - Sink.
```

Public Members
uint32_t operational_current
Operational Current in 10mA units.

uint32_t voltage
Voltage in 50mV units.

uint32_t reserved0
Reserved – Shall be set to zero.

enum pd_frs_type frs_required
Fast Role Swap required USB Type-C Current.

uint32_t dual_role_data
Dual-Role Data.

uint32_t usb_comms_capable
USB Communications Capable.

uint32_t unconstrained_power
Unconstrained Power.

uint32_t higher_capability
Higher Capability.

uint32_t dual_role_power
Dual-Role Power.

enum pdo_type type
Fixed supply.
SET TO PDO_FIXED

struct pd_fixed_supply_pdo_sink

uint32_t raw_value
Raw PDO value.

union pd_variable_supply_pdo_source
#include <usbc_pd.h> Create a Variable Supply PDO Source value See Table 6-11 Variable Supply (non-Battery) PDO - Source.

Public Members

uint32_t max_current
Maximum Current in 10mA units.

uint32_t min_voltage
Minimum Voltage in 50mV units.
```c
#include <usbc_pd.h>

uint32_t max_voltage
    Maximum Voltage in 50mV units.

enum pdo_type type
    Variable supply.
    SET TO PDO_VARIABLE

struct pd_variable_supply_pdo_source

uint32_t raw_value
    Raw PDO value.

union pd_variable_supply_pdo_sink
    #include <usbc_pd.h> Create a Variable Supply PDO Sink value See Table 6-15 Variable Supply (non-Battery) PDO - Sink.

Public Members

uint32_t operational_current
    operational Current in 10mA units

uint32_t min_voltage
    Minimum Voltage in 50mV units.

uint32_t max_voltage
    Maximum Voltage in 50mV units.

enum pdo_type type
    Variable supply.
    SET TO PDO_VARIABLE

struct pd_variable_supply_pdo_sink

uint32_t raw_value
    Raw PDO value.

union pd_battery_supply_pdo_source
    #include <usbc_pd.h> Create a Battery Supply PDO Source value See Table 6-12 Battery Supply PDO - Source.

Public Members

uint32_t max_power
    Maximum Allowable Power in 250mW units.
```

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uint32_t min_voltage
    Minimum Voltage in 50mV units.

uint32_t max_voltage
    Maximum Voltage in 50mV units.

definition pdo_type
type
    Battery supply.
    SET TO PDO_BATTERY

struct pd_battery_supply_pdo_source

    uint32_t raw_value
        Raw PDO value.

union pd_battery_supply_pdo_sink
    #include <usbc_pd.h> Create a Battery Supply PDO Sink value See Table 6-16 Battery Supply PDO - Sink.

Public Members

uint32_t operational_power
    Operational Power in 250mW units.

uint32_t min_voltage
    Minimum Voltage in 50mV units.

uint32_t max_voltage
    Maximum Voltage in 50mV units.

definition pdo_type type
    Battery supply.
    SET TO PDO_BATTERY

struct pd_battery_supply_pdo_sink

uint32_t raw_value
    Raw PDO value.

union pd_augmented_supply_pdo_source
    #include <usbc_pd.h> Create Augmented Supply PDO Source value See Table 6-13 Programmable Power Supply APDO - Source.

Public Members
uint32_t max_current
    Maximum Current in 50mA increments.

uint32_t reserved0
    Reserved – Shall be set to zero.

uint32_t min_voltage
    Minimum Voltage in 100mV increments.

uint32_t reserved1
    Reserved – Shall be set to zero.

uint32_t max_voltage
    Maximum Voltage in 100mV increments.

uint32_t reserved2
    Reserved – Shall be set to zero.

uint32_t pps_power_limited
    PPS Power Limited.

uint32_t reserved3
    00b – Programmable Power Supply 01b...11b - Reserved, Shall Not be used Setting as reserved because it defaults to 0 when not set.

enum pdo_type type
    Augmented Power Data Object (APDO).
    SET TO PDO_AUGMENTED

struct pd_augmented_supply_pdo_source

uint32_t raw_value
    Raw PDO value.

union pd_augmented_supply_pdo_sink
    #include <usbc_pd.h> Create Augmented Supply PDO Sink value See Table 6-17 Programmable Power Supply APDO - Sink.

Public Members

uint32_t max_current
    Maximum Current in 50mA increments.

uint32_t reserved0
    Reserved – Shall be set to zero.

uint32_t min_voltage
    Minimum Voltage in 100mV increments.
uint32_t reserved1
   Reserved – Shall be set to zero.

uint32_t max_voltage
   Maximum Voltage in 100mV increments.

uint32_t reserved2
   Reserved – Shall be set to zero.

uint32_t reserved3
   00b – Programmable Power Supply 01b...11b - Reserved, Shall Not be used Setting as reserved because it defaults to 0 when not set.

enum pdo_type type
   Augmented Power Data Object (APDO).
   SET TO PDO_AUGMENTED

struct pd_augmented_supply_pdo_sink

uint32_t raw_value
   Raw PDO value.

union pd_rdo
   #include <usbc_pd.h> The Request Data Object (RDO) Shall be returned by the Sink making a request for power.
   See Section 6.4.2 Request Message

Public Members

uint32_t min_or_max_operating_current
   Operating Current 10mA units NOTE: If Give Back Flag is zero, this field is the Maximum Operating Current.
   If Give Back Flag is one, this field is the Minimum Operating Current.

uint32_t operating_current
   Operating current in 10mA units.
   Operating Current 50mA units.

uint32_t reserved0
   Reserved - Shall be set to zero.

uint32_t unchuncked_ext_msg_supported
   Unchuncked Extended Messages Supported.

uint32_t no_usb_suspend
   No USB Suspend.
uint32_t usb_comm_capable
   USB Communications Capable.

uint32_t cap_mismatch
   Capability Mismatch.

uint32_t giveback
   Give Back Flag.

uint32_t object_pos
   Object Position (000b is Reserved and Shall Not be used)

uint32_t reserved1
   Reserved - Shall be set to zero.

struct pd_rdo fixed
   Create a Fixed RDO value See Table 6-19 Fixed and Variable Request Data Object.

struct pd_rdo variable
   Create a Variable RDO value See Table 6-19 Fixed and Variable Request Data Object.

uint32_t min_operating_power
   Minimum Operating Power in 250mW units.

uint32_t operating_power
   Operating power in 250mW units.

struct pd_rdo battery
   Create a Battery RDO value See Table 6-20 Battery Request Data Object.

uint32_t output_voltage
   Output Voltage in 20mV units.

uint32_t reserved2
   Reserved - Shall be set to zero.

uint32_t reserved3
   Reserved - Shall be set to zero.

struct pd_rdo augmented
   Create an Augmented RDO value See Table 6-22 Programmable Request Data Object.

uint32_t raw_value
   Raw RDO value.

struct pd_msg
   #include <usbc_pd.h> Power Delivery message.
Public Members

enum \textit{pd\_packet\_type} \textbf{type} \\
\hspace{1em} Type of this packet.
union \textit{pd\_header} \textbf{header} \\
\hspace{1em} Header of this message.

\begin{verbatim}
uint32_t len \\
\hspace{1em} Length of bytes in data.
uint8_t data[260] \\
\hspace{1em} Message data.
\end{verbatim}

\section*{7.6.49 Time-aware General-Purpose Input/Output (TGPIO)}

\subsection*{Overview}

\subsection*{Configuration Options}

Related configuration options:
\begin{itemize}
  \item CONFIG\_TIMEAWARE\_GPIO
\end{itemize}

\subsection*{API Reference}

\subsection*{Related code samples}

\subsection*{Time-aware GPIO}
Synchronize clocks.

\begin{verbatim}
group tgpio\_interface \\
\hspace{1em} Time-aware GPIO Interface.
\end{verbatim}

\subsection*{Enums}

enum \textit{tgpio\_pin\_polarity} \\
\hspace{1em} Event polarity. \\
\hspace{1em} Values:
\begin{itemize}
  \item \textbf{TGPIO\_RISING\_EDGE} = 0
  \item \textbf{TGPIO\_FALLING\_EDGE}
  \item \textbf{TGPIO\_TOGGLE\_EDGE}
\end{itemize}
Functions

int tgpio_port_get_time(const struct device *dev, uint64_t *current_time)
Get time from ART timer.

Parameters
• dev – TGPIO device
• current_time – Pointer to store timer value in cycles

Returns
0 if successful

int tgpio_port_get_cycles_per_second(const struct device *dev, uint32_t *cycles)
Get current running rate.

Parameters
• dev – TGPIO device
• cycles – pointer to store current running requency

Returns
0 if successful, negative errno code on failure.

int tgpio_pin_disable(const struct device *dev, uint32_t pin)
Disable operation on pin.

Parameters
• dev – TGPIO device
• pin – TGPIO pin

Returns
0 if successful, negative errno code on failure.

int tgpio_pin_config_ext_timestamp(const struct device *dev, uint32_t pin, uint32_t event_polarity)
Enable/Continue operation on pin.

Parameters
• dev – TGPIO device
• pin – TGPIO pin
• event_polarity – TGPIO pin event polarity

Returns
0 if successful, negative errno code on failure.

int tgpio_pin_periodic_output(const struct device *dev, uint32_t pin, uint64_t start_time,
uint64_t repeat_interval, bool periodic_enable)
Enable periodic pulse generation on a pin.

Parameters
• dev – TGPIO device
• pin – TGPIO pin
• start_time – start_time of first pulse in hw cycles
• repeat_interval – repeat interval between two pulses in hw cycles
• periodic_enable – enables periodic mode if ‘true’ is passed.

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Returns
0 if successful, negative errno code on failure.

int tgpio_pin_read_ts_ec(const struct device *dev, uint32_t pin, uint64_t *timestamp,
    uint64_t *event_count)

Read timestamp and event counter from TGPIO.

Parameters
• dev – TGPIO device
• pin – TGPIO pin
• timestamp – timestamp of the last pulse received
• event_count – number of pulses received since the pin is enabled

Returns
0 if successful, negative errno code on failure.

7.6.50 Video

The video driver API offers a generic interface to video devices.

Basic Operation

Video Device A video device is the abstraction of a hardware or software video function, which can produce, process, consume or transform video data. The video API is designed to offer flexible way to create, handle and combine various video devices.

Endpoint Each video device can have one or more endpoints. Output endpoints configure video output function and generate data. Input endpoints configure video input function and consume data.

Video Buffer A video buffer provides the transport mechanism for the data. There is no particular requirement on the content. The requirement for the content is defined by the endpoint format. A video buffer can be queued to a device endpoint for filling (input ep) or consuming (output ep) operation, once the operation is achieved, buffer can be dequeued for post-processing, release or reuse.

Controls A video control is accessed and identified by a CID (control identifier). It represents a video control property. Different devices will have different controls available which can be generic, related to a device class or vendor specific. The set/get control functions provide a generic scalable interface to handle and create controls.

Configuration Options

Related configuration options:
• CONFIG_VIDEO
API Reference

Related code samples

Video TCP server sink
Capture video frames and send them over the network to a TCP client.

Video capture
Use the video API to retrieve video frames from a capture device.

group video_interface
Video Interface.

Defines

video_fourcc(a, b, c, d)

Typedefs

typedef int (*video_api_set_format_t)(const struct device *dev, enum video_endpoint_id ep, struct video_format *fmt)
Set video format.
See video_set_format() for argument descriptions.

typedef int (*video_api_get_format_t)(const struct device *dev, enum video_endpoint_id ep, struct video_format *fmt)
Get current video format.
See video_get_format() for argument descriptions.

typedef int (*video_api_enqueue_t)(const struct device *dev, enum video_endpoint_id ep, struct video_buffer *buf)
Enqueue a buffer in the driver's incoming queue.
See video_enqueue() for argument descriptions.

typedef int (*video_api_dequeue_t)(const struct device *dev, enum video_endpoint_id ep, struct video_buffer **buf, k_timeout_t timeout)
Dequeue a buffer from the driver's outgoing queue.
See video_dequeue() for argument descriptions.

typedef int (*video_api_flush_t)(const struct device *dev, enum video_endpoint_id ep, bool cancel)
Flush endpoint buffers, buffer are moved from incoming queue to outgoing queue.
See video_flush() for argument descriptions.

typedef int (*video_api_stream_start_t)(const struct device *dev)
Start the capture or output process.
See video_stream_start() for argument descriptions.
typedef int (*video_api_stream_stop_t)(const struct device *dev)
    Stop the capture or output process.
    See video_stream_stop() for argument descriptions.

typedef int (*video_api_set_ctrl_t)(const struct device *dev, unsigned int cid, void *value)
    Set a video control value.
    See video_set_ctrl() for argument descriptions.

typedef int (*video_api_get_ctrl_t)(const struct device *dev, unsigned int cid, void *value)
    Get a video control value.
    See video_get_ctrl() for argument descriptions.

typedef int (*video_api_get_caps_t)(const struct device *dev, enum video_endpoint_id ep, struct video_caps *caps)
    Get capabilities of a video endpoint.
    See video_get_caps() for argument descriptions.

typedef int (*video_api_set_signal_t)(const struct device *dev, enum video_endpoint_id ep, struct k_poll_signal *signal)
    Register/Unregister poll signal for buffer events.
    See video_set_signal() for argument descriptions.

Enums

typedef enum video_endpoint_id
    video_endpoint_id enum
    Identify the video device endpoint.
    Values:

        enumerator VIDEO_EP_NONE

        enumerator VIDEO_EP_ANY

        enumerator VIDEO_EP_IN

        enumerator VIDEO_EP_OUT

enum video_signal_result
    video_event enum
    Identify video event.
    Values:

        enumerator VIDEO_BUF_DONE
Functions

static inline int video_set_format(const struct device *dev, enum video_endpoint_id ep, struct video_format *fmt)

Set video format.
Configure video device with a specific format.

Parameters
• dev – Pointer to the device structure for the driver instance.
• ep – Endpoint ID.
• fmt – Pointer to a video format struct.

Return values
• 0 – Is successful.
• -EINVAL – If parameters are invalid.
• -ENOTSUP – If format is not supported.
• -EIO – General input / output error.

static inline int video_get_format(const struct device *dev, enum video_endpoint_id ep, struct video_format *fmt)

Get video format.
Get video device current video format.

Parameters
• dev – Pointer to the device structure for the driver instance.
• ep – Endpoint ID.
• fmt – Pointer to video format struct.

Return values
pointer – to video format

static inline int video_enqueue(const struct device *dev, enum video_endpoint_id ep, struct video_buffer *buf)

Enqueue a video buffer.
Enqueue an empty (capturing) or filled (output) video buffer in the driver’s endpoint incoming queue.

Parameters
• dev – Pointer to the device structure for the driver instance.
• ep – Endpoint ID.
• buf – Pointer to the video buffer.

Return values
• 0 – Is successful.
• -EINVAL – If parameters are invalid.
Dequeue a video buffer.
Dequeue a filled (capturing) or displayed (output) buffer from the driver’s endpoint outgoing queue.

**Parameters**
- **dev** – Pointer to the device structure for the driver instance.
- **ep** – Endpoint ID.
- **buf** – Pointer a video buffer pointer.
- **timeout** – Timeout

**Return values**
- 0 – Is successful.
- -EINVAL – If parameters are invalid.
- -EIO – General input / output error.

Flush endpoint buffers.
A call to flush finishes when all endpoint buffers have been moved from incoming queue to outgoing queue. Either because canceled or fully processed through the video function.

**Parameters**
- **dev** – Pointer to the device structure for the driver instance.
- **ep** – Endpoint ID.
- **cancel** – If true, cancel buffer processing instead of waiting for completion.

**Return values**
0 – Is successful, -ERRNO code otherwise.

Start the video device function.
video_stream_start is called to enter ‘streaming’ state (capture, output...). The driver may receive buffers with video_enqueue() before video_stream_start is called. If driver/device needs a minimum number of buffers before being able to start streaming, then driver set the min_vbuf_count to the related endpoint capabilities.

**Return values**
- 0 – Is successful.
- -EIO – General input / output error.

Stop the video device function.
On video_stream_stop, driver must stop any transactions or wait until they finish.

**Return values**
- 0 – Is successful.
- -EIO – General input / output error.
static inline int video_get_caps(const struct device *dev, enum video_endpoint_id ep, struct video_caps *caps)

Get the capabilities of a video endpoint.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `ep` – Endpoint ID.
- `caps` – Pointer to the `video_caps` struct to fill.

**Return values**

- 0 – Is successful, -ERRNO code otherwise.

static inline int video_set_ctrl(const struct device *dev, unsigned int cid, void *value)

Set the value of a control.

This set the value of a video control, value type depends on control ID, and must be interpreted accordingly.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `cid` – Control ID.
- `value` – Pointer to the control value.

**Return values**

- 0 – Is successful.
- -EINVAL – If parameters are invalid.
- -ENOTSUP – If format is not supported.
- -EIO – General input / output error.

static inline int video_get_ctrl(const struct device *dev, unsigned int cid, void *value)

Get the current value of a control.

This retrieve the value of a video control, value type depends on control ID, and must be interpreted accordingly.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `cid` – Control ID.
- `value` – Pointer to the control value.

**Return values**

- 0 – Is successful.
- -EINVAL – If parameters are invalid.
- -ENOTSUP – If format is not supported.
- -EIO – General input / output error.

static inline int video_set_signal(const struct device *dev, enum video_endpoint_id ep, struct k_poll_signal *signal)

Register/Unregister k_poll signal for a video endpoint.

Register a poll signal to the endpoint, which will be signaled on frame completion (done, aborted, error). Registering a NULL poll signal unregisters any previously registered signal.

**Parameters**
• **dev** – Pointer to the device structure for the driver instance.
• **ep** – Endpoint ID.
• **signal** – Pointer to `k_poll_signal`

**Return values**

0 – Is successful, -ERRNO code otherwise.

```c
struct video_buffer *video_buffer_alloc(size_t size)
```
Allocate video buffer.

**Parameters**

• **size** – Size of the video buffer.

**Return values**

pointer – to allocated video buffer

```c
void video_buffer_release(struct video_buffer *buf)
```
Release a video buffer.

**Parameters**

• **buf** – Pointer to the video buffer to release.

```c
struct video_format

#include <video.h> Video format structure.
Used to configure frame format.

**Public Members**

```c
tUint32_t pixelformat

FourCC pixel format value (Video pixel formats)
```

```c
tUint32_t width

frame width in pixels.
```

```c
tUint32_t height

frame height in pixels.
```

```c
tUint32_t pitch

line stride.
This is the number of bytes that needs to be added to the address in the first pixel of a row in order to go to the address of the first pixel of the next row (>=width).
```

```c
struct video_format_cap

#include <video.h> Video format capability.
Used to describe a video endpoint format capability.

**Public Members**

```c
tUint32_t pixelformat

FourCC pixel format value (Video pixel formats).
```
`uint32_t` width_min
minimum supported frame width in pixels.

`uint32_t` width_max
maximum supported frame width in pixels.

`uint32_t` height_min
minimum supported frame height in pixels.

`uint32_t` height_max
maximum supported frame height in pixels.

`uint16_t` width_step
width step size in pixels.

`uint16_t` height_step
height step size in pixels.

`struct` video_caps
```
#include <video.h> Video format capabilities.
```
Used to describe video endpoint capabilities.

**Public Members**

const `struct` video_format_cap *format_caps
list of video format capabilities (zero terminated).

`uint8_t` min_vbuf_count
minimal count of video buffers to enqueue before being able to start the stream.

`struct` video_buffer
```
#include <video.h> Video buffer structure.
```
Represent a video frame.

**Public Members**

void *driver_data
pointer to driver specific data.

`uint8_t` *buffer
pointer to the start of the buffer.

`uint32_t` size
size of the buffer in bytes.
\begin{verbatim}

uint32_t bytesused
    number of bytes occupied by the valid data in the buffer.

uint32_t timestamp
    time reference in milliseconds at which the last data byte was actually received for
    input endpoints or to be consumed for output endpoints.

struct video_driver_api
    #include <video.h>

group video_controls
    Video controls.

Control classes

VIDEO_CTRL_CLASS_GENERIC
    Generic class controls.

VIDEO_CTRL_CLASS_CAMERA
    Camera class controls.

VIDEO_CTRL_CLASS_MPEG
    MPEG-compression controls.

VIDEO_CTRL_CLASS_JPEG
    JPEG-compression controls.

VIDEO_CTRL_CLASS_VENDOR
    Vendor-specific class controls.

Generic class control IDs

VIDEO_CID_HFLIP
    Mirror the picture horizontally.

VIDEO_CID_VFLIP
    Mirror the picture vertically.

Camera class control IDs

VIDEO_CID_CAMERA_EXPOSURE

VIDEO_CID_CAMERA_GAIN

VIDEO_CID_CAMERA_ZOOM
\end{verbatim}
7.6.51 Watchdog

Overview

API Reference

Related code samples

Watchdog

Use the watchdog driver API to reset the board when it gets stuck in an infinite loop.

group watchdog_interface

Watchdog Interface.

Watchdog options

WDT_OPT_PAUSE_IN_SLEEP
Pause watchdog timer when CPU is in sleep state.

WDT_OPT_PAUSE_HALTED_BY_DBG
Pause watchdog timer when CPU is halted by the debugger.

Watchdog behavior flags

WDT_FLAG_RESET_NONE
Reset: none.

WDT_FLAG_RESET_CPU_CORE
Reset: CPU core.
WDT_FLAG_RESET_SoC
Reset: SoC.

**Typedefs**

typedef void (*wdt_callback_t)(const struct device *dev, int channel_id)
Watchdog callback.

**Param dev**
Watchdog device instance.

**Param channel_id**
Channel identifier.

**Functions**

int wdt_setup(const struct device *dev, uint8_t options)
Set up watchdog instance.
This function is used for configuring global watchdog settings that affect all timeouts. It should be called after installing timeouts. After successful return, all installed timeouts are valid and must be serviced periodically by calling `wdt_feed()`.

**Parameters**
• dev – Watchdog device instance.
• options – Configuration options (see `WDT_OPT`).

**Return values**
• 0 – If successful.
• -ENOTSUP – If any of the set options is not supported.
• -EBUSY – If watchdog instance has been already setup.
• -errno – In case of any other failure.

int wdt_disable(const struct device *dev)
Disable watchdog instance.
This function disables the watchdog instance and automatically uninstalls all timeouts. To set up a new watchdog, install timeouts and call `wdt_setup()` again. Not all watchdogs can be restarted after they are disabled.

**Parameters**
• dev – Watchdog device instance.

**Return values**
• 0 – If successful.
• -EFAULT – If watchdog instance is not enabled.
• -EPERM – If watchdog can not be disabled directly by application code.
• -errno – In case of any other failure.
static inline int wdt_install_timeout(const struct device *dev, const struct wdt_timeout_cfg *cfg)

Install a new timeout.

**Note:** This function must be used before *wdt_setup()*.
Changes applied here have no effects until *wdt_setup()* is called.

**Parameters**
- *dev* – Watchdog device instance.

**Return values**
- *channel_id* – If successful, a non-negative value indicating the index of the channel to which the timeout was assigned. This value is supposed to be used as the parameter in calls to *wdt_feed()*.
- -EBUSY – If timeout can not be installed while watchdog has already been setup.
- -ENOMEM – If no more timeouts can be installed.
- -ENOTSUP – If any of the set flags is not supported.
- -EINVAL – If any of the window timeout value is out of possible range. This value is also returned if watchdog supports only one timeout value for all timeouts and the supplied timeout window differs from windows for alarms installed so far.
- -errno – In case of any other failure.

```
int wdt_feed(const struct device *dev, int channel_id)
```

Feed specified watchdog timeout.

**Parameters**
- *dev* – Watchdog device instance.
- *channel_id* – Channel index.

**Return values**
- 0 – If successful.
- -EAGAIN – If completing the feed operation would stall the caller, for example due to an in-progress watchdog operation such as a previous *wdt_feed()* call.
- -EINVAL – If there is no installed timeout for supplied channel.
- -errno – In case of any other failure.

```
struct wdt_window
```

#include <watchdog.h> Watchdog timeout window.

Each installed timeout needs feeding within the specified time window, otherwise the watchdog will trigger. If the watchdog instance does not support window timeouts then min value must be equal to 0.

**Note:** If specified values can not be precisely set they are always rounded up.
**Public Members**

- `uint32_t min`  
  Lower limit of watchdog feed timeout in milliseconds.

- `uint32_t max`  
  Upper limit of watchdog feed timeout in milliseconds.

```c
struct wdt_timeout_cfg
#include <watchdog.h>  
Watchdog timeout configuration.
```

**Public Members**

- `struct wdt_window window`  
  Timing parameters of watchdog timeout.

- `wdt_callback_t callback`  
  Timeout callback (can be `NULL`).

- `struct wdt_timeout_cfg *next`  
  Pointer to the next timeout configuration.
  
  This field is only available if `CONFIG_WDT_MULTISTAGE` is enabled (watchdogs with staged timeouts functionality). Value must be `NULL` for single stage timeout.

- `uint8_t flags`  
  Flags (see `WDT_FLAGS`).

## 7.7 Pin Control

This is a high-level guide to pin control. See *Pin Control API* for API reference material.

### 7.7.1 Introduction

The hardware blocks that control pin multiplexing and pin configuration parameters such as pin direction, pull-up/down resistors, etc. are named **pin controllers**. The pin controller's main users are SoC hardware peripherals, since the controller enables exposing peripheral signals, like for example, map `I2C0 SDA` signal to pin `PX0`. Not only that, but it usually allows configuring certain pin settings that are necessary for the correct functioning of a peripheral, for example, the slew-rate depending on the operating frequency. The available configuration options are vendor/SoC dependent and can range from simple pull-up/down options to more advanced settings such as debouncing, low-power modes, etc.

The way pin control is implemented in hardware is vendor/SoC specific. It is common to find a **centralized** approach, that is, all pin configuration parameters are controlled by a single hardware block (typically named pinmux), including signal mapping. The figure below illustrates this approach. `PX0` can be mapped to `UART0_TX`, `I2C0_SCK` or `SPI0_MOSI` depending on the `AF` control bits. Other configuration parameters such as pull-up/down are controlled in the same block via `CONFIG` bits. This model is used by several SoC families, such as many from NXP and STM32.
Other vendors/SoCs use a *distributed* approach. In such case, the pin mapping and configuration are controlled by multiple hardware blocks. The figure below illustrates a distributed approach where pin mapping is controlled by peripherals, such as in Nordic nRF SoCs.

From a user perspective, there is no difference in pin controller usage regardless of the hardware implementation: a user will always apply a state. The only difference lies in the driver implementation. In general, implementing a pin controller driver for a hardware that uses a distributed approach requires more effort, since the driver needs to gather knowledge of peripheral dependent registers.

**Pin control vs. GPIO**

Some functionality covered by a pin controller driver overlaps with GPIO drivers. For example, pull-up/down resistors can usually be enabled by both the pin control driver and the GPIO driver.
In Zephyr context, the pin control driver purpose is to perform peripheral signal multiplexing and configuration of other pin parameters required for the correct operation of that peripheral. Therefore, the main users of the pin control driver are SoC peripherals. In contrast, GPIO drivers are for general purpose control of a pin, that is, when its logic level is read or controlled manually.

### 7.7.2 State model

For a device driver to operate correctly, a certain pin configuration needs to be applied. Some device drivers require a static configuration, usually set up at initialization time. Others need to change the configuration at runtime depending on the operating conditions, for example, to enable a low-power mode when suspending the device. Such requirements are modeled using states, a concept that has been adapted from the one in the Linux kernel. Each device driver owns a set of states. Each state has a unique name and contains a full pin configuration set (see the figure below). This effectively means that states are independent of each other, so they do not need to be applied in any specific order. Another advantage of the state model is that it isolates device drivers from pin configuration.

#### Table 2: Example pin configuration encoded using the states model

<table>
<thead>
<tr>
<th>UART0 peripheral</th>
<th>default state</th>
<th>sleep state</th>
</tr>
</thead>
<tbody>
<tr>
<td>TX</td>
<td>Pin: PA0</td>
<td>TX</td>
</tr>
<tr>
<td></td>
<td>Pull: NONE</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Low Power: NO</td>
<td></td>
</tr>
<tr>
<td>RX</td>
<td>Pin: PA1</td>
<td>RX</td>
</tr>
<tr>
<td></td>
<td>Pull: UP</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Low Power: NO</td>
<td></td>
</tr>
</tbody>
</table>

#### Table 3: Standardized state names

<table>
<thead>
<tr>
<th>State</th>
<th>Identifier</th>
<th>Purpose</th>
</tr>
</thead>
<tbody>
<tr>
<td>default</td>
<td>PINCRTL_STATE_DEFAULT</td>
<td>State of the pins when the device is in operational state</td>
</tr>
<tr>
<td>sleep</td>
<td>PINCTRL_STATE_SLEEP</td>
<td>State of the pins when the device is in low power or sleep modes</td>
</tr>
</tbody>
</table>

Note that other standard states could be introduced in the future.
Custom states

Some device drivers may require using custom states beyond the standard ones. To achieve that, the device driver needs to have in its scope definitions for the custom state identifiers named as \texttt{PINCTRL\_STATE\_\{STATE\_NAME\}}, where \texttt{\{STATE\_NAME\}} is the capitalized state name. For example, if \texttt{mystate} has to be supported, a definition named \texttt{PINCTRL\_STATE\_Mystacke} needs to be in the driver's scope.

\textbf{Note:} It is important that custom state identifiers start from \texttt{PINCTRL\_STATE\_PRIV\_START}.

If custom states need to be accessed from outside the driver, for example to perform dynamic pin control, custom identifiers should be placed in a header that is publicly accessible.

Skipping states

In most situations, the states defined in Devicetree will be the ones used in the compiled firmware. However, there are some cases where certain states will be conditionally used depending on a compilation flag. A typical case is the sleep state. This state is only used in practice if \texttt{CONFIG\_PM} or \texttt{CONFIG\_PM\_DEVICE} is enabled. If a firmware variant without these power management configurations is needed, one should in theory remove the sleep state from Devicetree to not waste ROM space storing such unused state.

States can be skipped by the pinctrl Devicetree macros if a definition named \texttt{PINCTRL\_SKIP\_\{STATE\_NAME\}} expanding to \texttt{1} is present when pin control configuration is defined. In case of the sleep state, the pinctrl API already provides such definition conditional to the availability of device power management:

\begin{verbatim}
#if !defined(CONFIG\_PM) && !defined(CONFIG\_PM\_DEVICE)
/** Out of power management configurations, ignore "sleep" state. */
#define PINCTRL\_SKIP\_SLEEP 1
#endif
\end{verbatim}

7.7.3 Dynamic pin control

Dynamic pin control refers to the capability of changing pin configuration at runtime. This feature can be useful in situations where the same firmware needs to run onto slightly different boards, each having a peripheral routed at a different set of pins. This feature can be enabled by setting \texttt{CONFIG\_PINCTRL\_DYNAMIC}.

\textbf{Note:} Dynamic pin control should only be used on devices that have not been initialized. Changing pin configurations while a device is operating may lead to unexpected behavior. Since Zephyr does not support device de-initialization yet, this functionality should only be used during early boot stages.

One of the effects of enabling dynamic pin control is that \texttt{pinctrl\_dev\_config} will be stored in RAM instead of ROM (not states or pin configurations, though). The user can then use \texttt{pinctrl\_update\_states()} to update the states stored in \texttt{pinctrl\_dev\_config} with a new set. This effectively means that the device driver will apply the pin configurations stored in the updated states when it applies a state.
7.7.4 Devicetree representation

Because Devicetree is meant to describe hardware, it is the natural choice when it comes to storing pin control configuration. In the following sections you will find an overview on how states and pin configurations are represented in Devicetree.

States

Given a device, each of its pin control state is represented in Devicetree by `pinctrl-N` properties, being `N` the state index starting from zero. The `pinctrl-names` property is then used to assign a unique identifier for each state property by index, for example, `pinctrl-names list entry 0` is the name for `pinctrl-0`.

```
periph0: periph00 {
    /* state 0 ("default") */
    pinctrl-0 = <...>;
    /* state N ("mystate") */
    pinctrl-N = <...>;
    /* names for state 0 up to state N */
    pinctrl-names = "default", ..., "mystate";
    ...
};
```

Pin configuration

There are multiple ways to represent the pin configurations in Devicetree. However, all end up encoding the same information: the pin multiplexing and the pin configuration parameters. For example, UART_RX is mapped to PX0 and pull-up is enabled. The representation choice largely depends on each vendor/SoC, so the Devicetree binding files for the pin control drivers are the best place to look for details.

A popular and versatile option is shown in the example below. One of the advantages of this choice is the grouping capability based on shared pin configuration. This allows to reduce the verbosity of the pin control definitions. Another advantage is that the pin configuration parameters for a particular state are enclosed in a single Devicetree node.

```
/* board.dts */
#include "board-pinctrl.dtsi"

&periph0 {
    pinctrl-0 = <&periph0_default>;
    pinctrl-names = "default";
};
```

(`/vnd-soc-pkgxx.h
 * File with valid mappings for a specific package (may be autogenerated).
 * This file is optional, but recommended.
 */
#define PERIPH0_SIGA_PX0 VNDSOC_PIN(X, 0, MUX0)
#define PERIPH0_SIGB_PY7 VNDSOC_PIN(Y, 7, MUX4)
#define PERIPH0_SIGC_PZ1 VNDSOC_PIN(Z, 1, MUX2)
...`
Another popular model is based on having a node for each pin configuration and state. While this model may lead to shorter board pin control files, it also requires to have one node for each pin mapping and state, since in general, nodes cannot be re-used for multiple states. This method is discouraged if autogeneration is not an option.

**Note:** Because all Devicetree information is parsed into a C header, it is important to make sure its size is kept to a minimum. For this reason it is important to prefix pre-generated nodes with `/omit-if-no-ref/`. This prefix makes sure that the node is discarded when not used.
/* board-pinctrl.dts */
#include <vnd-soc-pkgxx.dtsi>

/* Enable pull-up for PX0 (default state) */
&periph0_siga_px0_default {
    bias-pull-up;
};

/* Enable pull-up for PZ1 (default state) */
&periph0_sigc_pz1_default {
    bias-pull-up;
};

Note: It is discouraged to add pin configuration defaults in pre-defined nodes. In general, pin configurations depend on the board design or on the peripheral working conditions, so the decision should be made by the board. For example, enabling a pull-up by default may not always be desired because the board already has one or because its value depends on the operating bus speed. Another downside of defaults is that user may not be aware of them, for example:

/* not evident that "periph0_siga_px0_default" also implies "bias-pull-up" */
/omit-if-no-ref/ periph0_siga_px0_default: periph0_siga_px0_default {
    pinctrl_soc_pin_t pinmux = <VNDSOC_PIN(X, 0, MUX0)>;
    bias-pull-up;
};

7.7.5 Implementation guidelines

Pin control drivers

Pin control drivers need to implement a single function: pinctrl_configure_pins(). This function receives an array of pin configurations that need to be applied. Furthermore, if CONFIG_PINCTRL_STORE_REG is set, it also receives the associated device register address for the given pins. This information may be required by some drivers to perform device specific actions.

The pin configuration is stored in an opaque type that is vendor/SoC dependent: pinctrl_soc_pin_t. This type needs to be defined in a header named pinctrl_soc.h file that is in the Zephyr's include path. It can range from a simple integer value to a struct with multiple fields. pinctrl_soc.h also needs to define a macro named Z_PINCTRL_STATE_PINS_INIT that accepts two arguments: a node identifier and a property name (pinctrl-N). With this information the macro needs to define an initializer for all pin configurations contained within the pinctrl-N property of the given node.

Regarding Devicetree pin configuration representation, vendors can decide which option is better for their devices. However, the following guidelines should be followed:

- Use pinctrl-N (N=0, 1, ...) and pinctrl-names properties to define pin control states. These properties are defined in dts/bindings/pinctrl/pinctrl-device.yaml.
- Use standard pin configuration properties as defined in dts/bindings/pinctrl/pincfg-node.yaml.

Representations not following these guidelines may be accepted if they are already used by the same vendor in other operating systems, e.g. Linux.
Device drivers

In this section you will find some tips on how a device driver should use the pinctrl API to successfully configure the pins it needs.

The device compatible needs to be modified in the corresponding binding so that the pinctrl-device.yaml is included. For example:

```
include: [base.yaml, pinctrl-device.yaml]
```

This file is needed to add pinctrl-N and pinctrl-names properties to the device.

From a device driver perspective there are two steps that need to be performed to be able to use the pinctrl API. First, the pin control configuration needs to be defined. This includes all states and pins. `PINCTRL_DT_DEFINE` or `PINCTRL_DT_INST_DEFINE` macros should be used for this purpose. Second, a reference to the device instance `pinctrl_dev_config` needs to be stored, since it is required to later use the API. This can be achieved using the `PINCTRL_DT_DEV_CONFIG_GET` and `PINCTRL_DT_INST_DEV_CONFIG_GET` macros.

It is worth to note that the only relationship between a device and its associated pin control configuration is based on variable naming conventions. The way an instance of `pinctrl_dev_config` is named for a corresponding device instance allows to later obtain a reference to it given the device's Devicetree node identifier. This allows to minimize ROM usage, since only devices requiring pin control will own a reference to a pin control configuration.

Once the driver has defined the pin control configuration and kept a reference to it, it is ready to use the API. The most common way to apply a state is by using `pinctrl_apply_state()`. It is also possible to use the lower level function `pinctrl_apply_state_direct()` to skip state lookup if it is cached in advance (e.g. at init time). Since state lookup time is expected to be fast, it is recommended to use `pinctrl_apply_state()`.

The example below contains a complete example of a device driver that uses the pinctrl API.

```c
/* A driver for the "mydev" compatible device */
#define DT_DRV_COMPAT mydev

... #include <zephyr/drivers/pinctrl.h>
...

struct mydev_config {
    ...
    /* Reference to mydev pinctrl configuration */
    const struct pinctrl_dev_config *pcfg;
    ...
};
...

static int mydev_init(const struct device *dev)
{
    const struct mydev_config *config = dev->config;
    int ret;
    ...
    /* Select "default" state at initialization time */
    ret = pinctrl_apply_state(config->pcfg, PINCTRL_STATE_DEFAULT);
    if (ret < 0) {
        return ret;
    }
    ...
}

#define MYDEV_DEFINE(i)
(continues on next page)```
7.7.6 Pin Control API

**group pinctrl_interface**

Pin Controller Interface.

**Pin control states**

- **PINCTRL_STATE_DEFAULT**
  Default state (state used when the device is in operational state).

- **PINCTRL_STATE_SLEEP**
  Sleep state (state used when the device is in low power mode).

- **PINCTRL_STATE_PRIV_START**
  This and higher values refer to custom private states.

**Defines**

- **PINCTRL_REG_NONE**
  Utility macro to indicate no register is used.

- **PINCTRL_DT_DEV_CONFIG_DECLARE(node_id)**
  Declare pin control configuration for a given node identifier.

  This macro should be used by tests or applications using runtime pin control to declare the pin control configuration for a device. `PINCTRL_DT_DEV_CONFIG_GET` can later be used to obtain a reference to such configuration.

  Only available if `CONFIG_PINCTRL_NON_STATIC` is selected.

  **Parameters**
  - `node_id` – Node identifier.
PINCTRL_DT_DEFINE(node_id)
Define all pin control information for the given node identifier.

This helper macro should be called together with device definition. It defines and initializes the pin control configuration for the device represented by node_id. Each pin control state (pinctrl-0, ..., pinctrl-N) is also defined and initialized. Note that states marked to be skipped will not be defined (refer to Z_PINCTRL_SKIP_STATE for more details).

**Parameters**
- node_id – Node identifier.

PINCTRL_DT_INST_DEFINE(inst)
Define all pin control information for the given compatible index.

See also:
PINCTRL_DT_DEFINE

**Parameters**
- inst – Instance number.

PINCTRL_DT_DEV_CONFIG_GET(node_id)
Obtain a reference to the pin control configuration given a node identifier.

**Parameters**
- node_id – Node identifier.

PINCTRL_DT_INST_DEV_CONFIG_GET(inst)
Obtain a reference to the pin control configuration given current compatible instance number.

See also:
PINCTRL_DT_DEV_CONFIG_GET

**Parameters**
- inst – Instance number.

Functions

int pinctrl_lookup_state(const struct pinctrl_dev_config *config, uint8_t id, const struct pinctrl_state **state)
Find the state configuration for the given state id.

**Parameters**
- config – Pin controller configuration.
- id – Pin controller state id (see PINCTRL_STATES).
- state – Found state.

**Return values**
- 0 – If state has been found.
- -ENOENT – If the state has not been found.
int pinctrl_configure_pins(const pinctrl_soc_pin_t *pins, uint8_t pin_cnt, uintptr_t reg)
Configure a set of pins.
This function will configure the necessary hardware blocks to make the configuration immediately effective.

**Warning:** This function must never be used to configure pins used by an instantiated device driver.

**Parameters**
- **pins** – List of pins to be configured.
- **pin_cnt** – Number of pins.
- **reg** – Device register (optional, use PINCTRL_REG_NONE if not used).

**Return values**
- 0 – If succeeded
- -errno – Negative errno for other failures.

static inline int pinctrl_apply_state_direct(const struct pinctrl_dev_config *config, const struct pinctrl_state *state)
Apply a state directly from the provided state configuration.

**Parameters**
- **config** – Pin control configuration.
- **state** – State.

**Return values**
- 0 – If succeeded
- -errno – Negative errno for other failures.

static inline int pinctrl_apply_state(const struct pinctrl_dev_config *config, uint8_t id)
Apply a state from the given device configuration.

**Parameters**
- **config** – Pin control configuration.
- **id** – Id of the state to be applied (see PINCTRL_STATES).

**Return values**
- 0 – If succeeded.
- -ENOENT – If given state id does not exist.
- -errno – Negative errno for other failures.

**struct pinctrl_state**

```
#include <pinctrl.h> Pin control state configuration.
```

**Public Members**

```
const pinctrl_soc_pin_t *pins
Pin configurations.
```
uint8_t pin_cnt
    Number of pin configurations.

uint8_t id
    State identifier (see PINCTRL_STATES).

struct pinctrl_dev_config
    #include <pinctrl.h> Pin controller configuration for a given device.

Public Members

uintptr_t reg
    Device address (only available if CONFIG_PINCTRL_STORE_REG is enabled).

const struct pinctrl_state *states
    List of state configurations.

uint8_t state_cnt
    Number of state configurations.

Dynamic pin control

group pinctrl_interface_dynamic

Defines

PINCTRL_DT_STATE_PINS_DEFINE(node_id, prop)
    Helper macro to define the pins of a pin control state from Devicetree.
    The name of the defined state pins variable is the same used by prop. This macro is expected to be used in conjunction with PINCTRL_DT_STATE_INIT.

    See also:
    PINCTRL_DT_STATE_INIT

Parameters

    • node_id – Node identifier containing prop.
    • prop – Property within node_id containing state configuration.

PINCTRL_DT_STATE_INIT(prop, state)
    Utility macro to initialize a pin control state.
    This macro should be used in conjunction with PINCTRL_DT_STATE_PINS_DEFINE when using dynamic pin control to define an alternative state configuration stored in Devicetree.

    Example:
// board.dts
/
{
  zephyr, user {
    // uart0_alt_default node contains alternative pin config
    uart0_alt_default = <&uart0_alt_default>;
  };
};

// application
PINCTRL_DT_STATE_PINS_DEFINE(DT_PATH(zephyr_user), uart0_alt_default);

static const struct pinctrl_state uart0_alt[] = {
  PINCTRL_DT_STATE_INIT(uart0_alt_default, PINCTRL_STATE_DEFAULT)
};

See also:

PINCTRL_DT_STATE_PINS_DEFINE

Parameters

- prop – Property name in Devicetree containing state configuration.
- state – State represented by prop (see PINCTRL_STATES).

Functions

int pinctrl_update_states(struct pinctrl_dev_config *config, const struct pinctrl_state *states, uint8_t state_cnt)

Update states with a new set.

Note: In order to guarantee device drivers correct operation the same states have to be provided. For example, if default and sleep are in the current list of states, it is expected that the new array of states also contains both.

Parameters

- config – Pin control configuration.
- states – New states to be set.
- state_cnt – Number of new states to be set.

Return values

- EINVAL – If the new configuration does not contain the same states as the current active configuration.
- ENOSYS – If the functionality is not available.
- 0 – On success.

7.7.7 Other reference material

- Introduction to pin muxing and GPIO control under Linux
7.8 Porting

These pages document how to port Zephyr to new hardware.

7.8.1 Architecture Porting Guide

An architecture port is needed to enable Zephyr to run on an ISA (instruction set architecture) or an ABI (Application Binary Interface) that is not currently supported.

The following are examples of ISAs and ABIs that Zephyr supports:

- x86_32 ISA with System V ABI
- ARMv7-M ISA with Thumb2 instruction set and ARM Embedded ABI (aeabi)
- ARCv2 ISA

For information on Kconfig configuration, see Setting Kconfig configuration values. Architectures use a Kconfig configuration scheme similar to boards.

An architecture port can be divided in several parts; most are required and some are optional:

- **The early boot sequence**: each architecture has different steps it must take when the CPU comes out of reset (required).
- **Interrupt and exception handling**: each architecture handles asynchronous and unrequested events in a specific manner (required).
- **Thread context switching**: the Zephyr context switch is dependent on the ABI and each ISA has a different set of registers to save (required).
- **Thread creation and termination**: A thread's initial stack frame is ABI and architecture-dependent, and thread abortion possibly as well (required).
- **Device drivers**: most often, the system clock timer and the interrupt controller are tied to the architecture (some required, some optional).
- **Utility libraries**: some common kernel APIs rely on a architecture-specific implementation for performance reasons (required).
- **CPU idling/power management**: most architectures implement instructions for putting the CPU to sleep (partly optional, most likely very desired).
- **Fault management**: for implementing architecture-specific debug help and handling of fatal error in threads (partly optional).
- **Linker scripts and toolchains**: architecture-specific details will most likely be needed in the build system and when linking the image (required).
- **Memory Management and Memory Mapping**: for architecture-specific details on supporting memory management and memory mapping.
- **Stack Objects**: for architecture-specific details on memory protection hardware regarding stack objects.
- **User Mode Threads**: for supporting threads in user mode.
- **GDB Stub**: for supporting GDB stub to enable remote debugging.

**Early Boot Sequence**

The goal of the early boot sequence is to take the system from the state it is after reset to a state where is can run C code and thus the common kernel initialization sequence. Most of the time, very few steps are needed, while some architectures require a bit more work to be performed.
Common steps for all architectures:

- Setup an initial stack.
- If running an XIP (eXecute-In-Place) kernel, copy initialized data from ROM to RAM.
- If not using an ELF loader, zero the BSS section.
- Jump to \texttt{z\_cstart()}, the early kernel initialization
  - \texttt{z\_cstart()} is responsible for context switching out of the fake context running at startup into the main thread.

Some examples of architecture-specific steps that have to be taken:

- If given control in real mode on x86\_32, switch to 32-bit protected mode.
- Setup the segment registers on x86\_32 to handle boot loaders that leave them in an unknown or broken state.
- Initialize a board-specific watchdog on Cortex-M3/4.
- Switch stacks from MSP to PSP on Cortex-M.
- Use a different approach than calling into \texttt{\_Swap()} on Cortex-M to prevent race conditions.
- Setup FIRQ and regular IRQ handling on ARCv2.

\textbf{Interrupt and Exception Handling}

Each architecture defines interrupt and exception handling differently.

When a device wants to signal the processor that there is some work to be done on its behalf, it raises an interrupt. When a thread does an operation that is not handled by the serial flow of the software itself, it raises an exception. Both, interrupts and exceptions, pass control to a handler. The handler is known as an ISR (Interrupt Service Routine) in the case of interrupts. The handler performs the work required by the exception or the interrupt. For interrupts, that work is device-specific. For exceptions, it depends on the exception, but most often the core kernel itself is responsible for providing the handler.

The kernel has to perform some work in addition to the work the handler itself performs. For example:

- Prior to handing control to the handler:
  - Save the currently executing context.
  - Possibly getting out of power saving mode, which includes waking up devices.
  - Updating the kernel uptime if getting out of tickless idle mode.
- After getting control back from the handler:
  - Decide whether to perform a context switch.
  - When performing a context switch, restore the context being context switched in.

This work is conceptually the same across architectures, but the details are completely different:

- The registers to save and restore.
- The processor instructions to perform the work.
- The numbering of the exceptions.
- etc.

It thus needs an architecture-specific implementation, called the interrupt/exception stub.

Another issue is that the kernel defines the signature of ISRs as:
Architectures do not have a consistent or native way of handling parameters to an ISR. As such there are two commonly used methods for handling the parameter.

- Using some architecture defined mechanism, the parameter value is forced in the stub. This is commonly found in X86-based architectures.
- The parameters to the ISR are inserted and tracked via a separate table requiring the architecture to discover at runtime which interrupt is executing. A common interrupt handler demuxer is installed for all entries of the real interrupt vector table, which then fetches the device’s ISR and parameter from the separate table. This approach is commonly used in the ARC and ARM architectures via the CONFIG_GEN_ISR_TABLES implementation. You can find examples of the stubs by looking at _interrupt_enter() in x86, _Interrupt() in ARM, _isr_wrapper() in ARM, or the full implementation description for ARC in arch/arc/core/isr_wrapper.S.

Each architecture also has to implement primitives for interrupt control:

- locking interrupts: irq_lock(), irq_unlock().
- registering interrupts: IRQ_CONNECT().
- programming the priority if possible irq_priority_set().
- enabling/disabling interrupts: irq_enable(), irq_disable().

**Note:** IRQ_CONNECT is a macro that uses assembler and/or linker script tricks to connect interrupts at build time, saving boot time and text size.

The vector table should contain a handler for each interrupt and exception that can possibly occur. The handler can be as simple as a spinning loop. However, we strongly suggest that handlers at least print some debug information. The information helps figuring out what went wrong when hitting an exception that is a fault, like divide-by-zero or invalid memory access, or an interrupt that is not expected (spurious interrupt). See the ARM implementation in arch/arm/core/cortex_m/fault.c for an example.

### Thread Context Switching

Multi-threading is the basic purpose to have a kernel at all. Zephyr supports two types of threads: preemptible and cooperative.

Two crucial concepts when writing an architecture port are the following:

- Cooperative threads run at a higher priority than preemptible ones, and always preempt them.
- After handling an interrupt, if a cooperative thread was interrupted, the kernel always goes back to running that thread, since it is not preemptible.

A context switch can happen in several circumstances:

- When a thread executes a blocking operation, such as taking a semaphore that is currently unavailable.
- When a preemptible thread unblocks a thread of higher priority by releasing the object on which it was blocked.
- When an interrupt unblocks a thread of higher priority than the one currently executing, if the currently executing thread is preemptible.
- When a thread runs to completion.
• When a thread causes a fatal exception and is removed from the running threads. For example, referencing invalid memory,

Therefore, the context switching must thus be able to handle all these cases.

The kernel keeps the next thread to run in a “cache”, and thus the context switching code only has to fetch from that cache to select which thread to run.

There are two types of context switches: cooperative and preemptive.

• A cooperative context switch happens when a thread willfully gives the control to another thread. There are two cases where this happens
  - When a thread explicitly yields.
  - When a thread tries to take an object that is currently unavailable and is willing to wait until the object becomes available.

• A preemptive context switch happens either because an ISR or a thread causes an operation that schedules a thread of higher priority than the one currently running, if the currently running thread is preemptible. An example of such an operation is releasing an object on which the thread of higher priority was waiting.

Note: Control is never taken from cooperative thread when one of them is the running thread.

A cooperative context switch is always done by having a thread call the _Swap() kernel internal symbol. When _Swap is called, the kernel logic knows that a context switch has to happen: _Swap does not check to see if a context switch must happen. Rather, _Swap decides what thread to context switch in. _Swap is called by the kernel logic when an object being operated on is unavailable, and some thread yielding/sleeping primitives.

Note: On x86 and Nios2, _Swap is generic enough and the architecture flexible enough that _Swap can be called when exiting an interrupt to provoke the context switch. This should not be taken as a rule, since neither the ARM Cortex-M or ARCv2 port do this.

Since _Swap is cooperative, the caller-saved registers from the ABI are already on the stack. There is no need to save them in the k_thread structure.

A context switch can also be performed preemptively. This happens upon exiting an ISR, in the kernel interrupt exit stub:

• _interrupt_enter on x86 after the handler is called.
• _IntExit on ARM.
• _firq_exit and _rirq_exit on ARCv2.

In this case, the context switch must only be invoked when the interrupted thread was preemptible, not when it was a cooperative one, and only when the current interrupt is not nested.

The kernel also has the concept of “locking the scheduler”. This is a concept similar to locking the interrupts, but lighter-weight since interrupts can still occur. If a thread has locked the scheduler, it is temporarily non-preemptible.

So, the decision logic to invoke the context switch when exiting an interrupt is simple:

• If the interrupted thread is not preemptible, do not invoke it.
• Else, fetch the cached thread from the ready queue, and:
  - If the cached thread is not the current thread, invoke the context switch.
  - Else, do not invoke it.
This is simple, but crucial: if this is not implemented correctly, the kernel will not function as intended and will experience bizarre crashes, mostly due to stack corruption.

**Note:** If running a coop-only system, i.e. if `CONFIG_NUM_PREEMPT_PRIORITIES` is 0, no preemptive context switch ever happens. The interrupt code can be optimized to not take any scheduling decision when this is the case.

### Thread Creation and Termination

To start a new thread, a stack frame must be constructed so that the context switch can pop it the same way it would pop one from a thread that had been context switched out. This is to be implemented in an architecture-specific `_new_thread` internal routine.

The thread entry point is also not to be called directly, i.e. it should not be set as the PC (program counter) for the new thread. Rather it must be wrapped in `_thread_entry`. This means that the PC in the stack frame shall be set to `_thread_entry`, and the thread entry point shall be passed as the first parameter to `_thread_entry`. The specifics of this depend on the ABI.

The need for an architecture-specific thread termination implementation depends on the architecture. There is a generic implementation, but it might not work for a given architecture.

One reason that has been encountered for having an architecture-specific implementation of thread termination is that aborting a thread might be different if aborting because of a graceful exit or because of an exception. This is the case for ARM Cortex-M, where the CPU has to be taken out of handler mode if the thread triggered a fatal exception, but not if the thread gracefully exits its entry point function.

This means implementing an architecture-specific version of `k_thread_abort()`, and setting the Kconfig option `CONFIG_ARCH_HAS_THREAD_ABORT` as needed for the architecture (e.g. see arch/arm/core/cortex_m/Kconfig).

### Thread Local Storage

To enable thread local storage on a new architecture:

1. Implement `arch_tls_stack_setup()` to setup the TLS storage area in stack. Refer to the toolchain documentation on how the storage area needs to be structured. Some helper functions can be used:
   - Function `z_tls_data_size()` returns the size needed for thread local variables (excluding any extra data required by toolchain and architecture).
   - Function `z_tls_copy()` prepares the TLS storage area for thread local variables. This only copies the variable themselves and does not do architecture and/or toolchain specific data.
2. In the context switching, grab the tls field inside the new thread's struct `k_thread` and put it into an appropriate register (or some other variable) for access to the TLS storage area. Refer to toolchain and architecture documentation on which registers to use.
3. In kconfig, add select `CONFIG_ARCH_HAS_THREAD_LOCAL_STORAGE` to kconfig related to the new architecture.
4. Run the tests/kernel/threads/tls to make sure the new code works.

7.8. Porting
Device Drivers

The kernel requires very few hardware devices to function. In theory, the only required device is the interrupt controller, since the kernel can run without a system clock. In practice, to get access to most, if not all, of the sanity check test suite, a system clock is needed as well. Since these two are usually tied to the architecture, they are part of the architecture port.

Interrupt Controllers There can be significant differences between the interrupt controllers and the interrupt concepts across architectures.

For example, x86 has the concept of an IDT and different interrupt controllers. The position of an interrupt in the IDT determines its priority.

On the other hand, the ARM Cortex-M has the NVIC (Nested Vectored Interrupt Controller) as part of the architecture definition. There is no need for an IDT-like table that is separate from the NVIC vector table. The position in the table has nothing to do with priority of an IRQ: priorities are programmable per-entry.

The ARCv2 has its interrupt unit as part of the architecture definition, which is somewhat similar to the NVIC. However, where ARC defines interrupts as having a one-to-one mapping between exception and interrupt numbers (i.e. exception 1 is IRQ1, and device IRQs start at 16), ARM has IRQ0 being equivalent to exception 16 (and weirdly enough, exception 1 can be seen as IRQ-15).

All these differences mean that very little, if anything, can be shared between architectures with regards to interrupt controllers.

System Clock x86 has APIC timers and the HPET as part of its architecture definition. ARM Cortex-M has the SYSTICK exception. Finally, ARCv2 has the timer0/1 device.

Kernel timeouts are handled in the context of the system clock timer driver's interrupt handler.

Console Over Serial Line There is one other device that is almost a requirement for an architecture port, since it is so useful for debugging. It is a simple polling, output-only, serial port driver on which to send the console (printk, printf) output.

It is not required, and a RAM console (CONFIG_RAM_CONSOLE) can be used to send all output to a circular buffer that can be read by a debugger instead.

Utility Libraries

The kernel depends on a few functions that can be implemented with very few instructions or in a lock-less manner in modern processors. Those are thus expected to be implemented as part of an architecture port.

- Atomic operators.
  - If instructions do exist for a given architecture, the implementation is configured using the CONFIG_ATOMIC_OPERATIONS_ARCH Kconfig option.
  - If instructions do not exist for a given architecture, a generic version that wraps irq_lock() or irq_unlock() around non-atomic operations exists. It is configured using the CONFIG_ATOMIC_OPERATIONS_C Kconfig option.
- Find-least-significant-bit-set and find-most-significant-bit-set.
  - If instructions do not exist for a given architecture, it is always possible to implement these functions as generic C functions.

It is possible to use compiler built-ins to implement these, but be careful they use the required compiler barriers.
CPU Idling/Power Management

The kernel provides support for CPU power management with two functions: `arch_cpu_idle()` and `arch_cpu_atomic_idle()`.

`arch_cpu_idle()` can be as simple as calling the power saving instruction for the architecture with interrupts unlocked, for example `hlt` on x86, `wfi` or `wfe` on ARM, `sleep` on ARC. This function can be called in a loop within a context that does not care if it get interrupted or not by an interrupt before going to sleep. There are basically two scenarios when it is correct to use this function:

- In a single-threaded system, in the only thread when the thread is not used for doing real work after initialization, i.e. it is sitting in a loop doing nothing for the duration of the application.
- In the idle thread.

`arch_cpu_atomic_idle()`, on the other hand, must be able to atomically re-enable interrupts and invoke the power saving instruction. It can thus be used in real application code, again in single-threaded systems.

Normally, idling the CPU should be left to the idle thread, but in some very special scenarios, these APIs can be used by applications.

Both functions must exist for a given architecture. However, the implementation can be simply the following steps, if desired:

1. unlock interrupts
2. NOP

However, a real implementation is strongly recommended.

Fault Management

In the event of an unhandled CPU exception, the architecture code must call into `z_fatal_error()`. This function dumps out architecture-agnostic information and makes a policy decision on what to do next by invoking `k_sys_fatal_error()`. This function can be overridden to implement application-specific policies that could include locking interrupts and spinning forever (the default implementation) or even powering off the system (if supported).

Toolchain and Linking

Toolchain support has to be added to the build system.

Some architecture-specific definitions are needed in `include/zephyr/toolchain/gcc.h`. See what exists in that file for currently supported architectures.

Each architecture also needs its own linker script, even if most sections can be derived from the linker scripts of other architectures. Some sections might be specific to the new architecture, for example the SCB section on ARM and the IDT section on x86.

Memory Management and Memory Mapping

If the target platform enables paging and requires drivers to memory-map their I/O regions, `CONFIG_MMU` needs to be enabled and the following API implemented:

- `arch_mem_map()`
- `arch_mem_unmap()`
- `arch_page_phys_get()`
Stack Objects

The presence of memory protection hardware affects how stack objects are created. All architecture ports must specify the required alignment of the stack pointer, which is some combination of CPU and ABI requirements. This is defined in architecture headers with `ARCH_STACK_PTR_ALIGN` and is typically something small like 4, 8, or 16 bytes.

Two types of thread stacks exist:

- “kernel” stacks defined with `K_KERNEL_STACK_DEFINE()` and related APIs, which can host kernel threads running in supervisor mode or used as the stack for interrupt/exception handling. These have significantly relaxed alignment requirements and use less reserved data. No memory is reserved for privilege elevation stacks.

- “thread” stacks which typically use more memory, but are capable of hosting thread running in user mode, as well as any use-cases for kernel stacks.

If `CONFIG_USERSPACE` is not enabled, “thread” and “kernel” stacks are equivalent.

Additional macros may be defined in the architecture layer to specify the alignment of the base of stack objects, any reserved data inside the stack object not used for the thread's stack buffer, and how to round up stack sizes to support user mode threads. In the absence of definitions some defaults are assumed:

- `ARCH_KERNEL_STACK_RESERVED`: default no reserved space
- `ARCH_THREAD_STACK_RESERVED`: default no reserved space
- `ARCH_KERNEL_STACK_OBJ_ALIGN`: default align to `ARCH_STACK_PTR_ALIGN`
- `ARCH_THREAD_STACK_OBJ_ALIGN`: default align to `ARCH_STACK_PTR_ALIGN`
- `ARCH_THREAD_STACK_SIZE_ALIGN`: default round up to `ARCH_STACK_PTR_ALIGN`

All stack creation macros are defined in terms of these.

Stack objects all have the following layout, with some regions potentially zero-sized depending on configuration. There are always two main parts: reserved memory at the beginning, and then the stack buffer itself. The bounds of some areas can only be determined at runtime in the context of its associated thread object. Other areas are entirely computable at build time.

Some architectures may need to carve-out reserved memory at runtime from the stack buffer, instead of unconditionally reserving it at build time, or to supplement an existing reserved area (as is the case with the ARM FPU). Such carve-outs will always be tracked in thread stack info start. The region specified by thread stack info start and thread stack info size is always fully accessible by a user mode thread. thread stack info delta denotes an offset which can be used to compute the initial stack pointer from the very end of the stack object, taking into account storage for TLS and ASLR random offsets.

```
+---------------------+ <- thread.stack_obj
| Reserved Memory     | } K_(THREAD|KERNEL)_STACK_RESERVED
+---------------------+
| Carved-out memory   | <- thread.stack_info.start
Unused stack buffer
|                      | <- thread's current stack pointer
Used stack buffer
| ASLR Random offset  | <- Initial stack pointer. Computable with thread.stack_info.delta
+---------------------| <- thread.userspace_local_data
| Thread-local data    | <- thread.stack_info.start + thread.stack_info.size
```

At present, Zephyr does not support stacks that grow upward.
No Memory Protection  If no memory protection is in use, then the defaults are sufficient.

**HW-based stack overflow detection**  This option uses hardware features to generate a fatal error if a thread in supervisor mode overflows its stack. This is useful for debugging, although for a couple reasons, you can't reliably make any assertions about the state of the system after this happens:

- The kernel could have been inside a critical section when the overflow occurs, leaving important global data structures in a corrupted state.
- For systems that implement stack protection using a guard memory region, it's possible to overshoot the guard and corrupt adjacent data structures before the hardware detects this situation.

To enable the CONFIG_HW_STACK_PROTECTION feature, the system must provide some kind of hardware-based stack overflow protection, and enable the CONFIG_ARCH_HAS_STACK_PROTECTION option.

Two forms of HW-based stack overflow detection are supported: dedicated CPU features for this purpose, or special read-only guard regions immediately preceding stack buffers.

CONFIG_HW_STACK_PROTECTION only catches stack overflows for supervisor threads. This is not required to catch stack overflow from user threads; CONFIG_USERSPACE is orthogonal.

This feature only detects supervisor mode stack overflows, including stack overflows when handling system calls. It doesn’t guarantee that the kernel has not been corrupted. Any stack overflow in supervisor mode should be treated as a fatal error, with no assertions about the integrity of the overall system possible.

Stack overflows in user mode are recoverable (from the kernel's perspective) and require no special configuration; CONFIG_HW_STACK_PROTECTION only applies to catching overflows when the CPU is in supervisor mode.

**CPU-based stack overflow detection**  If we are detecting stack overflows in supervisor mode via special CPU registers (like ARM's SPLIM), then the defaults are sufficient.

**Guard-based stack overflow detection**  We are detecting supervisor mode stack overflows via special memory protection region located immediately before the stack buffer that generates an exception on write. Reserved memory will be used for the guard region.

ARCH_KERNEL_STACK_RESERVED should be defined to the minimum size of a memory protection region. On most ARM CPUs this is 32 bytes. ARCH_KERNEL_STACK_OBJ_ALIGN should also be set to the required alignment for this region.

MMU-based systems should not reserve RAM for the guard region and instead simply leave an non-present virtual page below every stack when it is mapped into the address space. The stack object will still need to be properly aligned and sized to page granularity.

Guard carve-outs for kernel stacks are uncommon and should be avoided if possible. They tend to be needed for two situations:
The same stack may be re-purposed to host a user thread, in which case the guard is unnecessary and shouldn't be unconditionally reserved. This is the case when privilege elevation stacks are not inside the stack object.

The required guard size is variable and depends on context. For example, some ARM CPUs have lazy floating point stacking during exceptions and may decrement the stack pointer by a large value without writing anything, completely overshooting a minimally-sized guard and corrupting adjacent memory. Rather than unconditionally reserving a larger guard, the extra memory is carved out if the thread uses floating point.

**User mode enabled**  Enabling user mode activates two new requirements:

- A separate fixed-sized privilege mode stack, specified by `CONFIG_PRIVILEGED_STACK_SIZE`, must be allocated that the user thread cannot access. It is used as the stack by the kernel when handling system calls. If stack guards are implemented, a stack guard region must be able to be placed before it, with support for carve-outs if necessary.

- The memory protection hardware must be able to program a region that exactly covers the thread's stack buffer, tracked in thread.stack_info. This implies that `ARCH_THREAD_STACK_SIZE_ADJUST()` will need to round up the requested stack size so that a region may cover it, and that `ARCH_THREAD_STACK_OBJ_ALIGN()` is also specified per the granularity of the memory protection hardware.

This becomes more complicated if the memory protection hardware requires that all memory regions be sized to a power of two, and aligned to their own size. This is common on older MPUs and is known with `CONFIG_MPU_REQUIRES_POWER_OF_TWO_ALIGNMENT`.

`thread.stack_info` always tracks the user-accessible part of the stack object, it must always be correct to program a memory protection region with user access using the range stored within.

**Non power-of-two memory region requirements** On systems without power-of-two region requirements, the reserved memory area for threads stacks defined by `K_THREAD_STACK_RESERVED` may be used to contain the privilege mode stack. The layout could be something like:

```
+------------------------------+ <- thread.stack_obj
| Other platform data |
+------------------------+---
| Guard region (if enabled) |
+------------------------+---
| Guard carve-out (if needed) |
|..............................|
| Privilege elevation stack |
+------------------------------+ <- thread.stack_obj +
| Stack buffer                          |
.                         .                          K_THREAD_STACK_RESERVED =
.                         .                          thread.stack_info.start
```

The guard region, and any carve-out (if needed) would be configured as a read-only region when the thread is created.

- If the thread is a supervisor thread, the privilege elevation region is just extra stack memory. An overflow will eventually crash into the guard region.

- If the thread is running in user mode, a memory protection region will be configured to allow user threads access to the stack buffer, but nothing before or after it. An overflow in user mode will crash into the privilege elevation stack, which the user thread has no access to. An overflow when handling a system call will crash into the guard region.

On an MMU system there should be no physical guards; the privilege mode stack will be mapped into kernel memory, and the stack buffer in the user part of memory, each with non-present virtual guard pages below them to catch runtime stack overflows.
Other platform data may be stored before the guard region, but this is highly discouraged if such data could be stored in thread.arch somewhere.

ARCH_THREAD_STACK_RESERVED will need to be defined to capture the size of the reserved region containing platform data, privilege elevation stacks, and guards. It must be appropriately sized such that an MPU region to grant user mode access to the stack buffer can be placed immediately after it.

**Power-of-two memory region requirements**  Thread stack objects must be sized and aligned to the same power of two, without any reserved memory to allow efficient packing in memory. Thus, any guards in the thread stack must be completely carved out, and the privilege elevation stack must be allocated elsewhere.

ARCH_THREAD_STACK_SIZE_ADJUST() and ARCH_THREAD_STACK_OBJ_ALIGN() should both be defined to Z_POW2_CEIL(). K_THREAD_STACK_RESERVED must be 0.

For the privilege stacks, the CONFIG_GEN_PRIV_STACKS must be enabled. For every thread stack found in the system, a corresponding fixed-size kernel stack used for handling system calls is generated. The address of the privilege stacks can be looked up quickly at runtime based on the thread stack address using z_priv_stack_find(). These stacks are laid out the same way as other kernel-only stacks.

```plaintext
+-----------------------------+ <- z_priv_stack_find(thread.stack_obj)
    | Reserved memory          |
+-----------------------------+ } K_KERNEL_STACK_RESERVED
    | Guard carve-out (if needed) |
    |.............................|
    | Privilege elevation stack |
+-----------------------------+ <- z_priv_stack_find(thread.stack_obj) +
K_KERNEL_STACK_RESERVED +
CONFIG_PRIVILEGED_STACK_SIZE
+-----------------------------+ <- thread.stack_obj
    | MPU guard carve-out        |
    | (supervisor mode only)     |
    |.............................| <- thread.stack_info.start
    | Stack buffer              |
```

The guard carve-out in the thread stack object is only used if the thread is running in supervisor mode. If the thread drops to user mode, there is no guard and the entire object is used as the stack buffer, with full access to the associated user mode thread and thread.stack_info updated appropriately.

**User Mode Threads**

To support user mode threads, several kernel-to-arch APIs need to be implemented, and the system must enable the CONFIG_ARCH_HAS_USERSPACE option. Please see the documentation for each of these functions for more details:

- `arch_buffer_validate()` to test whether the current thread has access permissions to a particular memory region
- `arch_user_mode_enter()` which will irreversibly drop a supervisor thread to user mode privileges. The stack must be wiped.
- `arch_syscall_oops()` which generates a kernel oops when system call parameters can’t be validated, in such a way that the oops appears to be generated from where the system call was invoked in the user thread
• `arch_syscall_invoke0()` through `arch_syscall_invoke6()` invoke a system call with the appropriate number of arguments which must all be passed in during the privilege elevation via registers.

• `arch_is_user_context()` return nonzero if the CPU is currently running in user mode

• `arch_mem_domain_max_partitions_get()` which indicates the max number of regions for a memory domain. MMU systems have an unlimited amount, MPU systems have constraints on this.

Some architectures may need to update software memory management structures or modify hardware registers on another CPU when memory domain APIs are invoked. If so, `CONFIG_ARCH_MEM_DOMAIN_SYNCHRONOUS_API` must be selected by the architecture and some additional APIs must be implemented. This is common on MMU systems and uncommon on MPU systems:

• `arch_mem_domain_thread_add()`

• `arch_mem_domain_thread_remove()`

• `arch_mem_domain_partition_add()`

• `arch_mem_domain_partition_remove()`

Please see the doxygen documentation of these APIs for details.

In addition to implementing these APIs, there are some other tasks as well:

• `_new_thread()` needs to spawn threads with `K_USER` in user mode

• On context switch, the outgoing thread's stack memory should be marked inaccessible to user mode by making the appropriate configuration changes in the memory management hardware. The incoming thread's stack memory should likewise be marked as accessible. This ensures that threads can't mess with other thread stacks.

• On context switch, the system needs to switch between memory domains for the incoming and outgoing threads.

• Thread stack areas must include a kernel stack region. This should be inaccessible to user threads at all times. This stack will be used when system calls are made. This should be fixed size for all threads, and must be large enough to handle any system call.

• A software interrupt or some kind of privilege elevation mechanism needs to be established. This is closely tied to how the `arch_syscall_invoke` macros are implemented. On system call, the appropriate handler function needs to be looked up in `_k_syscall_table`. Bad system call IDs should jump to the `K_SYSCALL_BAD` handler. Upon completion of the system call, care must be taken not to leak any register state back to user mode.

GDB Stub

To enable GDB stub for remote debugging on a new architecture:

1. Create a new `gdbstub.h` header file under appropriate architecture include directory (include/arch/<arch>/gdbstub.h).
   - Create a new struct struct `gdb_ctx` as the GDB context.
     - Must define a member named `exception` of type `unsigned int` to store the GDB exception reason. This value needs to be set before entering `z_gdb_main_loop()`.
     - Architecture can define as many members as needed for GDB stub to function.
     - Pointer to this struct needs to be passed to `z_gdb_main_loop()`, where this pointer will be passed to other GDB stub functions.

2. Functions for entering and exiting GDB stub main loop.
• If the architecture relies on interrupts to service breakpoints, interrupt service routines (ISR) need to be implemented, which will serve as the entry point to GDB stub main loop.

• These functions need to save and restore context so code execution can continue as if no breakpoints have been encountered.

• These functions need to call z_gdb_main_loop() after saving execution context to go into the GDB stub main loop to receive commands from GDB.

• Before calling z_gdb_main_loop(), gdb_ctx.exception must be set to specify the exception reason.

3. Implement necessary functions to support GDB stub functionality:

• arch_gdb_init()
  – This needs to initialize necessary bits to support GDB stub functionality, for example, setting up the GDB context and connecting debug interrupts.
  – This must stop code execution via architecture specific method (e.g. raising debug interrupts). This allows GDB to connect during boot.

• arch_gdb_continue()
  – This function is called when GDB sends a `c` or `continue` command to continue code execution.

• arch_gdb_step()
  – This function is called when GDB sends a `si` or `stepi` command to execute one machine instruction, before returning to GDB prompt.

• Hardware register read/write functions:
  – Since the GDB stub is running on the target, manipulation of hardware registers need to cached to avoid affecting the execution of GDB stub. Think of it as context switching, where the execution context is changed to the GDB stub. So that the register values of the running thread before context switch need to be stored. Manipulation of register values must only be done to this cached copy. The updated values will then be written to hardware registers before switching back to the previous running thread.

    – arch_gdb_reg_readall()
      * This collects all hardware register values that would appear in a G packets which will be sent back to GDB. The format of the G-packet is architecture specific. Consult GDB on what is expected.
      * Note that, for most architectures, a valid G-packet must be returned and sent to GDB. If a packet without incorrect length is sent to GDB, GDB will abort the debugging session.

    – arch_gdb_reg_writeall()
      * This takes a G-packet sent by GDB and populates the hardware registers with values from the G-packet.

    – arch_gdb_reg_readone()
      * This reads the value of one hardware register and sends the result to GDB.

    – arch_gdb_reg_writeone()
      * This writes the value of one hardware register received from GDB.

• Breakpoints:
  – arch_gdb_add_breakpoint() and arch_gdb_remove_breakpoint()
– GDB may decide to use software breakpoints which modifies the memory at the breakpoint locations to replace the instruction with software breakpoint or trap instructions. GDB will then restore the memory content once execution reaches the breakpoints. GDB supports this by default and there is usually no need to handle software breakpoints in the architecture code (where breakpoint type is 0).

– Hardware breakpoints (type 1) are required if the code is in ROM or flash that cannot be modified at runtime. Consult the architecture datasheet on how to enable hardware breakpoints.

– If hardware breakpoints are not supported by the architecture, there is no need to implement these in architecture code. GDB will then rely on software breakpoints.

4. For architecture where certain memory regions are not accessible, an array named `gdb_mem_region_array` of type `gdb_mem_region` needs to be defined to specify regions that are accessible. For each array item:
   • `gdb_mem_region.start` specifies the start of a memory region.
   • `gdb_mem_region.end` specifies the end of a memory region.
   • `gdb_mem_region.attributes` specifies the permission of a memory region.
     - `GDB_MEM_REGION_RO`: region is read-only.
     - `GDB_MEM_REGION_RW`: region is read-write.
   • `gdb_mem_region.alignment` specifies read/write alignment of a memory region. Use 0 if there is no alignment requirement and read/write can be done byte-by-byte.

API Reference

Timing

group arch-timing

Functions

void arch_busy_wait(uint32_t usec_to_wait)
   Architecture-specific implementation of busy-waiting.

   Parameters
   • `usec_to_wait` – Wait period, in microseconds

static inline uint32_t arch_k_cycle_get_32(void)
   Obtain the current cycle count, in units specified by CONFIG_SYS_CLOCK_HW_CYCLES_PER_SEC.

   While this is historically specified as part of the architecture API, in practice virtually all platforms forward it to the sys_clock_cycle_get_32() API provided by the timer driver.

See also:

   `k_cycle_get_32()`

Returns

   The current cycle time. This should count up monotonically through the full 32 bit space, wrapping at 0xffffffff. Hardware with fewer bits of precision in the timer is expected to synthesize a 32 bit count.
static inline uint64_t arch_k_cycle_get_64(void)
As for arch_k_cycle_get_32(), but with a 64 bit return value.

Not all timer hardware has a 64 bit timer; this needs to be implemented only if CONFIG_TIMER_HAS_64BIT_CYCLE_COUNTER is set.

See also:
arch_k_cycle_get_32()

Returns
The current cycle time. This should count up monotonically through the full 64 bit space, wrapping at $2^{64} - 1$. Hardware with fewer bits of precision in the timer is generally not expected to implement this API.

Threads

group arch-threads

Functions

void arch_new_thread(struct k_thread *thread, k_thread_stack_t *stack, char *stack_ptr,
                     k_thread_entry_t entry, void *p1, void *p2, void *p3)
Handle arch-specific logic for setting up new threads.

The stack and arch-specific thread state variables must be set up such that a later attempt to switch to this thread will succeed and we will enter z_thread_entry with the requested thread and arguments as its parameters.

At some point in this function’s implementation, z_setup_new_thread() must be called with the true bounds of the available stack buffer within the thread's stack object.

The provided stack pointer is guaranteed to be properly aligned with respect to the CPU and ABI requirements. There may be space reserved between the stack pointer and the bounds of the stack buffer for initial stack pointer randomization and thread-local storage.

Fields in thread->base will be initialized when this is called.

Parameters

• thread – Pointer to uninitialized struct k_thread
• stack – Pointer to the stack object
• stack_ptr – Aligned initial stack pointer
• entry – Thread entry function
• p1 – 1st entry point parameter
• p2 – 2nd entry point parameter
• p3 – 3rd entry point parameter

static inline void arch_switch(void *switch_to, void **switched_from)
Cooperative context switch primitive.

The action of arch_switch() should be to switch to a new context passed in the first argument, and save a pointer to the current context into the address passed in the second argument.
The actual type and interpretation of the switch handle is specified by the architecture. It is the same data structure stored in the “switch_handle” field of a newly-created thread in \texttt{arch_new_thread()}, and passed to the kernel as the “interrupted” argument to \texttt{z_get_next_switch_handle()}.

Note that on SMP systems, the kernel uses the store through the second pointer as a synchronization point to detect when a thread context is completely saved (so another CPU can know when it is safe to switch). This store must be done AFTER all relevant state is saved, and must include whatever memory barriers or cache management code is required to be sure another CPU will see the result correctly.

The simplest implementation of \texttt{arch_switch()} is generally to push state onto the thread stack and use the resulting stack pointer as the switch handle. Some architectures may instead decide to use a pointer into the thread struct as the “switch handle” type. These can legally assume that the second argument to \texttt{arch_switch()} is the address of the switch_handle field of struct thread_base and can use an offset on this value to find other parts of the thread struct. For example a (C pseudocode) implementation of \texttt{arch_switch()} might look like:

```c
void arch_switch(void *switch_to, void **switched_from) { struct k_thread *new = switch_to; struct k_thread *old = CONTAINER_OF(switched_from, struct k_thread, switch_handle);
    // save old context... *switched_from = old; // restore new context... }
```

Note that the kernel manages the switch_handle field for synchronization as described above. So it is not legal for architecture code to assume that it has any particular value at any other time. In particular it is not legal to read the field from the address passed in the second argument.

**Parameters**

- \texttt{switch_to} – Incoming thread's switch handle
- \texttt{switched_from} – Pointer to outgoing thread's switch handle storage location, which must be updated.

void \texttt{arch_switch_to_main_thread(struct k_thread *main_thread, char *stack_ptr, k_thread_entry_t _main)}

Custom logic for entering main thread context at early boot.

Used by architectures where the typical trick of setting up a dummy thread in early boot context to “switch out” of isn't workable.

**Parameters**

- \texttt{main_thread} – main thread object
- \texttt{stack_ptr} – Initial stack pointer
- \texttt{_main} – Entry point for application main function.

int \texttt{arch_float_disable(struct k_thread *thread)}

Disable floating point context preservation.

The function is used to disable the preservation of floating point context information for a particular thread.

**Note:** For ARM architecture, disabling floating point preservation may only be requested for the current thread and cannot be requested in ISRs.

**Return values**

- \texttt{0} – On success.
int arch_float_enable(struct k_thread *thread, unsigned int options)
Enable floating point context preservation.

The function is used to enable the preservation of floating point context information for a particular thread. This API depends on each architecture implementation. If the architecture does not support enabling, this API will always be failed.

The options parameter indicates which floating point register sets will be used by the specified thread. Currently it is used by x86 only.

Parameters
- thread – ID of thread.
- options – architecture dependent options

Return values
- 0 – On success.
- EINVAL – If the floating point enabling could not be performed.
- ENOTSUP – If the operation is not supported

Functions

group arch-tls

size_t arch_tls_stack_setup(struct k_thread *new_thread, char *stack_ptr)
Setup Architecture-specific TLS area in stack.

This sets up the stack area for thread local storage. The structure inside TLS area is architecture specific.

Parameters
- new_thread – New thread object
- stack_ptr – Stack pointer

Returns
Number of bytes taken by the TLS area

Power Management

group arch-pm

Functions

FUNC_NORETURN void arch_system_halt(unsigned int reason)
Halt the system, optionally propagating a reason code.
void arch_cpu_idle(void)
    Power save idle routine.
    This function will be called by the kernel idle loop or possibly within an implementation
    of z_pm_save_idle in the kernel when the '_pm_save_flag' variable is non-zero.
    Architectures that do not implement power management instructions may immediately return, otherwise a power-saving instruction should be issued to wait for an interrupt.

See also:
    k_cpu_idle()

Note: The function is expected to return after the interrupt that has caused the CPU
to exit power-saving mode has been serviced, although this is not a firm requirement.

void arch_cpu_atomic_idle(unsigned int key)
    Atomically re-enable interrupts and enter low power mode.
    The requirements for arch_cpu_atomic_idle() are as follows:

    a. Enabling interrupts and entering a low-power mode needs to be atomic, i.e. there
should be no period of time where interrupts are enabled before the processor
enters a low-power mode. See the comments in k_lifo_get(), for example, of the
race condition that occurs if this requirement is not met.
    b. After waking up from the low-power mode, the interrupt lockout state must be
restored as indicated in the 'key' input parameter.

See also:
    k_cpu_atomic_idle()

Parameters

• key – Lockout key returned by previous invocation of arch_irq_lock()

Symmetric Multi-Processing

group arch-smp

Typedefs

typedef void (*arch_cpustart_t)(void *data)
    Per-cpu entry function.

Param data
    context parameter, implementation specific
Functions

```c
void arch_start_cpu(int cpu_num, k_thread_stack_t *stack, int sz, arch_cpustart_t fn, void *arg)
```

Start a numbered CPU on a MP-capable system.

This starts and initializes a specific CPU. The main thread on startup is running on
CPU zero, other processors are numbered sequentially. On return from this function,
the CPU is known to have begun operating and will enter the provided function. Its
interrupts will be initialized but disabled such that `irq_unlock()` with the provided key
will work to enable them.

Normally, in SMP mode this function will be called by the kernel initialization and
should not be used as a user API. But it is defined here for special-purpose apps which
want Zephyr running on one core and to use others for design-specific processing.

**Parameters**

- `cpu_num` – Integer number of the CPU
- `stack` – Stack memory for the CPU
- `sz` – Stack buffer size, in bytes
- `fn` – Function to begin running on the CPU.
- `arg` – Untyped argument to be passed to “fn”

```c
bool arch_cpu_active(int cpu_num)
```

Return CPU power status.

**Parameters**

- `cpu_num` – Integer number of the CPU

```c
static inline struct _cpu *arch_curr_cpu(void)
```

Return the CPU struct for the currently executing CPU.

```c
static inline uint32_t arch_proc_id(void)
```

Processor hardware ID.

Most multiprocessor architectures have a low-level unique ID value associated with
the current CPU that can be retrieved rapidly and efficiently in kernel context. Note
that while the numbering of the CPUs is guaranteed to be unique, the values are
platform-defined. In particular, they are not guaranteed to match Zephyr’s own se-
quential CPU IDs (even though on some platforms they do).

**Note:** There is an inherent race with this API: the system may preempt the current
thread and migrate it to another CPU before the value is used. Safe usage requires
knowing the migration is impossible (e.g. because the code is in interrupt context,
holds a spinlock, or cannot migrate due to k_cpu_mask state).

**Returns**

Unique ID for currently-executing CPU

```c
void arch_sched_ipi(void)
```

Broadcast an interrupt to all CPUs.

This will invoke `z_sched_ipi()` on other CPUs in the system.

```c
int arch_smp_init(void)
```
static inline unsigned int arch_num_cpus(void)
    Returns the number of CPUs.
    For most systems this will be the same as CONFIG_MP_MAX_NUM_CPUS, however
    some systems may determine this at runtime instead.

Returns
    the number of CPUs

Interrupts

Functions

static inline bool arch_is_in_isr(void)
    Test if the current context is in interrupt context.
    XXX: This is inconsistently handled among arches wrt exception context See: #17656

Returns
    true if we are in interrupt context

static inline unsigned int arch_irq_lock(void)
    Lock interrupts on the current CPU.

See also:
    irq_lock()

static inline void arch_irq_unlock(unsigned int key)
    Unlock interrupts on the current CPU.

See also:
    irq_unlock()

static inline bool arch_irq_unlocked(unsigned int key)
    Test if calling arch_irq_unlock() with this key would unlock irqs.

Parameters
    • key – value returned by arch_irq_lock()

Returns
    true if interrupts were unlocked prior to the arch_irq_lock() call that pro-
    duced the key argument.

void arch_irq_disable(unsigned int irq)
    Disable the specified interrupt line.

See also:
    irq_disable()

Note: The behavior of interrupts that arrive after this call returns and before the
    corresponding call to arch_irq_enable() is undefined. The hardware is not required
to latch and deliver such an interrupt, though on some architectures that may work.
Other architectures will simply lose such an interrupt and never deliver it. Many drivers and subsystems are not tolerant of such dropped interrupts and it is the job of the application layer to ensure that behavior remains correct.

```c
void arch_irq_enable(unsigned int irq)
Enable the specified interrupt line.

See also:
irq_enable()
```

```c
int arch_irq_is_enabled(unsigned int irq)
Test if an interrupt line is enabled.

See also:
irq_is_enabled()
```

```c
int arch_irq_connect_dynamic(unsigned int irq, unsigned int priority, void (*routine)(const void *parameter), const void *parameter, uint32_t flags)
Arch-specific hook to install a dynamic interrupt.

Parameters
- irq – IRQ line number
- priority – Interrupt priority
- routine – Interrupt service routine
- parameter – ISR parameter
- flags – Arch-specific IRQ configuration flag

Returns
The vector assigned to this interrupt
```

```c
int arch_irq_disconnect_dynamic(unsigned int irq, unsigned int priority, void (*routine)(const void *parameter), const void *parameter, uint32_t flags)
Arch-specific hook to dynamically uninstall a shared interrupt.
If the interrupt is not being shared, then the associated _sw_isr_table entry will be replaced by (NULL, z_irq_spurious) (default entry).

Parameters
- irq – IRQ line number
- priority – Interrupt priority
- routine – Interrupt service routine
- parameter – ISR parameter
- flags – Arch-specific IRQ configuration flag

Returns
0 in case of success, negative value otherwise
```
unsigned int arch_irq_allocate(void)
Arch-specific hook for allocating IRQs.

Note: disable/enable IRQ relevantly inside the implementation of such function to
avoid concurrency issues. Also, an allocated IRQ is assumed to be used thus a following
See also:
arch_irq_is_used() should return true.

Returns
The newly allocated IRQ or UINT_MAX on error.

void arch_irq_set_used(unsigned int irq)
Arch-specific hook for declaring an IRQ being used.

Note: disable/enable IRQ relevantly inside the implementation of such function to
avoid concurrency issues.

Parameters
• irq – the IRQ to declare being used

bool arch_irq_is_used(unsigned int irq)
Arch-specific hook for checking if an IRQ is being used already.

Parameters
• irq – the IRQ to check

Returns
ture if being, false otherwise

Userspace

group arch-userspace

Functions

static inline uintptr_t arch_syscall_invoke0(uintptr_t call_id)
Invoke a system call with 0 arguments.

No general-purpose register state other than return value may be preserved when
transitioning from supervisor mode back down to user mode for security reasons.

It is required that all arguments be stored in registers when elevating privileges from
user to supervisor mode.

Processing of the syscall takes place on a separate kernel stack. Interrupts should be
enabled when invoking the system call marshalers from the dispatch table. Thread
preemption may occur when handling system calls.

Call IDs are untrusted and must be bounds-checked, as the value is used to index the
system call dispatch table, containing function pointers to the specific system call code.

Parameters
• call_id – System call ID

Returns
Return value of the system call. Void system calls return 0 here.
static inline uintptr_t arch_syscall_invoke1(uintptr_t arg1, uintptr_t call_id)
    Invoke a system call with 1 argument.

See also:
arch_syscall_invoke0()

Parameters
• **arg1** – First argument to the system call.
• **call_id** – System call ID, will be bounds-checked and used to reference
  kernel-side dispatch table

Returns
Return value of the system call. Void system calls return 0 here.

static inline uintptr_t arch_syscall_invoke2(uintptr_t arg1, uintptr_t arg2, uintptr_t call_id)
    Invoke a system call with 2 arguments.

See also:
arch_syscall_invoke0()

Parameters
• **arg1** – First argument to the system call.
• **arg2** – Second argument to the system call.
• **call_id** – System call ID, will be bounds-checked and used to reference
  kernel-side dispatch table

Returns
Return value of the system call. Void system calls return 0 here.

static inline uintptr_t arch_syscall_invoke3(uintptr_t arg1, uintptr_t arg2, uintptr_t arg3, uintptr_t call_id)
    Invoke a system call with 3 arguments.

See also:
arch_syscall_invoke0()

Parameters
• **arg1** – First argument to the system call.
• **arg2** – Second argument to the system call.
• **arg3** – Third argument to the system call.
• **call_id** – System call ID, will be bounds-checked and used to reference
  kernel-side dispatch table

Returns
Return value of the system call. Void system calls return 0 here.
static inline uintptr_t arch_syscall_invoke4(uintptr_t arg1, uintptr_t arg2, uintptr_t arg3, uintptr_t arg4, uintptr_t call_id)

Invoke a system call with 4 arguments.

See also:
arch_syscall_invoke0()

Parameters
• arg1 – First argument to the system call.
• arg2 – Second argument to the system call.
• arg3 – Third argument to the system call.
• arg4 – Fourth argument to the system call.
• call_id – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

Returns
Return value of the system call. Void system calls return 0 here.

static inline uintptr_t arch_syscall_invoke5(uintptr_t arg1, uintptr_t arg2, uintptr_t arg3, uintptr_t arg4, uintptr_t arg5, uintptr_t call_id)

Invoke a system call with 5 arguments.

See also:
arch_syscall_invoke0()

Parameters
• arg1 – First argument to the system call.
• arg2 – Second argument to the system call.
• arg3 – Third argument to the system call.
• arg4 – Fourth argument to the system call.
• arg5 – Fifth argument to the system call.
• call_id – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

Returns
Return value of the system call. Void system calls return 0 here.

static inline uintptr_t arch_syscall_invoke6(uintptr_t arg1, uintptr_t arg2, uintptr_t arg3, uintptr_t arg4, uintptr_t arg5, uintptr_t arg6, uintptr_t call_id)

Invoke a system call with 6 arguments.

See also:
arch_syscall_invoke0()

Parameters
• arg1 – First argument to the system call.
• **arg2** – Second argument to the system call.
• **arg3** – Third argument to the system call.
• **arg4** – Fourth argument to the system call.
• **arg5** – Fifth argument to the system call.
• **arg6** – Sixth argument to the system call.
• **call_id** – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

**Returns**
Return value of the system call. Void system calls return 0 here.

static inline bool arch_is_user_context(void)
Indicate whether we are currently running in user mode.

**Returns**
True if the CPU is currently running with user permissions

int arch_mem_domain_max_partitions_get(void)
Get the maximum number of partitions for a memory domain.

**Returns**
Max number of partitions, or -1 if there is no limit

int arch_buffer_validate(void *addr, size_t size, int write)
Check memory region permissions.
Given a memory region, return whether the current memory management hardware configuration would allow a user thread to read/write that region. Used by system calls to validate buffers coming in from userspace.

Notes: The function is guaranteed to never return validation success, if the entire buffer area is not user accessible.
The function is guaranteed to correctly validate the permissions of the supplied buffer, if the user access permissions of the entire buffer are enforced by a single, enabled memory management region.
In some architectures the validation will always return failure if the supplied memory buffer spans multiple enabled memory management regions (even if all such regions permit user access).

**Warning:** Buffer of size zero (0) has undefined behavior.

**Parameters**
• **addr** – start address of the buffer
• **size** – the size of the buffer
• **write** – If non-zero, additionally check if the area is writable. Otherwise, just check if the memory can be read.

**Returns**
nonzero if the permissions don’t match.

size_t arch_virt_region_align(uintptr_t phys, size_t size)
Get the optimal virtual region alignment to optimize the MMU table layout.
Some MMU HW requires some region to be aligned to some of the intermediate block alignment in order to reduce table usage. This call returns the optimal virtual address alignment in order to permit such optimization in the following MMU mapping call.

**Parameters**

- `phys` – [in] Physical address of region to be mapped, aligned to CONFIG_MMU_PAGE_SIZE
- `size` – [in] Size of region to be mapped, aligned to CONFIG_MMU_PAGE_SIZE

**Returns**

Alignment to apply on the virtual address of this region

FUNC_NORETURN void `arch_user_mode_enter(k_thread_entry_t user_entry, void *p1, void *p2, void *p3)`

Perform a one-way transition from supervisor to user mode.

Implementations of this function must do the following:

- Reset the thread's stack pointer to a suitable initial value. We do not need any prior context since this is a one-way operation.
- Set up any kernel stack region for the CPU to use during privilege elevation
- Put the CPU in whatever its equivalent of user mode is
- Transfer execution to `arch_new_thread()` passing along all the supplied arguments, in user mode.

**Parameters**

- `user_entry` – Entry point to start executing as a user thread
- `p1` – 1st parameter to user thread
- `p2` – 2nd parameter to user thread
- `p3` – 3rd parameter to user thread

FUNC_NORETURN void `arch_syscall_oops(void *ssf)`

Induce a kernel oops that appears to come from a specific location.

Normally, `k_oops()` generates an exception that appears to come from the call site of the `k_oops()` itself.

However, when validating arguments to a system call, if there are problems we want the oops to appear to come from where the system call was invoked and not inside the validation function.

**Parameters**

- `ssf` – System call stack frame pointer. This gets passed as an argument to _k_syscall_handler_t functions and its contents are completely architecture specific.

`size_t arch_user_string_nlen(const char *s, size_t maxsize, int *err)`

Safely take the length of a potentially bad string.

This must not fault, instead the `err` parameter must have -1 written to it. This function otherwise should work exactly like libc `strnlen()`. On success `err` should be set to 0.

**Parameters**

- `s` – String to measure
- `maxsize` – Max length of the string
• **err** – Error value to write

**Returns**
Length of the string, not counting NULL byte, up to maxsize

```c
static inline bool arch_mem_coherent(void *ptr)
```
Detect memory coherence type.

Required when ARCH_HAS_COHERENCE is true. This function returns true if the byte pointed to lies within an architecture-defined “coherence region” (typically implemented with uncached memory) and can safely be used in multiprocessor code without explicit flush or invalidate operations.

**Note:** The result is for only the single byte at the specified address, this API is not required to check region boundaries or to expect aligned pointers. The expectation is that the code above will have queried the appropriate address(es).

```c
static inline void arch_cohere_stacks(struct k_thread *old_thread, void *old_switch_handle, struct k_thread *new_thread)
```
Ensure cache coherence prior to context switch.

Required when ARCH_HAS_COHERENCE is true. On cache-incoherent multiprocessor architectures, thread stacks are cached by default for performance reasons. They must therefore be flushed appropriately on context switch. The rules are:

a. The region containing live data in the old stack (generally the bytes between the current stack pointer and the top of the stack memory) must be flushed to underlying storage so a new CPU that runs the same thread sees the correct data. This must happen before the assignment of the switch_handle field in the thread struct which signals the completion of context switch.

b. Any data areas to be read from the new stack (generally the same as the live region when it was saved) should be invalidated (and NOT flushed!) in the data cache. This is because another CPU may have run or re-initialized the thread since this CPU suspended it, and any data present in cache will be stale.

**Note:** The kernel will call this function during interrupt exit when a new thread has been chosen to run, and also immediately before entering `arch_switch()` to effect a code-driven context switch. In the latter case, it is very likely that more data will be written to the old_thread stack region after this function returns but before the completion of the switch. Simply flushing naively here is not sufficient on many architectures and coordination with the `arch_switch()` implementation is likely required.

**Parameters**

- **old_thread** – The old thread to be flushed before being allowed to run on other CPUs.
- **old_switch_handle** – The switch handle to be stored into old_thread (it will not be valid until the cache is flushed so is not present yet). This will be NULL if inside `z_swap()` (because the `arch_switch()` has not saved it yet).
- **new_thread** – The new thread to be invalidated before it runs locally.
group arch-mmu

Defines

ARCH_DATA_PAGE_ACCESSED
  Bit indicating the data page was accessed since the value was last cleared.
  Used by marking eviction algorithms. Safe to set this if uncertain.
  This bit is undefined if ARCH_DATA_PAGE_LOADED is not set.

ARCH_DATA_PAGE_DIRTY
  Bit indicating the data page, if evicted, will need to be paged out.
  Set if the data page was modified since it was last paged out, or if it has never been
  paged out before. Safe to set this if uncertain.
  This bit is undefined if ARCH_DATA_PAGE_LOADED is not set.

ARCH_DATA_PAGE_LOADED
  Bit indicating that the data page is loaded into a physical page frame.
  If un-set, the data page is paged out or not mapped.

ARCH_DATA_PAGE_NOT_MAPPED
  If ARCH_DATA_PAGE_LOADED is un-set, this will indicate that the page is not mapped
  at all.
  This bit is undefined if ARCH_DATA_PAGE_LOADED is set.

Enums

enum arch_page_location
  Status of a particular page location.
  Values:

  enumerator ARCH_PAGE_LOCATION_PAGED_OUT
    The page has been evicted to the backing store.

  enumerator ARCH_PAGE_LOCATION_PAGED_IN
    The page is resident in memory.

  enumerator ARCH_PAGE_LOCATION_BAD
    The page is not mapped.

Functions
void arch_mem_map(void *virt, uintptr_t phys, size_t size, uint32_t flags)
Map physical memory into the virtual address space.

This is a low-level interface to mapping pages into the address space. Behavior when providing unaligned addresses/sizes is undefined, these are assumed to be aligned to CONFIG_MMU_PAGE_SIZE.

The core kernel handles all management of the virtual address space; by the time we invoke this function, we know exactly where this mapping will be established. If the page tables already had mappings installed for the virtual memory region, these will be overwritten.

If the target architecture supports multiple page sizes, currently only the smallest page size will be used.

The memory range itself is never accessed by this operation.

This API must be safe to call in ISRs or exception handlers. Calls to this API are assumed to be serialized, and indeed all usage will originate from kernel/mm.c which handles virtual memory management.

Architectures are expected to pre-allocate page tables for the entire address space, as defined by CONFIG_KERNEL_VM_BASE and CONFIG_KERNEL_VM_SIZE. This operation should never require any kind of allocation for paging structures.

Validation of arguments should be done via assertions.

This API is part of infrastructure still under development and may change.

Parameters

• virt – Page-aligned Destination virtual address to map
• phys – Page-aligned Source physical address to map
• size – Page-aligned size of the mapped memory region in bytes
• flags – Caching, access and control flags, see K_MAP_* macros

void arch_mem_unmap(void *addr, size_t size)
Remove mappings for a provided virtual address range.

This is a low-level interface for un-mapping pages from the address space. When this completes, the relevant page table entries will be updated as if no mapping was ever made for that memory range. No previous context needs to be preserved. This function must update mappings in all active page tables.

Behavior when providing unaligned addresses/sizes is undefined, these are assumed to be aligned to CONFIG_MMU_PAGE_SIZE.

Behavior when providing an address range that is not already mapped is undefined.

This function should never require memory allocations for paging structures, and it is not necessary to free any paging structures. Empty page tables due to all contained entries being un-mapped may remain in place.

Implementations must invalidate TLBs as necessary.

This API is part of infrastructure still under development and may change.

Parameters

• addr – Page-aligned base virtual address to un-map
• size – Page-aligned region size
int arch_page_phys_get(void *virt, uintptr_t *phys)
Get the mapped physical memory address from virtual address.

The function only needs to query the current set of page tables as the information it reports must be common to all of them if multiple page tables are in use. If multiple page tables are active it is unnecessary to iterate over all of them.

Unless otherwise specified, virtual pages have the same mappings across all page tables. Calling this function on data pages that are exceptions to this rule (such as the scratch page) is undefined behavior. Just check the currently installed page tables and return the information in that.

Parameters
• virt – Page-aligned virtual address
• phys – [out] Mapped physical address (can be NULL if only checking if virtual address is mapped)

Return values
• 0 – if mapping is found and valid
• -EFAULT – if virtual address is not mapped

void arch_reserved_pages_update(void)
Update page frame database with reserved pages.

Some page frames within system RAM may not be available for use. A good example of this is reserved regions in the first megabyte on PC-like systems.

Implementations of this function should mark all relevant entries in z_page_frames with K_PAGE_FRAME_RESERVED. This function is called at early system initialization with mm_lock held.

void arch_mem_page_out(void *addr, uintptr_t location)
Update all page tables for a paged-out data page.

This function:
• Sets the data page virtual address to trigger a fault if accessed that can be distinguished from access violations or un-mapped pages.
• Saves the provided location value so that it can retrieved for that data page in the page fault handler.
• The location value semantics are undefined here but the value will be always be page-aligned. It could be 0.

If multiple page tables are in use, this must update all page tables. This function is called with interrupts locked.

Calling this function on data pages which are already paged out is undefined behavior.

This API is part of infrastructure still under development and may change.

void arch_mem_page_in(void *addr, uintptr_t phys)
Update all page tables for a paged-in data page.

This function:
• Maps the specified virtual data page address to the provided physical page frame address, such that future memory accesses will function as expected. Access and caching attributes are undisturbed.
• Clears any accounting for “accessed” and “dirty” states.
If multiple page tables are in use, this must update all page tables. This function is called with interrupts locked.

Calling this function on data pages which are already paged in is undefined behavior. This API is part of infrastructure still under development and may change.

```c
void arch_mem_scratch(uintptr_t phys)
```

Update current page tables for a temporary mapping.

Map a physical page frame address to a special virtual address Z_SCRATCH_PAGE, with read/write access to supervisor mode, such that when this function returns, the calling context can read/write the page frame's contents from the Z_SCRATCH_PAGE address.

This mapping only needs to be done on the current set of page tables, as it is only used for a short period of time exclusively by the caller. This function is called with interrupts locked.

This API is part of infrastructure still under development and may change.

```c
eenum arch_page_location
enum arch_page_location_get(void *addr, uintptr_t *location)
```

Fetch location information about a page at a particular address.

The function only needs to query the current set of page tables as the information it reports must be common to all of them if multiple page tables are in use. If multiple page tables are active it is unnecessary to iterate over all of them. This may allow certain types of optimizations (such as reverse page table mapping on x86).

This function is called with interrupts locked, so that the reported information can’t become stale while decisions are being made based on it.

Unless otherwise specified, virtual data pages have the same mappings across all page tables. Calling this function on data pages that are exceptions to this rule (such as the scratch page) is undefined behavior. Just check the currently installed page tables and return the information in that.

**Parameters**

- `addr` – Virtual data page address that took the page fault
- `location` – [out] In the case of ARCH_PAGE_FAULT_PAGED_OUT, the backing store location value used to retrieve the data page. In the case of ARCH_PAGE_FAULT_PAGED_IN, the physical address the page is mapped to.

**Return values**

- `ARCH_PAGE_FAULT_PAGED_OUT` – The page was evicted to the backing store.
- `ARCH_PAGE_FAULT_PAGED_IN` – The data page is resident in memory.
- `ARCH_PAGE_FAULT_BAD` – The page is un-mapped or otherwise has had invalid access

```c
uintptr_t arch_page_info_get(void *addr, uintptr_t *location, bool clear_accessed)
```

Retrieve page characteristics from the page table(s)

The architecture is responsible for maintaining “accessed” and “dirty” states of data pages to support marking eviction algorithms. This can either be directly supported by hardware or emulated by modifying protection policy to generate faults on reads or writes. In all cases the architecture must maintain this information in some way.

For the provided virtual address, report the logical OR of the accessed and dirty states for the relevant entries in all active page tables in the system if the page is mapped and not paged out.
If clear_accessed is true, the ARCH_DATA_PAGE_ACCESSED flag will be reset. This function will report its prior state. If multiple page tables are in use, this function clears accessed state in all of them.

This function is called with interrupts locked, so that the reported information can’t become stale while decisions are being made based on it.

The return value may have other bits set which the caller must ignore.

Clearing accessed state for data pages that are not ARCH_DATA_PAGE_LOADED is undefined behavior.

ARCH_DATA_PAGE_DIRTY and ARCH_DATA_PAGE_ACCESSED bits in the return value are only significant if ARCH_DATA_PAGE_LOADED is set, otherwise ignore them.

ARCH_DATA_PAGE_NOT_MAPPED bit in the return value is only significant if ARCH_DATA_PAGE_LOADED is un-set, otherwise ignore it.

Unless otherwise specified, virtual data pages have the same mappings across all page tables. Calling this function on data pages that are exceptions to this rule (such as the scratch page) is undefined behavior.

This API is part of infrastructure still under development and may change.

**Parameters**

- **addr** – Virtual address to look up in page tables
- **location** – ![out] If non-NULL, updated with either physical page frame address or backing store location depending on ARCH_DATA_PAGE_LOADED state. This is not touched if ARCH_DATA_PAGE_NOT_MAPPED.
- **clear_accessed** – Whether to clear ARCH_DATA_PAGE_ACCESSED state

**Return values**

Value – with ARCH_DATA_PAGE_* bits set reflecting the data page configuration

---

**Miscellaneous Architecture APIs**

*group arch-misc*

**Functions**

```
int arch_printk_char_out(int c)
```

Early boot console output hook.

Definition of this function is optional. If implemented, any invocation of printk() (or logging calls with CONFIG_LOG_MODE_MINIMAL which are backed by printk) will default to sending characters to this function. It is useful for early boot debugging before main serial or console drivers come up.

This can be overridden at runtime with __printk_hook_install().

The default __weak implementation of this does nothing.

**Parameters**

- **c** – Character to print

**Returns**

The character printed
static inline void arch_kernel_init(void)
  Architecture-specific kernel initialization hook.
  This function is invoked near the top of z_cstart, for additional architecture-specific
  setup before the rest of the kernel is brought up.

static inline void arch_nop(void)
  Do nothing and return.
  Yawn.

GDB Stub APIs

*group* arch-gdbstub

**Functions**

void arch_gdb_init(void)
  Architecture layer debug start.
  This function is called by gdb_init()

void arch_gdb_continue(void)
  Continue running program.
  Continue software execution.

void arch_gdb_step(void)
  Continue with one step.
  Continue software execution until reaches the next statement.

size_t arch_gdb_reg_readall(struct gdb_ctx *ctx, uint8_t *buf, size_t buflen)
  Read all registers, and outputs as hexadecimal string.
  This reads all CPU registers and outputs as hexadecimal string. The output string must
  be parsable by GDB.

  **Parameters**
  • ctx – GDB context
  • buf – Buffer to output hexadecimal string.
  • buflen – Length of buffer.

  **Returns**
  Length of hexadecimal string written. Return 0 if error or not supported.

size_t arch_gdb_reg_writeall(struct gdb_ctx *ctx, uint8_t *hex, size_t hexlen)
  Take a hexadecimal string and update all registers.
  This takes in a hexadecimal string as presented from GDB, and updates all CPU regis-
  ters with new values.

  **Parameters**
  • ctx – GDB context
  • hex – Input hexadecimal string.
  • hexlen – Length of hexadecimal string.

  **Returns**
  Length of hexadecimal string parsed. Return 0 if error or not supported.
size_t arch_gdb_reg_readone(struct gdb_ctx *ctx, uint8_t *buf, size_t buflen, uint32_t regno)

Read one register, and outputs as hexadecimal string.
This reads one CPU register and outputs as hexadecimal string. The output string must be parsable by GDB.

Parameters
• ctx – GDB context
• buf – Buffer to output hexadecimal string.
• buflen – Length of buffer.
• regno – Register number

Returns
Length of hexadecimal string written. Return 0 if error or not supported.

size_t arch_gdb_reg_writeone(struct gdb_ctx *ctx, uint8_t *hex, size_t hexlen, uint32_t regno)

Take a hexadecimal string and update one register.
This takes in a hexadecimal string as presented from GDB, and updates one CPU registers with new value.

Parameters
• ctx – GDB context
• hex – Input hexadecimal string.
• hexlen – Length of hexadecimal string.
• regno – Register number

Returns
Length of hexadecimal string parsed. Return 0 if error or not supported.

int arch_gdb_add_breakpoint(struct gdb_ctx *ctx, uint8_t type, uintptr_t addr, uint32_t kind)

Add breakpoint or watchpoint.

Parameters
• ctx – GDB context
• type – Breakpoint or watchpoint type
• addr – Address of breakpoint or watchpoint
• kind – Size of breakpoint/watchpoint in bytes

Return values
• 0 – Operation successful
• -1 – Error encountered
• -2 – Not supported

int arch_gdb_remove_breakpoint(struct gdb_ctx *ctx, uint8_t type, uintptr_t addr, uint32_t kind)

Remove breakpoint or watchpoint.

Parameters
• ctx – GDB context
• type – Breakpoint or watchpoint type
• **addr** – Address of breakpoint or watchpoint
• **kind** – Size of breakpoint/watchpoint in bytes

**Return values**
• 0 – Operation successful
• -1 – Error encountered
• -2 – Not supported

### 7.8.2 Board Porting Guide

To add Zephyr support for a new board, you at least need a `board` directory with various files in it. Files in the board directory inherit support for at least one SoC and all of its features. Therefore, Zephyr must support your SoC as well.

**Boards, SoCs, etc.**

Zephyr’s hardware support hierarchy has these layers, from most to least specific:
• Board: a particular CPU instance and its peripherals in a concrete hardware specification
• SoC: the exact system on a chip the board’s CPU is part of
• SoC series: a smaller group of tightly related SoCs
• SoC family: a wider group of SoCs with similar characteristics
• CPU core: a particular CPU in an architecture
• Architecture: an instruction set architecture

You can visualize the hierarchy like this:

![Fig. 5: Configuration Hierarchy](image-url)
Here are some examples. Notice how the SoC series and family levels are not always used.

<table>
<thead>
<tr>
<th>Board</th>
<th>SoC</th>
<th>SoC series</th>
<th>SoC family</th>
<th>CPU core</th>
<th>Architecture</th>
</tr>
</thead>
<tbody>
<tr>
<td>nrf52dk_nrf52832</td>
<td>nRF52832</td>
<td>nRF52</td>
<td>Nordic nRF5</td>
<td>Arm M4</td>
<td>Cortex-Arm</td>
</tr>
<tr>
<td>frdm_k64f</td>
<td>MK64F12</td>
<td>Kinetis K6x</td>
<td>NXP Kinetis</td>
<td>Arm M4</td>
<td>Cortex-Arm</td>
</tr>
<tr>
<td>stm32h747i_disco</td>
<td>STM32H747XI</td>
<td>STM32H7</td>
<td>STMicro STM32</td>
<td>Arm M7</td>
<td>Cortex-Arm</td>
</tr>
<tr>
<td>rv32m1_vega_ri5cy</td>
<td>RV32M1</td>
<td>(Not used)</td>
<td>(Not used)</td>
<td>RI5CY</td>
<td>RISC-V</td>
</tr>
</tbody>
</table>

**Make sure your SoC is supported**

Start by making sure your SoC is supported by Zephyr. If it is, it’s time to *Create your board directory*. If you don’t know, try:

- checking boards for names that look relevant, and reading individual board documentation to find out for sure.
- asking your SoC vendor

If you need to add SoC, CPU core, or even architecture support, this is the wrong page, but here is some general advice.

**Architecture**  See *Architecture Porting Guide*.

**CPU Core**  CPU core support files go in *core* subdirectories under *arch*, e.g. *arch/x86/core*.

See *Install a Toolchain* for information about toolchains (compiler, linker, etc.) supported by Zephyr. If you need to support a new toolchain, *Build and Configuration Systems* is a good place to start learning about the build system. Please reach out to the community if you are looking for advice or want to collaborate on toolchain support.

**SoC**  Zephyr SoC support files are in architecture-specific subdirectories of *soc*. They are generally grouped by SoC family.

When adding a new SoC family or series for a vendor that already has SoC support within Zephyr, please try to extract common functionality into shared files to avoid duplication. If there is no support for your vendor yet, you can add it in a new directory *zephyr/soc/<YOUR-ARCH>/<YOUR-SOC>*; please use self-explanatory directory names.

**Create your board directory**

Once you’ve found an existing board that uses your SoC, you can usually start by copy/pasting its board directory and changing its contents for your hardware.

You need to give your board a unique name. Run *west boards* for a list of names that are already taken, and pick something new. Let’s say your board is called *plank* (please don’t actually use that name).

Start by creating the board directory *zephyr/boards/<ARCH>/plank*, where *<ARCH>* is your SoC’s architecture subdirectory. (You don’t have to put your board directory in the zephyr repository, but it’s the easiest way to get started. See *Custom Board, Devicetree and SOC Definitions* for documentation on moving your board directory to a separate repository once it’s working.)
**Note:** The board directory name does not need to match the name of the board. Multiple boards can even be defined in one directory. For example, for boards with multi-core SoC, a logical board might be created for each core following the naming scheme `<board>_soc-core`, with definitions for all of these different boards defined inside the same directory. This and similar schemes are common for upstream vendor boards.

Your board directory should look like this:

```plaintext
groups/<ARCH>/plank
  ├── board.cmake
  │   └── CMakeLists.txt
  │       └── doc
  │           └── index.rst
  │       └── Kconfig.board
  │       └── Kconfig.defconfig
  │       └── plank_defconfig
  │       └── plank.dts
  │       └── plank.yaml
```

Replace `plank` with your board’s name, of course.

The mandatory files are:

1. `plank.dts`: a hardware description in devicetree format. This declares your SoC, connectors, and any other hardware components such as LEDs, buttons, sensors, or communication peripherals (USB, BLE controller, etc).
2. `Kconfig.board`, `Kconfig.defconfig`, `plank_defconfig`: software configuration in Configuration System (Kconfig) formats. This provides default settings for software features and peripheral drivers.

The optional files are:

- `board.cmake`: used for Flash and debug support
- `CMakeLists.txt`: if you need to add additional source files to your build.
- `doc/index.rst`, `doc/plank.png`: documentation for and a picture of your board. You only need this if you’re Contributing your board to Zephyr.
- `plank.yaml`: a YAML file with miscellaneous metadata used by the Test Runner (Twister).

**Write your devicetree**

The devicetree file `boards/<ARCH>/plank/plank.dts` describes your board hardware in the Devicetree Source (DTS) format (as usual, change `plank` to your board’s name). If you’re new to devicetree, see Introduction to devicetree.

In general, `plank.dts` should look like this:

```plaintext
#include <your_soc_vendor/your_soc.dtsi>

/ {
  model = "A human readable name";
  compatible = "yourcompany,plank";

  chosen {
    zephyr,console = &your_uart_console;
    zephyr,sram = &your_memory_node;
  }
}
```

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If you're in a hurry, simple hardware can usually be supported by copy/paste followed by trial and error. If you want to understand details, you will need to read the rest of the devicetree documentation and the devicetree specification.

**Example: FRDM-K64F and Hexiwear K64**  
This section contains concrete examples related to writing your board's devicetree.

The FRDM-K64F and Hexiwear K64 board devicetrees are defined in frdm_k64fs.dts and hexiwear_k64.dts respectively. Both boards have NXP SoCs from the same Kinetis SoC family, the K6X.

Common devicetree definitions for K6X are stored in nxp_k6x.dtsi, which is included by both board .dts files. nxp_k6x.dtsi in turn includes armv7-m.dtsi, which has common definitions for Arm v7-M cores.

Since nxp_k6x.dtsi is meant to be generic across K6X-based boards, it leaves many devices disabled by default using status properties. For example, there is a CAN controller defined as follows (with unimportant parts skipped):

```dts
&can0: can@40024000 {
    ...status = "disabled";
    ...
};
```
It is up to the board .dts or application overlay files to enable these devices as desired, by setting `status = "okay"`. The board .dts files are also responsible for any board-specific configuration of the device, such as adding nodes for on-board sensors, LEDs, buttons, etc.

For example, FRDM-K64 (but not Hexiwear K64) .dts enables the CAN controller and sets the bus speed:

```
&can0 {
    status = "okay";
    bus-speed = <125000>;
};
```

The &can0 { ... }; syntax adds/overrides properties on the node with label can0, i.e. the can0@4002400 node defined in the .dtsi file.

Other examples of board-specific customization is pointing properties in aliases and chosen to the right nodes (see Aliases and chosen nodes), and making GPIO/pinmux assignments.

**Write Kconfig files**

Zephyr uses the Kconfig language to configure software features. Your board needs to provide some Kconfig settings before you can compile a Zephyr application for it.

Setting Kconfig configuration values is documented in detail in Setting Kconfig configuration values.

There are three mandatory Kconfig files in the board directory for a board named plank:

- `boards/<ARCH>/plank/
  ├── Kconfig.board
  │   └── Kconfig.defconfig
  │       └── plank_defconfig

  **Kconfig.board**

  Included by boards/Kconfig to include your board in the list of options.

  This should at least contain a definition for a BOARD_PLANK option, which looks something like this:

  ```
  config BOARD_PLANK
  bool "Plank board"
  depends on SOC_SERIES_YOUR_SOC_SERIES_HERE
  select SOC_PART_NUMBER_ABCDEFGH
  ```

  **Kconfig.defconfig**

  Board-specific default values for Kconfig options.

  The entire file should be inside an if BOARD_PLANK / endif pair of lines, like this:

  ```
  if BOARD_PLANK
      # Always set CONFIG_BOARD here. This isn't meant to be customized,
      # but is set as a "default" due to Kconfig language restrictions.
      config BOARD
          default "plank"
      # Other options you want enabled by default go next. Examples:
      config FOO
          default y
      if NETWORKING
  ```

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plank_defconfig
A Kconfig fragment that is merged as-is into the final build directory .config whenever an application is compiled for your board.

You should at least select your board's SOC and do any mandatory settings for your system clock, console, etc. The results are architecture-specific, but typically look something like this:

```
CONFIG_SOC_${VENDOR_XYZ3000}=y  # select your SoC
CONFIG_SYS_CLOCK_HW_CYCLES_PER_SEC=12000000  # set up your clock, etc
CONFIG_SERIAL=y
```

plank_x_y_z.conf
A Kconfig fragment that is merged as-is into the final build directory .config whenever an application is compiled for your board revision x.y.z.

Build, test, and fix

Now it's time to build and test the application(s) you want to run on your board until you're satisfied.

For example:

```
west build -b plank samples/hello_world
west flash
```

For west flash to work, see Flash and debug support below. You can also just flash build/zephyr/zephyr.elf, zephyr.hex, or zephyr.bin with any other tools you prefer.

General recommendations

For consistency and to make it easier for users to build generic applications that are not board specific for your board, please follow these guidelines while porting.

- Unless explicitly recommended otherwise by this section, leave peripherals and their drivers disabled by default.
- Configure and enable a system clock, along with a tick source.
- Provide pin and driver configuration that matches the board's valuable components such as sensors, buttons or LEDs, and communication interfaces such as USB, Ethernet connector, or Bluetooth/Wi-Fi chip.
- If your board uses a well-known connector standard (like Arduino, Mikrobus, Grove, or 96Boards connectors), add connector nodes to your DTS and configure pin muxes accordingly.
- Configure components that enable the use of these pins, such as configuring an SPI instance to use the usual Arduino SPI pins.
- If available, configure and enable a serial output for the console using the zephyr,console chosen node in the devicetree.
- If your board supports networking, configure a default interface.
• Enable all GPIO ports connected to peripherals or expansion connectors.
• If available, enable pinmux and interrupt controller drivers.
• It is recommended to enable the MPU by default, if there is support for it in hardware. For boards with limited memory resources it is acceptable to disable it. When the MPU is enabled, it is recommended to also enable hardware stack protection (CONFIG_HW_STACK_PROTECTION=y) and, thus, allow the kernel to detect stack overflows when the system is running in privileged mode.

**Flash and debug support**

Zephyr supports *Building, Flashing and Debugging* via west extension commands.

To add `west flash` and `west debug` support for your board, you need to create a `board.cmake` file in your board directory. This file's job is to configure a “runner” for your board. (There's nothing special you need to do to get `west build` support for your board.)

“Runners” are Zephyr-specific Python classes that wrap flash and debug host tools and integrate with west and the zephyr build system to support `west flash` and related commands. Each runner supports flashing, debugging, or both. You need to configure the arguments to these Python scripts in your `board.cmake` to support those commands like this example `board.cmake`:

```makefile
board_runner_args(jlink "--device=nrf52" "--speed=4000")
board_runner_args(pyocd "--target=nrf52" "--frequency=4000000")

include(${ZEPHYR_BASE}/boards/common/nrfjprog.board.cmake)
include(${ZEPHYR_BASE}/boards/common/jlink.board.cmake)
include(${ZEPHYR_BASE}/boards/common/pyocd.board.cmake)
```

This example configures the nrfjprog, jlink, and pyocd runners.

**Warning:** Runners usually have names which match the tools they wrap, so the jlink runner wraps Segger’s J-Link tools, and so on. But the runner command line options like `--speed` etc. are specific to the Python scripts.

**Note:** Runners and board configuration should be created without being targeted to a single operating system if the tool supports multiple operating systems, nor should it rely upon special system setup/configuration. For example: do not assume that a user will have prior knowledge/configuration or (if using Linux) special udev rules installed, do not assume one specific `/dev/X` device for all platforms as this will not be compatible with Windows or macOS, and allow for overriding of the selected device so that multiple boards can be connected to a single system and flashed/debugged at the choice of the user.

For more details:

• Run `west flash --context` to see a list of available runners which support flashing, and `west flash --context -r <RUNNER>` to view the specific options available for an individual runner.
• Run `west debug --context` and `west debug --context <RUNNER>` to get the same output for runners which support debugging.
• Run `west flash --help` and `west debug --help` for top-level options for flashing and debugging.
• See *Flash and debug runners* for Python APIs.
• Look for `board.cmake` files for other boards similar to your own for more examples.
To see what a west flash or west debug command is doing exactly, run it in verbose mode:

```
west --verbose flash
west --verbose debug
```

Verbose mode prints any host tool commands the runner uses.

The order of the include() calls in your board.cmake matters. The first include sets the default runner if it's not already set. For example, including nrfjprog.board.cmake first means that nrfjprog is the default flash runner for this board. Since nrfjprog does not support debugging, jlink is the default debug runner.

**Multiple board revisions**

See Building for a board revision for basics on this feature from the user perspective.

To create a new board revision for the plank board, create these additional files in the board folder:

```
boards/<ARCH>/plank
|-- plank_<revision>.conf    # optional
| `-- plank_<revision>.overlay # optional
|-- revision.cmake
```

When the user builds for board plank@<revision>:

- The optional Kconfig settings specified in the file plank_<revision>.conf will be merged into the board's default Kconfig configuration.
- The optional devicetree overlay plank_<revision>.overlay will be added to the common plank.dts devicetree file
- The revision.cmake file controls how the Zephyr build system matches the <board>@<revision> string specified by the user when building an application for the board.

Currently, <revision> can be either a numeric MAJOR.MINOR.PATCH style revision like 1.5.0, an integer number like 1, or a single letter like A, B, etc. Zephyr provides a CMake board extension function, board_check_revision(), to make it easy to match either style from revision.cmake.

Valid board revisions may be specified as arguments to the board_check_revision() function, like:

```
board_check_revision(FORMAT MAJOR.MINOR.PATCH
                   VALID_REVISIONS 0.1.0 0.3.0 ...
)
```

**Note:** VALID_REVISIONS can be omitted if all valid revisions have specific Kconfig fragments, such as <board>_0_1_0.conf, <board>_0_3_0.conf. This allows you to just place Kconfig revision fragments in the board folder and not have to keep the corresponding VALID_REVISIONS in sync.

The following sections describe how to support these styles of revision numbers.

**MAJOR.MINOR.PATCH revisions** Let's say you want to add support for revisions 0.5.0, 1.0.0, and 1.5.0 of the plank board with both Kconfig fragments and devicetree overlays. Create revision.cmake with board_check_revision(FORMAT MAJOR.MINOR.PATCH), and create the following additional files in the board directory:
Notice how the board files have changed periods (".") in the revision number to underscores ("_").

**Fuzzy revision matching** To support "fuzzy" MAJOR.MINOR.PATCH revision matching for the plank board, use the following code in revision.cmake:

```c
board_check_revision(FORMAT MAJOR.MINOR.PATCH)
```

If the user selects a revision between those available, the closest revision number that is not larger than the user's choice is used. For example, if the user builds for `plank@0.7.0`, the build system will target revision `0.5.0`.

The build system will print this at CMake configuration time:

```text
-- Board: plank, Revision: 0.7.0 (Active: 0.5.0)
```

This allows you to only create revision configuration files for board revision numbers that introduce incompatible changes.

Any revision less than the minimum defined will be treated as an error.

You may use `0.0.0` as a minimum revision to build for by creating the file `plank_0_0_0.conf` in the board directory. This will be used for any revision lower than `0.5.0`, for example if the user builds for `plank@0.1.0`.

**Exact revision matching** Alternatively, the EXACT keyword can be given to `board_check_revision()` in revision.cmake to allow exact matches only, like this:

```c
board_check_revision(FORMAT MAJOR.MINOR.PATCH EXACT)
```

With this revision.cmake, building for `plank@0.7.0` in the above example will result in the following error message:

```text
Board revision '0.7.0' not found. Please specify a valid board revision.
```

**Letter revision matching** Let's say instead that you need to support revisions A, B, and C of the plank board. Create the following additional files in the board directory:

```bash
boards/<ARCH>/plank
├── plank_A.conf
├── plank_A.overlay
├── plank_B.conf
├── plank_B.overlay
├── plank_C.conf
├── plank_C.overlay
├── revision.cmake
```

And add the following to revision.cmake:

```c
boards/<ARCH>/plank
├── plank_A.conf
├── plank_A.overlay
├── plank_B.conf
├── plank_B.overlay
├── plank_C.conf
├── plank_C.overlay
├── revision.cmake
```
Number revision matching  Let's say instead that you need to support revisions 1, 2, and 3 of the plank board. Create the following additional files in the board directory:

```
boards/<ARCH>/plank
    ├── plank_1.conf
    ├── plank_1.overlay
    ├── plank_2.conf
    ├── plank_2.overlay
    ├── plank_3.conf
    ├── plank_3.overlay
    └── revision.cmake
```

And add the following to revision.cmake:

```
board_check_revision(FORMAT NUMBER)
```

**board_check_revision() details**

```
board_check_revision(FORMAT <LETTER | NUMBER | MAJOR.MINOR.PATCH>
[OPTIONAL EXACT]
[DEFAULT_REVISION <revision>]
[HIGHEST_REVISION <revision>]
[VALID_REVISIONS <revision> [<revision> ...]]
)
```

This function supports the following arguments:

- **FORMAT LETTER**: matches single letter revisions from A to Z only
- **FORMAT NUMBER**: matches integer revisions
- **FORMAT MAJOR.MINOR.PATCH**: matches exactly three digits. The command line allows for loose typing, that is -DBOARD=<board>@1 and -DBOARD=<board>@1.0 will be handled as -DBOARD=<board>@1.0.0. Kconfig fragment and devicetree overlay files must use full numbering to avoid ambiguity, so only <board>_1_0_0.conf and <board>_1_0_0.overlay are allowed.
- **OPTIONAL**: if given, a revision is not required to be specified. If the revision is not supplied, the base board is used with no overlays. Can be combined with EXACT, in which case providing the revision is optional, but if given the EXACT rules apply. Mutually exclusive with DEFAULT_REVISION.
- **EXACT**: if given, the revision is required to be an exact match. Otherwise, the closest matching revision not greater than the user's choice will be selected.
- **DEFAULT_REVISION <revision>**: if given, <revision> is the default revision to use when user has not selected a revision number. If not given, the build system prints an error when the user does not specify a board revision.
- **HIGHEST_REVISION <revision>**: if given, specifies the highest valid revision for a board. This can be used to ensure that a newer board cannot be used with an older Zephyr. For example, if the current board directory supports revisions 0.x.0-0.99.99 and 1.0.0-1.99.99, and it is expected that the implementation will not work with board revision 2.0.0, then giving HIGHEST_REVISION 1.99.99 causes an error if the user builds using <board>@2.0.0.
- **VALID_REVISIONS**: if given, specifies a list of revisions that are valid for this board. If this argument is not given, then each Kconfig fragment of the form <board>_<revision>.conf in the board folder will be used as a valid revision for the board.
Custom revision.cmake files

Some boards may not use board revisions supported by board_check_revision(). To support revisions of any type, the file revision.cmake can implement custom revision matching without calling board_check_revision().

To signal to the build system that it should use a different revision than the one specified by the user, revision.cmake can set the variable ACTIVE_BOARD_REVISION to the revision to use instead. The corresponding Kconfig files and devicetree overlays must be named <board>_<ACTIVE_BOARD_REVISION>.conf and <board>_<ACTIVE_BOARD_REVISION>.overlay.

For example, if the user builds for plank@zero, revision.cmake can set ACTIVE_BOARD_REVISION to one to use the files plank_one.conf and plank_one.overlay.

Contributing your board

If you want to contribute your board to Zephyr, first – thanks!

There are some extra things you'll need to do:

1. Make sure you’ve followed all the General recommendations. They are requirements for boards included with Zephyr.
2. Add documentation for your board using the template file doc/templates/board.tmpl. See Documentation Generation for information on how to build your documentation before submitting your pull request.
3. Prepare a pull request adding your board which follows the Contribution Guidelines.

Board extensions

Boards already supported by Zephyr can be extended by downstream users, such as example-application or vendor SDKs. In some situations, certain hardware description or choices can not be added in the upstream Zephyr repository, but they can be in a downstream project, where custom bindings or driver classes can also be created. This feature may also be useful in development phases, when the board skeleton lives upstream, but other features are developed in a downstream module.

Board extensions are board fragments that can be present in an out-of-tree board root folder, under ${BOARD_ROOT}/boards/extensions. Here is an example structure of an extension for the plank board and its revisions:

```
boards/extensions/plank
|-- plank.conf    # optional
|-- plank_<revision>.conf   # optional
|-- plank.overlay     # optional
|-- plank_<revision>.overlay # optional
```

A board extension directory must follow the naming structure of the original board it extends. It may contain Kconfig fragments and/or devicetree overlays. Extensions are, by default, automatically loaded and applied on top of board files, before anything else. There is no guarantee on which order extensions are applied, in case multiple exist. This feature can be disabled by passing -DBOARD_EXTENSIONS=OFF when building.

Note that board extensions need to follow the same guidelines as regular boards. For example, it is wrong to enable extra peripherals or subsystems in a board extension.

Warning: Board extensions are not allowed in any module referenced in Zephyr's west.yml manifest file. Any board changes are required to be submitted to the main Zephyr repository.
7.8.3 Shields

Shields, also known as “add-on” or “daughter boards”, attach to a board to extend its features and services for easier and modularized prototyping. In Zephyr, the shield feature provides Zephyr-formatted shield descriptions for easier compatibility with applications.

Shield porting and configuration

Shield configuration files are available in the board directory under `/boards/shields`:

```
boards/shields/<shield>
├── <shield>.overlay
├── Kconfig.shield
└── Kconfig.defconfig
```

These files provide shield configuration as follows:

- **<shield>.overlay**: This file provides a shield description in devicetree format that is merged with the board's `devicetree` before compilation.
- **Kconfig.shield**: This file defines shield Kconfig symbols that will be used for default shield configuration. To ease use with applications, the default shield configuration here should be consistent with those in the `Write your devicetree`.
- **Kconfig.defconfig**: This file defines the default shield configuration. It is made to be consistent with the `Write your devicetree`. Hence, shield configuration should be done by keeping in mind that features activation is application responsibility.

Besides, in order to avoid name conflicts with devices that may be defined at board level, it is advised, specifically for shields devicetree descriptions, to provide a device node label in the form `<device>_<shield>`, for instance:

```
sdhc_mysheild: sdhc@[1] {
    reg = <1>;
    ...
};
```

Board compatibility

Hardware shield-to-board compatibility depends on the use of well-known connectors used on popular boards (such as Arduino and 96boards). For software compatibility, boards must also provide a configuration matching their supported connectors.

This should be done at two different level:

- **Pinmux**: Connector pins should be correctly configured to match shield pins
- **Devicetree**: A board `devicetree` file, `BOARD.dts` should define an alternate node label for each connector interface. For example, for Arduino I2C:

```
arduino_i2c: &i2c1 {};
```

Board specific shield configuration

If modifications are needed to fit a shield to a particular board or board revision, you can override a shield description for a specific board by adding board or board revision overriding files to a shield, as follows:
Shield activation

Activate support for one or more shields by adding the matching -DSHIELD arg to CMake command:

```
# From the root of the zephyr repository
west build -b None your_app -- -DSHIELD="x_nucleo_idb05a1 x_nucleo_iks01a1"
```

Alternatively, it could be set by default in a project’s CMakeLists.txt:

```
set(SHIELD x_nucleo_iks01a1)
```

Shield variants

Some shields may support several variants or revisions. In that case, it is possible to provide multiple version of the shields description:

```
boards/shields/<shield>
├── <shield_v1>.overlay
├── <shield_v1>.defconfig
├── <shield_v2>.overlay
└── <shield_v2>.defconfig
```

In this case, a shield-particular revision name can be used:

```
# From the root of the zephyr repository
west build -b None your_app -- -DSHIELD=shield_v2
```

You can also provide a board-specific configuration to a specific shield revision:

```
boards/shields/<shield>
├── <shield_v1>.overlay
├── <shield_v1>.defconfig
├── <shield_v2>.overlay
├── <shield_v2>.defconfig
└── boards
    └── <shield_v2>
        ├── <board>.overlay
        └── <board>.defconfig
```

GPIO nexus nodes

GPIOs accessed by the shield peripherals must be identified using the shield GPIO abstraction, for example from the arduino-header-r3 compatible. Boards that provide the header must map the header pins to SOC-specific pins. This is accomplished by including a nexus node that looks like the following into the board devicetree file:
This specifies how Arduino pin references like <&arduino_header 11 0> are converted to SOC gpio pin references like <&gpiob 4 0>.

In Zephyr GPIO specifiers generally have two parameters (indicated by #gpio-cells = <2>): the pin number and a set of flags. The low 6 bits of the flags correspond to features that can be configured in devicetree. In some cases it’s necessary to use a non-zero flag value to tell the driver how a particular pin behaves, as with:

\[
\text{drdy-gpios} = <\&\text{arduino_header}~11~\text{GPIO_ACTIVE_LOW}>;
\]

After preprocessing this becomes <&arduino_header 11 1>. Normally the presence of such a flag would cause the map lookup to fail, because there is no map entry with a non-zero flags value. The gpio-map-mask property specifies that, for lookup, all bits of the pin and all but the low 6 bits of the flags are used to identify the specifier. Then the gpio-map-pass-thru specifies that the low 6 bits of the flags are copied over, so the SOC GPIO reference becomes <&gpiob 4 1> as intended.

See nexus node for more information about this capability.
Chapter 8

Contributing to Zephyr

Contributions from the community are the backbone of the project. Whether it is by submitting code, improving documentation, or proposing new features, your efforts are highly appreciated. This page lists useful resources and guidelines to help you in your contribution journey.

8.1 General Guidelines

8.1.1 Contribution Guidelines

As an open-source project, we welcome and encourage the community to submit patches directly to the project. In our collaborative open source environment, standards and methods for submitting changes help reduce the chaos that can result from an active development community.

This document explains how to participate in project conversations, log bugs and enhancement requests, and submit patches to the project so your patch will be accepted quickly in the codebase.

Licensing

Licensing is very important to open source projects. It helps ensure the software continues to be available under the terms that the author desired.

Zephyr uses the Apache 2.0 license (as found in the LICENSE file in the project's GitHub repo) to strike a balance between open contribution and allowing you to use the software however you would like to. The Apache 2.0 license is a permissive open source license that allows you to freely use, modify, distribute and sell your own products that include Apache 2.0 licensed software. (For more information about this, check out articles such as Why choose Apache 2.0 licensing and Top 10 Apache License Questions Answered).

A license tells you what rights you have as a developer, as provided by the copyright holder. It is important that the contributor fully understands the licensing rights and agrees to them. Sometimes the copyright holder isn't the contributor, such as when the contributor is doing work on behalf of a company.

Components using other Licenses  There are some imported or reused components of the Zephyr project that use other licensing, as described in Licensing of Zephyr Project components.

Importing code into the Zephyr OS from other projects that use a license other than the Apache 2.0 license needs to be fully understood in context and approved by the Zephyr governing board.
By carefully reviewing potential contributions and also enforcing a Developer Certification of Origin (DCO) for contributed code, we can ensure that the Zephyr community can develop products with the Zephyr Project without concerns over patent or copyright issues.

See Contributing External Components for more information about this contributing and review process for imported components.

**Licensing of Zephyr Project components**  The Zephyr kernel tree imports or reuses packages, scripts and other files that are not covered by the Apache 2.0 License. In some places there is no LICENSE file or way to put a LICENSE file there, so we describe the licensing in this document.

`scripts/{checkpatch.pl,checkstack.pl,spelling.txt}`

*Origin:* Linux Kernel

*Licensing:* GPLv2 License

**Copyrights Notices**

Please follow this Community Best Practice for Copyright Notices from the Linux Foundation.

**Developer Certification of Origin (DCO)**

To make a good faith effort to ensure licensing criteria are met, the Zephyr project requires the Developer Certificate of Origin (DCO) process to be followed.

The DCO is an attestation attached to every contribution made by every developer. In the commit message of the contribution, (described more fully later in this document), the developer simply adds a Signed-off-by statement and thereby agrees to the DCO.

When a developer submits a patch, it is a commitment that the contributor has the right to submit the patch per the license. The DCO agreement is shown below and at [http://developercertificate.org/](http://developercertificate.org/).

---

**Developer's Certificate of Origin 1.1**

By making a contribution to this project, I certify that:

(a) The contribution was created in whole or in part by me and I have the right to submit it under the open source license indicated in the file; or

(b) The contribution is based upon previous work that, to the best of my knowledge, is covered under an appropriate open source license and I have the right under that license to submit that work with modifications, whether created in whole or in part by me, under the same open source license (unless I am permitted to submit under a different license), as indicated in the file; or

(c) The contribution was provided directly to me by some other person who certified (a), (b) or (c) and I have not modified it.

(d) I understand and agree that this project and the contribution are public and that a record of the contribution (including all personal information I submit with it, including my sign-off) is maintained indefinitely and may be redistributed consistent with this project or the open source license(s) involved.
DCO Sign-Off  The “sign-off” in the DCO is a “Signed-off-by:” line in each commit's log message. The Signed-off-by: line must be in the following format:

```
Signed-off-by: Your Name <your.email@example.com>
```

For your commits, replace:

- Your Name with your legal name (pseudonyms, hacker handles, and the names of groups are not allowed)
- your.email@example.com with the same email address you are using to author the commit (CI will fail if there is no match)

You can automatically add the Signed-off-by: line to your commit body using `git commit -s`. Use other commits in the zephyr git history as examples.

Additional requirements:

- If you are altering an existing commit created by someone else, you must add your Signed-off-by: line without removing the existing one.
- If you forget to add the Signed-off-by: line, you can add it to your previous commit by running `git commit --amend -s`.
- If you've pushed your changes to GitHub already you'll need to force push your branch after this with `git push -f`.

Notes  Any contributions made as part of submitted pull requests are considered free for the Project to use. Developers are permitted to cherry-pick patches that are included in pull requests submitted by other contributors. It is expected that

- the content of the patches will not be substantially modified,
- the cherry-picked commits or portions of a commit shall preserve the original sign-off messages and the author identity.

*Modifying Contributions made by other developers* describes additional recommended policies around working with contributions submitted by other developers.

Prerequisites

As a contributor, you'll want to be familiar with the Zephyr project, how to configure, install, and use it as explained in the Zephyr Project website and how to set up your development environment as introduced in the Zephyr Getting Started Guide.

You should be familiar with common developer tools such as Git and CMake, and platforms such as GitHub.

If you haven't already done so, you'll need to create a (free) GitHub account on https://github.com and have Git tools available on your development system.

Note:  The Zephyr development workflow supports all 3 major operating systems (Linux, macOS, and Windows) but some of the tools used in the sections below are only available on Linux and macOS. On Windows, instead of running these tools yourself, you will need to rely on the Continuous Integration (CI) service using Github Actions, which runs automatically on GitHub when you submit your Pull Request (PR). You can see any failure results in the workflow details link near the end of the PR conversation list. See Continuous Integration for more information

8.1. General Guidelines
Source Tree Structure

To clone the main Zephyr Project repository use the instructions in Get Zephyr and install Python dependencies.

This section describes the main repository’s source tree. In addition to the Zephyr kernel itself, you'll also find the sources for technical documentation, sample code, supported board configurations, and a collection of subsystem tests. All of these are available for developers to contribute to and enhance.

Understanding the Zephyr source tree can help locate the code associated with a particular Zephyr feature.

At the top of the tree, several files are of importance:

CMakeLists.txt
The top-level file for the CMake build system, containing a lot of the logic required to build Zephyr.

Kconfig
The top-level Kconfig file, which refers to the file Kconfig.zephyr also found in the top-level directory.

See the Kconfig section of the manual for detailed Kconfig documentation.

west.yml
The West (Zephyr’s meta-tool) manifest, listing the external repositories managed by the west command-line tool.

The Zephyr source tree also contains the following top-level directories, each of which may have one or more additional levels of subdirectories not described here.

arch
Architecture-specific kernel and system-on-chip (SoC) code. Each supported architecture (for example, x86 and ARM) has its own subdirectory, which contains additional subdirectories for the following areas:

- architecture-specific kernel source files
- architecture-specific kernel include files for private APIs

soc
SoC related code and configuration files.

boards
Board related code and configuration files.

doc
Zephyr technical documentation source files and tools used to generate the https://docs.zephyrproject.org web content.

drivers
Device driver code.

dts
devicetree source files used to describe non-discoverable board-specific hardware details.

include
Include files for all public APIs, except those defined under lib.

kernel
Architecture-independent kernel code.

lib
Library code, including the minimal standard C library.

misc
Miscellaneous code that doesn’t belong to any of the other top-level directories.
samples
Sample applications that demonstrate the use of Zephyr features.

scripts
Various programs and other files used to build and test Zephyr applications.

cmake
Additional build scripts needed to build Zephyr.

subsys
Subsystems of Zephyr, including:
- USB device stack code
- Networking code, including the Bluetooth stack and networking stacks
- File system code
- Bluetooth host and controller

tests
Test code and benchmarks for Zephyr features.

share
Additional architecture independent data. It currently contains Zephyr's CMake package.

Pull Requests and Issues

Before starting on a patch, first check in our issues Zephyr Project Issues system to see what's been reported on the issue you'd like to address. Have a conversation on the Zephyr devel mailing list (or the Zephyr Discord Server) to see what others think of your issue (and proposed solution). You may find others that have encountered the issue you're finding, or that have similar ideas for changes or additions. Send a message to the Zephyr devel mailing list to introduce and discuss your idea with the development community.

It's always a good practice to search for existing or related issues before submitting your own. When you submit an issue (bug or feature request), the triage team will review and comment on the submission, typically within a few business days.

You can find all open pull requests on GitHub and open Zephyr Project Issues in Github issues.

Tools and Git Setup

Name and email  We need to know who you are, and how to contact you. To add this information to your Git installation, set the Git configuration variables user.name to your full name, and user.email to your email address.

For example, if your name is Zephyr Developer and your email address is z.developer@example.com:

```
git config --global user.name "Zephyr Developer"
git config --global user.email "z.developer@example.com"
```

gitlint  When you submit a pull request to the project, a series of checks are performed to verify your commit messages meet the requirements. The same step done during the CI process can be performed locally using the gitlint command.

Run gitlint locally in your tree and branch where your patches have been committed:
gitlint

Note, gitlint only checks HEAD (the most recent commit), so you should run it after each commit, or use the --commits option to specify a commit range covering all the development patches to be submitted.

twister

Note: twister support on windows is limited and execution of tests is not supported, only building.

To verify that your changes did not break any tests or samples, please run the twister script locally before submitting your pull request to GitHub.

Twister allows limiting the scope of the tests built and run by pointing it to the tests related to the code or the platform you have modified. For example, to limit tests to a single platform and an area in the kernel:

```
source zephyr-env.sh
west twister -p qemu_x86 -T tests/kernel/sched
```

Running tests on connected devices is also supported using the --device-testing options. Please consult with the Twister documentation for more details.

To run the same tests the CI system runs, follow these steps from within your local Zephyr source working directory:

```
source zephyr-env.sh
west twister --integration
```

The above will execute the basic twister script, which will run various tests using the QEMU emulator and other simulators supported in Zephyr. It will also do some build tests on various samples with advanced features that can't run in a simulator or QEMU.

We highly recommend you run these tests locally to avoid any CI failures. However, note that building and executing tests using twister requires significant computing resources. When running locally and to get results in a reasonable time, limit the scope to the areas and platforms you have modified. In case of major changes to the kernel, build or configuration infrastructures of Zephyr, it is advised to use twister for verifying majority the changes before handing over to the dedicated CI resources provided by the Zephyr project.

clang-format

The clang-format tool can be helpful to quickly reformat large amounts of new source code to our Coding Style standards together with the .clang-format configuration file provided in the repository. clang-format is well integrated into most editors, but you can also run it manually like this:

```
clang-format -i my_source_file.c
```

clang-format is part of LLVM, which can be downloaded from the project releases page <https://github.com/llvm/llvm-project/releases>. Note that if you are a Linux user, clang-format will likely be available as a package in your distribution repositories.

Coding Style

Use these coding guidelines to ensure that your development complies with the project’s style and naming conventions.

In general, follow the Linux kernel coding style, with the following exceptions:
• The line length is 100 columns or fewer. In the documentation, longer lines for URL references are an allowed exception.

• Add braces to every if, else, do, while, for and switch body, even for single-line code blocks. Use the --ignore BRACES flag to make checkpatch stop complaining.

• Use spaces instead of tabs to align comments after declarations, as needed.

• Use C89-style single line comments, /* */. The C99-style single line comment, //, is not allowed.

• Use /** */ for doxygen comments that need to appear in the documentation.

• Avoid using binary literals (constants starting with 0b).

When there are differences between the guidelines above and the formatting generated by code formatting tools, the guidelines above take precedence.

The Linux kernel GPL-licensed tool checkpatch is used to check coding style conformity.

Note: checkpatch does not currently run on Windows.

Checkpatch is available in the scripts directory. To invoke it when committing code, make the file $ZEPHYR_BASE/.git/hooks/pre-commit executable and edit it to contain:

```
#!/bin/sh
set -e exec
diff --cached | $(ZEPHYR_BASE)/scripts/checkpatch.pl -
```

Instead of running checkpatch at each commit, you may prefer to run it only before pushing on zephyr repo. To do this, make the file $ZEPHYR_BASE/.git/hooks/pre-push executable and edit it to contain:

```
#!/bin/sh
remote="$1"
url="$2"

z40=0000000000000000000000000000000000000000

echo "Run push hook"

while read local_ref local_sha remote_ref remote_sha
do
    args="remote $url $local_ref $local_sha $remote_ref $remote_sha"
done

exec $(ZEPHYR_BASE)/scripts/series-push-hook.sh $args

exit 0
```

If you want to override checkpatch verdict and push you branch despite reported issues, you can add option --no-verify to the git push command.

A more complete alternative to this is using check_compliance.py script from ci-tools repo.

Static Code Analysis

Coverity Scan is a free service for static code analysis of Open Source projects. It is based on Coverity's commercial product and is able to analyze C, C++ and Java code.

Coverity's static code analysis doesn't run the code. Instead of that it uses abstract interpretation to gain information about the code's control flow and data flow. It's able to follow all possible code paths that a program may take. For example the analyzer understands that malloc() returns
a memory that must be freed with free() later. It follows all branches and function calls to see if all possible combinations free the memory. The analyzer is able to detect all sorts of issues like resource leaks (memory, file descriptors), NULL dereferencing, use after free, unchecked return values, dead code, buffer overflows, integer overflows, uninitialized variables, and many more.

The results are available on the Coverity Scan website. In order to access the results you have to create an account yourself. From the Zephyr project page, you may select “Add me to project” to be added to the project. New members must be approved by an admin.

Static analysis of the Zephyr codebase is conducted on a bi-weekly basis. GitHub issues are automatically created for any issues detected by static analysis tools. These issues will have the same (or equivalent) priority initially defined by the tool.

To ensure accountability and efficient issue resolution, they are assigned to the respective maintainer who is responsible for the affected code.

A dedicated team comprising members with expertise in static analysis, code quality, and software security ensures the effectiveness of the static analysis process and verifies that identified issues are properly triaged and resolved in a timely manner.

**Workflow** If after analyzing the Coverity report it is concluded that it is a false positive please set the classification to either “False positive” or “Intentional”, the action to “Ignore”, owner to your own account and add a comment why the issue is considered false positive or intentional.

Update the related Github issue in the zephyr project with the details, and only close it after completing the steps above on scan service website. Any issues closed without a fix or without ignoring the entry in the scan service will be automatically reopened if the issue continues to be present in the code.

**Contribution Workflow**

One general practice we encourage, is to make small, controlled changes. This practice simplifies review, makes merging and rebasing easier, and keeps the change history clean and clear.

When contributing to the Zephyr Project, it is also important you provide as much information as you can about your change, update appropriate documentation, and test your changes thoroughly before submitting.

The general GitHub workflow used by Zephyr developers uses a combination of command line Git commands and browser interaction with GitHub. As it is with Git, there are multiple ways of getting a task done. We’ll describe a typical workflow here:

1. **Create a Fork of Zephyr** to your personal account on GitHub. (Click on the fork button in the top right corner of the Zephyr project repo page in GitHub.)

2. On your development computer, change into the zephyr folder that was created when you obtained the code:

   ```bash
   cd zephyrproject/zephyr
   ```

   Rename the default remote pointing to the *upstream repository* from origin to upstream:

   ```bash
   git remote rename origin upstream
   ```

   Let Git know about the fork you just created, naming it origin:

   ```bash
   git remote add origin https://github.com/<your github id>/zephyr
   ```

   and verify the remote repos:

   ```bash
   git remote -v
   ```
3. Create a topic branch (off of `main`) for your work (if you’re addressing an issue, we suggest including the issue number in the branch name):

```bash
  git checkout main
  git checkout -b fix_comment_typo
```

Some Zephyr subsystems do development work on a separate branch from `main` so you may need to indicate this in your checkout:

```bash
  git checkout -b fix_out_of_date_patch origin/net
```

4. Make changes, test locally, change, test, test again, ... (Check out the prior chapter on `twister` as well).

5. When things look good, start the pull request process by adding your changed files:

```bash
  git add [file(s) that changed, add -p if you want to be more specific]
```

You can see files that are not yet staged using:

```bash
  git status
```

6. Verify changes to be committed look as you expected:

```bash
  git diff --cached
```

7. Commit your changes to your local repo:

```bash
  git commit -s
```

The `-s` option automatically adds your `Signed-off-by:` to your commit message. Your commit will be rejected without this line that indicates your agreement with the `Developer Certification of Origin (DCO)`. See the `Commit Message Guidelines` section for specific guidelines for writing your commit messages.

8. Push your topic branch with your changes to your fork in your personal GitHub account:

```bash
  git push origin fix_comment_typo
```

9. In your web browser, go to your forked repo and click on the `Compare & pull request` button for the branch you just worked on and you want to open a pull request with.

10. Review the pull request changes, and verify that you are opening a pull request for the `main` branch. The title and message from your commit message should appear as well.

11. A bot will assign one or more suggested reviewers (based on the MAINTAINERS file in the repo). If you are a project member, you can select additional reviewers now too.

12. Click on the submit button and your pull request is sent and awaits review. Email will be sent as review comments are made, or you can check on your pull request at `https://github.com/zephyrproject-rtos/zephyr/pulls`.

**Note:** As more commits are merged upstream, the GitHub PR page will show a `This branch is out-of-date with the base branch message and a Update branch button on the PR page. That message should be ignored, as the commits will be rebased as part of merging
anyway, and triggering a branch update from the GitHub UI will cause the PR approvals to be dropped.

13. While you’re waiting for your pull request to be accepted and merged, you can create another branch to work on another issue. (Be sure to make your new branch off of main and not the previous branch.):

   ```
   git checkout main
   git checkout -b fix_another_issue
   ```

   and use the same process described above to work on this new topic branch.

14. If reviewers do request changes to your patch, you can interactively rebase commit(s) to fix review issues. In your development repo:

   ```
   git fetch --all
   git rebase --ignore-whitespace upstream/main
   ```

   The `--ignore-whitespace` option stops `git apply` (called by rebase) from changing any whitespace. Continuing:

   ```
   git rebase -i <offending-commit-id>^*
   ```

   In the interactive rebase editor, replace pick with edit to select a specific commit (if there’s more than one in your pull request), or remove the line to delete a commit entirely. Then edit files to fix the issues in the review.

   As before, inspect and test your changes. When ready, continue the patch submission:

   ```
   git add [file(s)]
   git rebase --continue
   ```

   Update commit comment if needed, and continue:

   ```
   git push --force origin fix_comment_typo
   ```

   By force pushing your update, your original pull request will be updated with your changes so you won’t need to resubmit the pull request.

   **Note:** While amending commits and force pushing is a common review model outside GitHub, and the one recommended by Zephyr, it’s not the main model supported by GitHub. Forced pushes can cause unexpected behavior, such as not being able to use “View Changes” buttons except for the last one - GitHub complains it can’t find older commits. You’re also not always able to compare the latest reviewed version with the latest submitted version. When rewriting history GitHub only guarantees access to the latest version.

15. If the CI run fails, you will need to make changes to your code in order to fix the issues and amend your commits by rebasing as described above. Additional information about the CI system can be found in *Continuous Integration*.

**Commit Message Guidelines**

Changes are submitted as Git commits. Each commit has a *commit message* describing the change. Acceptable commit messages look like this:

```
[area]: [summary of change]
[Commit message body (must be non-empty)]
```
Signed-off-by: [Your Full Name] <[your.email@address]>

You need to change text in square brackets ([like this]) above to fit your commit. Examples and more details follow.

**Example**  Here is an example of a good commit message.

```plaintext
drivers: sensor: abcd1234: fix bus I/O error handling
```

The abcd1234 sensor driver is failing to check the flags field in the response packet from the device which signals that an error occurred. This can lead to reading invalid data from the response buffer. Fix it by checking the flag and adding an error path.

Signed-off-by: Zephyr Developer <z.developer@example.com>

**[area]: [summary of change]**  This line is called the commit’s **title**. Titles must be:

- one line
- less than 72 characters long
- followed by a completely blank line

**[area]**  The [area] prefix usually identifies the area of code being changed. It can also identify the change’s wider context if multiple areas are affected.

Here are some examples:

- doc: ... for documentation changes
- drivers: foo: for foo driver changes
- Bluetooth: Shell: for changes to the Bluetooth shell
- net: ethernet: for Ethernet-related networking changes
- dts: for treewide devicetree changes
- style: for code style changes

If you’re not sure what to use, try running `git log FILE`, where `FILE` is a file you are changing, and using previous commits that changed the same file as inspiration.

**[summary of change]**  The [summary of change] part should be a quick description of what you’ve done. Here are some examples:

- doc: update wiki references to new site
- drivers: sensor: sensor_shell: fix channel name collision

**Warning:**  An empty commit message body is not permitted. Even for trivial changes, please include a descriptive commit message body. Your pull request will fail CI checks if you do not.

**Commit Message Body**  This part of the commit should explain what your change does, and why it’s needed. Be specific. A body that says “Fixes stuff” will be rejected. Be sure to include the following as relevant:

8.1. General Guidelines
• **what** the change does,
• **why** you chose that approach,
• **what** assumptions were made, and
• **how** you know it works – for example, which tests you ran.

Each line in your commit message should usually be 75 characters or less. Use newlines to wrap longer lines. Exceptions include lines with long URLs, email addresses, etc.

For examples of accepted commit messages, you can refer to the Zephyr GitHub changelog.

If the change addresses a GitHub issue, include a line of the form:

`Fixes #[issue number]`

Where `[issue number]` is the relevant GitHub issue's number. For example:

Fixes: #1234

**Signed-off-by:** ...

**Tip:** You should have set your *Name and email* already. Create your commit with `git commit -s` to add the Signed-off-by: line automatically using this information.

For open source licensing reasons, your commit must include a Signed-off-by: line that looks like this:

`Signed-off-by: [Your Full Name] <[your.email@address]>`

For example, if your full name is Zephyr Developer and your email address is z.developer@example.com:

`Signed-off-by: Zephyr Developer <z.developer@example.com>`

This means that you have personally made sure your change complies with the *Developer Certification of Origin (DCO).* For this reason, you must use your legal name. Pseudonyms or “hacker aliases” are not permitted.

Your name and the email address you use must match the name and email in the Git commit’s Author: field.

**Other Commit Expectations**  See the *Contributor Expectations* for a more complete discussion of contributor and reviewer expectations.

**Submitting Proposals**  You can request a new feature or submit a proposal by submitting an issue to our GitHub Repository. If you would like to implement a new feature, please submit an issue with a proposal (RFC) for your work first, to be sure that we can use it. Please consider what kind of change it is:

• For a Major Feature, first open an issue and outline your proposal so that it can be discussed. This will also allow us to better coordinate our efforts, prevent duplication of work, and help you to craft the change so that it is successfully accepted into the project. Providing the following information will increase the chances of your issue being dealt with quickly:
  – Overview of the Proposal
  – Motivation for or Use Case
  – Design Details
  – Alternatives
Test Strategy

- Small Features can be crafted and directly submitted as a Pull Request.

**Identifying Contribution Origin** When adding a new file to the tree, it is important to detail the source of origin on the file, provide attributions, and detail the intended usage. In cases where the file is an original to Zephyr, the commit message should include the following (“Original” is the assumption if no Origin tag is present):

| Origin: Original |

In cases where the file is imported from an external project, the commit message shall contain details regarding the original project, the location of the project, the SHA-id of the origin commit for the file and the intended purpose.

For example, a copy of a locally maintained import:

| Origin: Contiki OS |
| License: BSD 3-Clause |
| URL: http://www.contiki-os.org/ |
| commit: 853207a6fcb649b10e0b34504ba75a1ad63a |
| Purpose: Introduction of networking stack. |

For example, a copy of an externally maintained import in a module repository:

| Origin: Tiny Crypt |
| License: BSD 3-Clause |
| URL: https://github.com/01org/tinycrypt |
| commit: 88ded7f21529c39e5133688fb93a9d8c94e5c6e |
| Purpose: Introduction of TinyCrypt |

**Continuous Integration (CI)**

The Zephyr Project operates a Continuous Integration (CI) system that runs on every Pull Request (PR) in order to verify several aspects of the PR:

- Git commit formatting
- Coding Style
- Twister builds for multiple architectures and boards
- Documentation build to verify any doc changes

CI is run on Github Actions and it uses the same tools described in the Contribution Tools section. The CI results must be green indicating “All checks have passed” before the Pull Request can be merged. CI is run when the PR is created, and again every time the PR is modified with a commit.

The current status of the CI run can always be found at the bottom of the GitHub PR page, below the review status. Depending on the success or failure of the run you will see:

- “All checks have passed”
- “All checks have failed”

In case of failure you can click on the “Details” link presented below the failure message in order to navigate to Github Actions and inspect the results. Once you click on the link you will be taken to the Github actions summary results page where a table with all the different builds will be shown. To see what build or test failed click on the row that contains the failed (i.e. non-green) build.
Contributions to External Modules

Follow the guidelines in the Modules (External projects) section for contributing new modules and submitting changes to existing modules.

Treewide Changes

This section describes contributions that are treewide changes and some additional associated requirements that apply to them. These requirements exist to try to give such changes increased review and user visibility due to their large impact.

Definition and Decision Making

A treewide change is defined as any change to Zephyr APIs, coding practices, or other development requirements that either implies required changes throughout the zephyr source code repository or can reasonably be expected to do so for a wide class of external Zephyr-based source code.

This definition is informal by necessity. This is because the decision on whether any particular change is treewide can be subjective and may depend on additional context.

Project maintainers should use good judgement and prioritize the Zephyr developer experience when deciding when a proposed change is treewide. Protracted disagreements can be resolved by the Zephyr Project's Technical Steering Committee (TSC), but please avoid premature escalation to the TSC.

Requirements for Treewide Changes

- The zephyr repository must apply the ‘treewide’ GitHub label to any issues or pull requests that are treewide changes
- The person proposing a treewide change must create an RFC issue describing the change, its rationale and impact, etc. before any pull requests related to the change can be merged
- The project's Architecture Working Group (WG) must include the issue on the agenda and discuss whether the project will accept or reject the change before any pull requests related to the change can be merged (with escalation to the TSC if consensus is not reached at the WG)
- The Architecture WG must specify the procedure for merging any PRs associated with each individual treewide change, including any required approvals for pull requests affecting specific subsystems or extra review time requirements
- The person proposing a treewide change must email devel@lists.zephyrproject.org about the RFC if it is accepted by the Architecture WG before any pull requests related to the change can be merged

Examples

Some example past treewide changes are:

- the deprecation of version 1 of the Logging API in favor of version 2 (see commit 262cc55609)
- the removal of support for a legacy Devicetree bindings syntax (6bf761fc0a)

Note that adding a new version of a widely used API while maintaining support for the old one is not a treewide change. Deprecation and removal of such APIs, however, are treewide changes.
Specialized driver requirements

Drivers for standalone devices should use the Zephyr bus APIs (SPI, I2C...) whenever possible so that the device can be used with any SoC from any vendor implementing a compatible bus. If it is not technically possible to achieve full performance using the Zephyr APIs due to specialized accelerators in a particular SoC family, one could extend the support for an external device by providing a specialized path for that SoC family. However, the driver must still provide a regular path (via Zephyr APIs) for all other SoCs. Every exception must be approved by the Architecture WG in order to be validated and potentially to be learned/improved from.

8.1.2 Coding Guidelines

The project TSC and the Safety Committee of the project agreed to implement a staged and incremental approach for complying with a set of coding rules (AKA Coding Guidelines) to improve quality and consistency of the code base. Below are the agreed upon stages and the approximate timelines:

**Stage I**
- Coding guideline rules are available to be followed and referenced, but not enforced. Rules are not yet enforced in CI and pull-requests cannot be blocked by reviewers/approvers due to violations.

**Stage II**
- Begin enforcement on a limited scope of the code base. Initially, this would be the safety certification scope. For rules easily applied across codebase, we should not limit compliance to initial scope. This step requires tooling, CI setup and an enforcement strategy.

**Stage III**
- Revisit the coding guideline rules and based on experience from previous stages, refine/iterate on selected rules.

**Stage IV**
- Expand enforcement to the wider codebase. Exceptions may be granted on some areas of the codebase with a proper justification. Exception would require TSC approval.

**Note:** Coding guideline rules may be removed/changed at any time by filing a GH issue/RFC.

Main rules

The coding guideline rules are based on MISRA-C 2012 and are a subset of MISRA-C. The subset is listed in the table below with a summary of the rules, its severity and the equivalent rules from other standards for reference.

**Note:** For existing Zephyr maintainers and collaborators, if you are unable to obtain a copy through your employer, a limited number of copies will be made available through the project. If you need a copy of MISRA-C 2012, please send email to safety@lists.zephyrproject.org and provide details on reason why you can’t obtain one through other options and expected contributions once you have one. The safety committee will review all requests.
<table>
<thead>
<tr>
<th>MISRA C 2012</th>
<th>Severity</th>
<th>Description</th>
<th>CERT C</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>Dir 1.1</td>
<td>Required</td>
<td>Any implementation-defined behaviour on which the output of the program depends shall be documented and understood</td>
<td>MSC09-C</td>
<td>Dir 1.1</td>
</tr>
<tr>
<td>Dir 2.1</td>
<td>Required</td>
<td>All source files shall compile without any compilation errors</td>
<td>N/A</td>
<td>Dir 2.1</td>
</tr>
<tr>
<td>Dir 3.1</td>
<td>Required</td>
<td>All code shall be traceable to documented requirements</td>
<td>N/A</td>
<td>Dir 3.1</td>
</tr>
<tr>
<td>Dir 4.1</td>
<td>Required</td>
<td>Run-time failures shall be minimized</td>
<td>N/A</td>
<td>Dir 4.1</td>
</tr>
<tr>
<td>Dir 4.2</td>
<td>Advisory</td>
<td>All usage of assembly language should be documented</td>
<td>N/A</td>
<td>Dir 4.2</td>
</tr>
<tr>
<td>Dir 4.4</td>
<td>Advisory</td>
<td>Sections of code should not be “commented out”</td>
<td>MSC04-C</td>
<td>Dir 4.4</td>
</tr>
<tr>
<td>Dir 4.5</td>
<td>Advisory</td>
<td>Identifiers in the same name space with overlapping visibility should be typographically unambiguous typedefs that indicate size and signedness should be used in place of the basic numerical types</td>
<td>DCL02-C</td>
<td>Dir 4.5</td>
</tr>
<tr>
<td>Dir 4.6</td>
<td>Advisory</td>
<td>If a function returns error information, then that error information shall be tested</td>
<td>N/A</td>
<td>Dir 4.6</td>
</tr>
<tr>
<td>Dir 4.7</td>
<td>Required</td>
<td>If a pointer to a structure or union is never dereferenced within a translation unit, then the implementation of the object should be hidden</td>
<td>DCL12-C</td>
<td>Dir 4.7</td>
</tr>
<tr>
<td>Dir 4.8</td>
<td>Advisory</td>
<td>A function should be used in preference to a function-like macro where they are interchangeable</td>
<td>PRE00-C</td>
<td>Dir 4.9</td>
</tr>
<tr>
<td>Dir 4.9</td>
<td>Advisory</td>
<td>Precautions shall be taken in order to prevent the contents of a header file being included more than once</td>
<td>PRE06-C</td>
<td>Dir 4.10</td>
</tr>
<tr>
<td>Dir 4.10</td>
<td>Required</td>
<td>The validity of values passed to library functions shall be checked</td>
<td>N/A</td>
<td>Dir 4.11</td>
</tr>
<tr>
<td>Dir 4.11</td>
<td>Required</td>
<td>Dynamic memory allocation shall not be used</td>
<td>STR01-C</td>
<td>Dir 4.12</td>
</tr>
<tr>
<td>Dir 4.12</td>
<td>Advisory</td>
<td>Functions which are designed to provide operations on a resource should be called in an appropriate sequence</td>
<td>N/A</td>
<td>Dir 4.13</td>
</tr>
<tr>
<td>Dir 4.13</td>
<td>Required</td>
<td>The validity of values received from external sources shall be checked</td>
<td>N/A</td>
<td>Dir 4.14</td>
</tr>
<tr>
<td>Rule 1.2</td>
<td>Advisory</td>
<td>Language extensions should not be used</td>
<td>MSC04-C</td>
<td>Rule 1.2</td>
</tr>
<tr>
<td>Rule 1.3</td>
<td>Required</td>
<td>There shall be no occurrence of undefined or critical unspecified behaviour</td>
<td>N/A</td>
<td>Rule 1.3</td>
</tr>
</tbody>
</table>

continues on next page
<table>
<thead>
<tr>
<th>MISRA C 2012</th>
<th>Severity</th>
<th>Description</th>
<th>CERT C</th>
<th>Example</th>
</tr>
</thead>
</table>
| Rule 2.1    | Required | A project shall not contain unreachable code | MSC07-C | Rule 2.1 example 1  
|             |          |             |        | Rule 2.1 example 2 |
| Rule 2.2    | Required | There shall be no dead code | MSC12-C | Rule 2.2 |
| Rule 2.3    | Advisory | A project should not contain unused type declarations | N/A | Rule 2.3 |
| Rule 2.6    | Advisory | A function should not contain unused label declarations | N/A | Rule 2.6 |
| Rule 2.7    | Advisory | There should be no unused parameters in functions | N/A | Rule 2.7 |
| Rule 3.1    | Required | The character sequences /* and // shall not be used within a comment | MSC04-C | Rule 3.1 |
| Rule 3.2    | Required | Line-splicing shall not be used in // comments | N/A | Rule 3.2 |
| Rule 4.1    | Required | Octal and hexadecimal escape sequences shall be terminated | MSC09-C | Rule 4.1 |
| Rule 4.2    | Advisory | Trigraphs should not be used | PRE07-C | Rule 4.2 |
| Rule 5.1    | Required | External identifiers shall be distinct | DCL23-C | Rule 5.1 example 1  
|             |          |             |        | Rule 5.1 example 2 |
| Rule 5.2    | Required | Identifiers declared in the same scope and name space shall be distinct | DCL23-C | Rule 5.2 |
| Rule 5.3    | Required | An identifier declared in an inner scope shall not hide an identifier declared in an outer scope | DCL23-C | Rule 5.3 |
| Rule 5.4    | Required | Macro identifiers shall be distinct | DCL23-C | Rule 5.4 |
| Rule 5.5    | Required | Identifiers shall be distinct from macro names | DCL23-C | Rule 5.5 |
| Rule 5.6    | Required | A typedef name shall be a unique identifier | N/A | Rule 5.6 |
| Rule 5.7    | Required | A tag name shall be a unique identifier | N/A | Rule 5.7 |
| Rule 5.8    | Required | Identifiers that define objects or functions with external linkage shall be unique | N/A | Rule 5.8 example 1  
|             |          |             |        | Rule 5.8 example 2 |

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| Rule 5.9     | Advisory | Identifiers that define objects or functions with internal linkage should be unique | N/A    | Rule 5.9 example 1  
|              |          |             |        | Rule 5.9 example 2 |
| Rule 6.1     | Required | Bit-fields shall only be declared with an appropriate type | INT14-C | Rule 6.1 |
| Rule 6.2     | Required | Single-bit named bit fields shall not be of a signed type | INT14-C | Rule 6.2 |
| Rule 7.1     | Required | Octal constants shall not be used | DCL18-C | Rule 7.1 |
| Rule 7.2     | Required | A u or U suffix shall be applied to all integer constants that are represented in an unsigned type | N/A    | Rule 7.2 |
| Rule 7.3     | Required | The lowercase character l shall not be used in a literal suffix | DCL16-C | Rule 7.3 |
| Rule 7.4     | Required | A string literal shall not be assigned to an object unless the objects type is pointer to const-qualified char | N/A    | Rule 7.4 |
| Rule 8.1     | Required | Types shall be explicitly specified | N/A    | Rule 8.1 |
| Rule 8.2     | Required | Function types shall be in prototype form with named parameters | DCL20-C | Rule 8.2 |
| Rule 8.3     | Required | All declarations of an object or function shall use the same names and type qualifiers | N/A    | Rule 8.3 |
| Rule 8.4     | Required | A compatible declaration shall be visible when an object or function with external linkage is defined | N/A    | Rule 8.4 |
| Rule 8.5     | Required | An external object or function shall be declared once in one and only one file | N/A    | Rule 8.5 example 1  
|              |          |             |        | Rule 8.5 example 2 |
| Rule 8.6     | Required | An identifier with external linkage shall have exactly one external definition | N/A    | Rule 8.6 example 1  
|              |          |             |        | Rule 8.6 example 2 |
| Rule 8.8     | Required | The static storage class specifier shall be used in all declarations of objects and functions that have internal linkage | DCL15-C | Rule 8.8 |

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<tr>
<td>Rule 8.9</td>
<td>Advisory</td>
<td>An object should be defined at block scope if its identifier only appears in a single function</td>
<td>DCL19-C</td>
<td>Rule 8.9</td>
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<td>Rule 8.10</td>
<td>Required</td>
<td>An inline function shall be declared with the static storage class</td>
<td>N/A</td>
<td>Rule 8.10</td>
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<tr>
<td>Rule 8.12</td>
<td>Required</td>
<td>Within an enumerator list, the value of an implicitly-specified enumeration constant shall be unique</td>
<td>INT09-C</td>
<td>Rule 8.12</td>
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<td>Rule 8.14</td>
<td>Required</td>
<td>The restrict type qualifier shall not be used</td>
<td>N/A</td>
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<tr>
<td>Rule 9.1</td>
<td>Mandatory</td>
<td>The value of an object with automatic storage duration shall not be read before it has been set</td>
<td>N/A</td>
<td>Rule 9.1</td>
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<tr>
<td>Rule 9.2</td>
<td>Required</td>
<td>The initializer for an aggregate or union shall be enclosed in braces</td>
<td>N/A</td>
<td>Rule 9.2</td>
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<tr>
<td>Rule 9.3</td>
<td>Required</td>
<td>Arrays shall not be partially initialized</td>
<td>N/A</td>
<td>Rule 9.3</td>
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<td>Rule 9.4</td>
<td>Required</td>
<td>An element of an object shall not be initialized more than once</td>
<td>N/A</td>
<td>Rule 9.4</td>
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<tr>
<td>Rule 9.5</td>
<td>Required</td>
<td>Where designated initializers are used to initialize an array object the size of the array shall be specified explicitly</td>
<td>N/A</td>
<td>Rule 9.5</td>
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<tr>
<td>Rule 10.1</td>
<td>Required</td>
<td>Operands shall not be of an inappropriate essential type</td>
<td>STR04-C</td>
<td>Rule 10.1</td>
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<tr>
<td>Rule 10.2</td>
<td>Required</td>
<td>Expressions of essentially character type shall not be used inappropriately in addition and subtraction operations</td>
<td>STR04-C</td>
<td>Rule 10.2</td>
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<tr>
<td>Rule 10.3</td>
<td>Required</td>
<td>The value of an expression shall not be assigned to an object with a narrower essential type or of a different essential type category</td>
<td>STR04-C</td>
<td>Rule 10.3</td>
</tr>
<tr>
<td>Rule 10.4</td>
<td>Required</td>
<td>Both operands of an operator in which the usual arithmetic conversions are performed shall have the same essential type category</td>
<td>STR04-C</td>
<td>Rule 10.4</td>
</tr>
<tr>
<td>Rule 10.5</td>
<td>Advisory</td>
<td>The value of an expression should not be cast to an inappropriate essential type</td>
<td>N/A</td>
<td>Rule 10.5</td>
</tr>
<tr>
<td>Rule 10.6</td>
<td>Required</td>
<td>The value of a composite expression shall not be assigned to an object with wider essential type</td>
<td>INT02-C</td>
<td>Rule 10.6</td>
</tr>
<tr>
<td>Rule 10.7</td>
<td>Required</td>
<td>If a composite expression is used as one operand of an operator in which the usual arithmetic conversions are performed then the other operand shall not have wider essential type</td>
<td>INT02-C</td>
<td>Rule 10.7</td>
</tr>
<tr>
<td>Rule 10.8</td>
<td>Required</td>
<td>The value of a composite expression shall not be cast to a different essential type category or a wider essential type</td>
<td>INT02-C</td>
<td>Rule 10.8</td>
</tr>
<tr>
<td>Rule 11.2</td>
<td>Required</td>
<td>Conversions shall not be performed between a pointer to an incomplete type and any other type</td>
<td>N/A</td>
<td>Rule 11.2</td>
</tr>
<tr>
<td>Rule 11.6</td>
<td>Required</td>
<td>A cast shall not be performed between pointer to void and an arithmetic type</td>
<td>N/A</td>
<td>Rule 11.6</td>
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<tr>
<td>Rule 11.7</td>
<td>Required</td>
<td>A cast shall not be performed between pointer to object and a noninteger arithmetic type</td>
<td>N/A</td>
<td>Rule 11.7</td>
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<tr>
<td>Rule 11.8</td>
<td>Required</td>
<td>A cast shall not remove any const or volatile qualification from the type pointed to by a pointer</td>
<td>EXP05-C</td>
<td>Rule 11.8</td>
</tr>
<tr>
<td>Rule 11.9</td>
<td>Required</td>
<td>The macro NULL shall be the only permitted form of integer null pointer constant</td>
<td>N/A</td>
<td>Rule 11.9</td>
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<tr>
<td>Rule 12.1</td>
<td>Advisory</td>
<td>The precedence of operators within expressions should be made explicit</td>
<td>EXP00-C</td>
<td>Rule 12.1</td>
</tr>
<tr>
<td>Rule 12.2</td>
<td>Required</td>
<td>The right hand operand of a shift operator shall lie in the range zero to one less than the width in bits of the essential type of the left hand operand</td>
<td>N/A</td>
<td>Rule 12.2</td>
</tr>
<tr>
<td>Rule 12.4</td>
<td>Advisory</td>
<td>Evaluation of constant expressions should not lead to unsigned integer wrap-around</td>
<td>N/A</td>
<td>Rule 12.4</td>
</tr>
<tr>
<td>Rule 12.5</td>
<td>Mandatory</td>
<td>The sizeof operator shall not have an operand which is a function parameter declared as “array of type”</td>
<td>N/A</td>
<td>Rule 12.5</td>
</tr>
<tr>
<td>Rule 13.1</td>
<td>Required</td>
<td>Initializer lists shall not contain persistent side effects</td>
<td>N/A</td>
<td>Rule 13.1 example 1  Rule 13.1 example 2</td>
</tr>
<tr>
<td>Rule 13.2</td>
<td>Required</td>
<td>The value of an expression and its persistent side effects shall be the same under all permitted evaluation orders</td>
<td>N/A</td>
<td>Rule 13.2</td>
</tr>
<tr>
<td>Rule 13.3</td>
<td>Advisory</td>
<td>A full expression containing an increment (++) or decrement (--) operator should have no other potential side effects other than that caused by the increment or decrement operator</td>
<td>N/A</td>
<td>Rule 13.3</td>
</tr>
<tr>
<td>Rule 13.4</td>
<td>Advisory</td>
<td>The result of an assignment operator should not be used</td>
<td>N/A</td>
<td>Rule 13.4</td>
</tr>
<tr>
<td>Rule 13.5</td>
<td>Required</td>
<td>The right hand operand of a logical &amp;&amp; or</td>
<td></td>
<td>operator shall not contain persistent side effects</td>
</tr>
<tr>
<td>Rule 13.6</td>
<td>Mandatory</td>
<td>The operand of the sizeof operator shall not contain any expression which has potential side effects</td>
<td>N/A</td>
<td>Rule 13.6</td>
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<tr>
<td>Rule 14.1</td>
<td>Required</td>
<td>A loop counter shall not have essentially floating type</td>
<td>N/A</td>
<td>Rule 14.1</td>
</tr>
<tr>
<td>Rule 14.2</td>
<td>Required</td>
<td>A for loop shall be well-formed</td>
<td>N/A</td>
<td>Rule 14.2</td>
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<tr>
<td>Rule 14.3</td>
<td>Required</td>
<td>Controlling expressions shall not be invariant</td>
<td>N/A</td>
<td>Rule 14.3</td>
</tr>
<tr>
<td>Rule 14.4</td>
<td>Required</td>
<td>The controlling expression of an if statement and the controlling expression of an iteration-statement shall have essentially Boolean type</td>
<td>N/A</td>
<td>Rule 14.4</td>
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<tr>
<td>Rule 15.2</td>
<td>Required</td>
<td>The goto statement shall jump to a label declared later in the same function</td>
<td>N/A</td>
<td>Rule 15.2</td>
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<tr>
<td>Rule 15.3</td>
<td>Required</td>
<td>Any label referenced by a goto statement shall be declared in the same block, or in any block enclosing the goto statement</td>
<td>N/A</td>
<td>Rule 15.3</td>
</tr>
<tr>
<td>Rule 15.6</td>
<td>Required</td>
<td>The body of an iteration-statement or a selection-statement shall be a compound-statement</td>
<td>EXP19-C</td>
<td>Rule 15.6</td>
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<tr>
<td>Rule 15.7</td>
<td>Required</td>
<td>All if else if constructs shall be terminated with an else statement</td>
<td>N/A</td>
<td>Rule 15.7</td>
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<tr>
<td>Rule 16.1</td>
<td>Required</td>
<td>All switch statements shall be well-formed</td>
<td>N/A</td>
<td>Rule 16.1</td>
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<tr>
<td>Rule 16.2</td>
<td>Required</td>
<td>A switch label shall only be used when the most closely-enclosing compound statement is the body of a switch statement</td>
<td>MSC20-C</td>
<td>Rule 16.2</td>
</tr>
<tr>
<td>Rule 16.3</td>
<td>Required</td>
<td>An unconditional break statement shall terminate every switch-clause</td>
<td>N/A</td>
<td>Rule 16.3</td>
</tr>
<tr>
<td>Rule 16.4</td>
<td>Required</td>
<td>Every switch statement shall have a default label</td>
<td>N/A</td>
<td>Rule 16.4</td>
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<tr>
<td>Rule 16.5</td>
<td>Required</td>
<td>A default label shall appear as either the first or the last switch label of a switch statement</td>
<td>N/A</td>
<td>Rule 16.5</td>
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<tr>
<td>Rule 16.6</td>
<td>Required</td>
<td>Every switch statement shall have at least two switch-clauses</td>
<td>N/A</td>
<td>Rule 16.6</td>
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<tr>
<td>Rule 16.7</td>
<td>Required</td>
<td>A switch-expression shall not have essentially Boolean type</td>
<td>N/A</td>
<td>Rule 16.7</td>
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<tr>
<td>Rule 17.1</td>
<td>Required</td>
<td>The features of <code>&lt;stdarg.h&gt;</code> shall not be used</td>
<td>ERR00-C</td>
<td>Rule 17.1</td>
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<td>Rule 17.2</td>
<td>Required</td>
<td>Functions shall not call themselves, either directly or indirectly</td>
<td>MEM05-C</td>
<td>Rule 17.2</td>
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<tr>
<td>Rule 17.3</td>
<td>Mandatory</td>
<td>A function shall not be declared implicitly</td>
<td>N/A</td>
<td>Rule 17.3</td>
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<tr>
<td>Rule 17.4</td>
<td>Mandatory</td>
<td>All exit paths from a function with non-void return type shall have an explicit return statement with an expression</td>
<td>N/A</td>
<td>Rule 17.4</td>
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<tr>
<td>Rule 17.5</td>
<td>Advisory</td>
<td>The function argument corresponding to a parameter declared to have an array type shall have an appropriate number of elements</td>
<td>N/A</td>
<td>Rule 17.5</td>
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<tr>
<td>Rule 17.6</td>
<td>Mandatory</td>
<td>The declaration of an array parameter shall not contain the static keyword between the [ ]</td>
<td>N/A</td>
<td>Rule 17.6</td>
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<tr>
<td>Rule 17.7</td>
<td>Required</td>
<td>The value returned by a function having non-void return type shall be used</td>
<td>N/A</td>
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<td>Rule 18.1</td>
<td>Required</td>
<td>A pointer resulting from arithmetic on a pointer operand shall address an element of the same array as that pointer operand</td>
<td>EXP08-C</td>
<td>Rule 18.1</td>
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<tr>
<td>Rule 18.2</td>
<td>Required</td>
<td>Subtraction between pointers shall only be applied to pointers that address elements of the same array</td>
<td>EXP08-C</td>
<td>Rule 18.2</td>
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<tr>
<td>Rule 18.3</td>
<td>Required</td>
<td>The relational operators &gt;, &gt;=, &lt; and &lt;= shall not be applied to objects of pointer type except where they point into the same object</td>
<td>EXP08-C</td>
<td>Rule 18.3</td>
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<tr>
<td>Rule 18.5</td>
<td>Advisory</td>
<td>Declarations should contain no more than two levels of pointer nesting</td>
<td>N/A</td>
<td>Rule 18.5</td>
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<td>Rule 18.6</td>
<td>Required</td>
<td>The address of an object with automatic storage shall not be copied to another object that persists after the first object has ceased to exist</td>
<td>N/A</td>
<td>Rule 18.6 example 1</td>
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<td>Rule 18.8</td>
<td>Required</td>
<td>Variable-length array types shall not be used</td>
<td>N/A</td>
<td>Rule 18.8</td>
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<td>Rule 19.1</td>
<td>Mandatory</td>
<td>An object shall not be assigned or copied to an overlapping object</td>
<td>N/A</td>
<td>Rule 19.1</td>
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<td>Rule 20.2</td>
<td>Required</td>
<td>The ‘‘, or characters and the ‘/’ or ‘//’ character sequences shall not occur in a header file name”</td>
<td>N/A</td>
<td>Rule 20.2</td>
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<td>Rule 20.3</td>
<td>Required</td>
<td>The #include directive shall be followed by either a &lt;filename&gt; or “filename” sequence</td>
<td>N/A</td>
<td>Rule 20.3</td>
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<tr>
<td>Rule 20.4</td>
<td>Required</td>
<td>A macro shall not be defined with the same name as a keyword</td>
<td>N/A</td>
<td>Rule 20.4</td>
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<tr>
<td>Rule 20.7</td>
<td>Required</td>
<td>Expressions resulting from the expansion of macro parameters shall be enclosed in parentheses</td>
<td>PRE01-C</td>
<td>Rule 20.7</td>
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<tr>
<td>Rule 20.8</td>
<td>Required</td>
<td>The controlling expression of a #if or #elif preprocessing directive shall evaluate to 0 or 1</td>
<td>N/A</td>
<td>Rule 20.8</td>
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<tr>
<td>Rule 20.9</td>
<td>Required</td>
<td>All identifiers used in the controlling expression of #if or #elif preprocessing directives shall be #defined before evaluation</td>
<td>N/A</td>
<td>Rule 20.9</td>
</tr>
<tr>
<td>Rule 20.11</td>
<td>Required</td>
<td>A macro parameter immediately following a # operator shall not immediately be followed by a ## operator</td>
<td>N/A</td>
<td>Rule 20.11</td>
</tr>
<tr>
<td>Rule 20.12</td>
<td>Required</td>
<td>A macro parameter used as an operand to the # or ## operators, which is itself subject to further macro replacement, shall only be used as an operand to these operators</td>
<td>N/A</td>
<td>Rule 20.12</td>
</tr>
<tr>
<td>Rule 20.13</td>
<td>Required</td>
<td>A line whose first token is # shall be a valid preprocessing directive</td>
<td>N/A</td>
<td>Rule 20.13</td>
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<td>Rule 20.14</td>
<td>Required</td>
<td>All #else, #elif and #endif preprocessor directives shall reside in the same file as the #if, #ifdef or #ifndef directive to which they are related</td>
<td>N/A</td>
<td>Rule 20.14</td>
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<td>Rule 21.1</td>
<td>Required</td>
<td>#define and #undef shall not be used on a reserved identifier or reserved macro name</td>
<td>N/A</td>
<td>Rule 21.1</td>
</tr>
<tr>
<td>Rule 21.2</td>
<td>Required</td>
<td>A reserved identifier or macro name shall not be declared</td>
<td>N/A</td>
<td>Rule 21.2</td>
</tr>
<tr>
<td>Rule 21.3</td>
<td>Required</td>
<td>The memory allocation and deallocation functions of &lt;stdlib.h&gt; shall not be used</td>
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<td>Rule 21.3</td>
</tr>
<tr>
<td>Rule 21.4</td>
<td>Required</td>
<td>The standard header file &lt;setjmp.h&gt; shall not be used</td>
<td>N/A</td>
<td>Rule 21.4</td>
</tr>
<tr>
<td>Rule 21.6</td>
<td>Required</td>
<td>The Standard Library input/output functions shall not be used</td>
<td>N/A</td>
<td>Rule 21.6</td>
</tr>
<tr>
<td>Rule 21.7</td>
<td>Required</td>
<td>The atof, atoi, atol and atoll functions of &lt;stdlib.h&gt; shall not be used</td>
<td>N/A</td>
<td>Rule 21.7</td>
</tr>
<tr>
<td>Rule 21.9</td>
<td>Required</td>
<td>The library functions bsearch and qsort of &lt;stdlib.h&gt; shall not be used</td>
<td>N/A</td>
<td>Rule 21.9</td>
</tr>
<tr>
<td>Rule 21.11</td>
<td>Required</td>
<td>The standard header file &lt;tgmath.h&gt; shall not be used</td>
<td></td>
<td>Rule 21.11</td>
</tr>
<tr>
<td>Rule 21.12</td>
<td>Advisory</td>
<td>The exception handling features of &lt;fenv.h&gt; should not be used</td>
<td>N/A</td>
<td>Rule 21.12</td>
</tr>
<tr>
<td>Rule 21.13</td>
<td>Mandatory</td>
<td>Any value passed to a function in &lt;ctype.h&gt; shall be representable as an unsigned char or be the value EOF</td>
<td>N/A</td>
<td>Rule 21.13</td>
</tr>
<tr>
<td>Rule 21.14</td>
<td>Required</td>
<td>The Standard Library function memcmp shall not be used to compare null terminated strings</td>
<td>N/A</td>
<td>Rule 21.14</td>
</tr>
<tr>
<td>Rule 21.15</td>
<td>Required</td>
<td>The pointer arguments to the Standard Library functions memcpy, memmove and memcmp shall be pointers to qualified or unqualified versions of compatible types</td>
<td>N/A</td>
<td>Rule 21.15</td>
</tr>
<tr>
<td>Rule 21.16</td>
<td>Required</td>
<td>The pointer arguments to the Standard Library function memcmp shall point to either a pointer type, an essentially signed type, an essentially unsigned type, an essentially Boolean type or an essentially enum type</td>
<td>N/A</td>
<td>Rule 21.16</td>
</tr>
<tr>
<td>Rule 21.17</td>
<td>Mandatory</td>
<td>Use of the string handling functions from &lt;string.h&gt; shall not result in accesses beyond the bounds of the objects referenced by their pointer parameters</td>
<td>N/A</td>
<td>Rule 21.17</td>
</tr>
<tr>
<td>Rule 21.18</td>
<td>Mandatory</td>
<td>The size_t argument passed to any function in &lt;string.h&gt; shall have an appropriate value</td>
<td>N/A</td>
<td>Rule 21.18</td>
</tr>
<tr>
<td>Rule 21.19</td>
<td>Mandatory</td>
<td>The pointers returned by the Standard Library functions localeconv, getenv, setlocale or strerror shall only be used as if they have pointer to const-qualified type</td>
<td>N/A</td>
<td>Rule 21.19</td>
</tr>
</tbody>
</table>
Table 1 – continued from previous page

<table>
<thead>
<tr>
<th>MISRA C 2012</th>
<th>Severity</th>
<th>Description</th>
<th>CERT C</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rule 21.20</td>
<td>Mandatory</td>
<td>The pointer returned by the Standard Library functions asctime, ctime, gmtime, localtime, localeconv, getenv, setlocale or strerror shall not be used following a subsequent call to the same function</td>
<td>N/A</td>
<td>Rule 21.20</td>
</tr>
<tr>
<td>Rule 22.1</td>
<td>Required</td>
<td>All resources obtained dynamically by means of Standard Library functions shall be explicitly released</td>
<td>N/A</td>
<td>Rule 22.1</td>
</tr>
<tr>
<td>Rule 22.2</td>
<td>Mandatory</td>
<td>A block of memory shall only be freed if it was allocated by means of a Standard Library function</td>
<td>N/A</td>
<td>Rule 22.2</td>
</tr>
<tr>
<td>Rule 22.3</td>
<td>Required</td>
<td>The same file shall not be open for read and write access at the same time on different streams</td>
<td>N/A</td>
<td>Rule 22.3</td>
</tr>
<tr>
<td>Rule 22.4</td>
<td>Mandatory</td>
<td>There shall be no attempt to write to a stream which has been opened as read-only</td>
<td>N/A</td>
<td>Rule 22.4</td>
</tr>
<tr>
<td>Rule 22.5</td>
<td>Mandatory</td>
<td>A pointer to a FILE object shall not be dereferenced</td>
<td>N/A</td>
<td>Rule 22.5</td>
</tr>
<tr>
<td>Rule 22.6</td>
<td>Mandatory</td>
<td>The value of a pointer to a FILE shall not be used after the associated stream has been closed</td>
<td>N/A</td>
<td>Rule 22.6</td>
</tr>
<tr>
<td>Rule 22.7</td>
<td>Required</td>
<td>The macro EOF shall only be compared with the unmodified return value from any Standard Library function capable of returning EOF</td>
<td>N/A</td>
<td>Rule 22.7</td>
</tr>
<tr>
<td>Rule 22.8</td>
<td>Required</td>
<td>The value of errno shall be set to zero prior to a call to an errno-setting-function</td>
<td>N/A</td>
<td>Rule 22.8</td>
</tr>
<tr>
<td>Rule 22.9</td>
<td>Required</td>
<td>The value of errno shall be tested against zero after calling an errno-setting-function</td>
<td>N/A</td>
<td>Rule 22.9</td>
</tr>
<tr>
<td>Rule 22.10</td>
<td>Required</td>
<td>The value of errno shall only be tested when the last function to be called was an errno-setting-function</td>
<td>N/A</td>
<td>Rule 22.10</td>
</tr>
</tbody>
</table>

Additional rules

Rule A.1: Conditional Compilation

Severity Required

Description Do not conditionally compile function declarations in header files. Do not conditionally compile structure declarations in header files. You may conditionally exclude fields within structure definitions to avoid wasting memory when the feature they support is not enabled.

Rationale Excluding declarations from the header based on compile-time options may prevent their documentation from being generated. Their absence also prevents use of if
(IS_ENABLED(CONFIG_FOO)) {} as an alternative to preprocessor conditionals when the code path should change based on the selected options.

**Rule A.2: Inclusive Language**

**Severity**  Required

**Description**  Do not introduce new usage of offensive terms listed below. This rule applies but is not limited to source code, comments, documentation, and branch names. Replacement terms may vary by area or subsystem, but should aim to follow updated industry standards when possible.

Exceptions are allowed for maintaining existing implementations or adding new implementations of industry standard specifications governed externally to the Zephyr Project.

Existing usage is recommended to change as soon as updated industry standard specifications become available or new terms are publicly announced by the governing body, or immediately if no specifications apply.

<table>
<thead>
<tr>
<th>Offensive Terms</th>
<th>Recommended Replacements</th>
</tr>
</thead>
<tbody>
<tr>
<td>{master,leader} / slave</td>
<td>• {primary,main} / {secondary, replica}</td>
</tr>
<tr>
<td></td>
<td>• {initiator, requester} / {target, responder}</td>
</tr>
<tr>
<td></td>
<td>• {controller, host} / {device, worker, proxy, target}</td>
</tr>
<tr>
<td></td>
<td>• director / performer</td>
</tr>
<tr>
<td></td>
<td>• central / peripheral</td>
</tr>
<tr>
<td>blacklist / whitelist</td>
<td>• denylist / allowlist</td>
</tr>
<tr>
<td></td>
<td>• blocklist / allowlist</td>
</tr>
<tr>
<td></td>
<td>• rejectlist / acceptlist</td>
</tr>
<tr>
<td>grandfather policy</td>
<td>• legacy</td>
</tr>
<tr>
<td>sanity</td>
<td>• coherence</td>
</tr>
<tr>
<td></td>
<td>• confidence</td>
</tr>
</tbody>
</table>

**Rationale**  Offensive terms do not create an inclusive community environment and therefore violate the Zephyr Project Code of Conduct. This coding rule was inspired by a similar rule in Linux.

**Status**  Related GitHub Issues and Pull Requests are tagged with the Inclusive Language Label.
<table>
<thead>
<tr>
<th>Area</th>
<th>Selected Replacements</th>
<th>Status</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Bluetooth APIs</strong></td>
<td>See Bluetooth Appropriate Language Mapping Tables</td>
<td></td>
</tr>
<tr>
<td>CAN</td>
<td>This CAN in Automation Inclusive Language news post has a list of general recommendations. See CAN in Automation Inclusive Language for terms to be used in specification document updates.</td>
<td></td>
</tr>
<tr>
<td>eSPI</td>
<td>• master / slave =&gt; TBD</td>
<td></td>
</tr>
<tr>
<td>gPTP</td>
<td>• master / slave =&gt; TBD</td>
<td></td>
</tr>
<tr>
<td>Inter-Integrated Circuit (I2C) Bus</td>
<td>• master / slave =&gt; TBD</td>
<td>NXP publishes the I2C Specification and has selected controller / target as replacement terms, but the timing to publish an announcement or new specification is TBD. Zephyr will update I2C when replacement terminology is confirmed by a public announcement or updated specification. See Zephyr Issue 27033.</td>
</tr>
<tr>
<td>Inter-IC Sound (I2S) Bus</td>
<td>• master / slave =&gt; TBD</td>
<td></td>
</tr>
<tr>
<td>SMP/AMP</td>
<td>• master / slave =&gt; TBD</td>
<td></td>
</tr>
<tr>
<td>Serial Peripheral Interface (SPI) Bus</td>
<td>• master / slave =&gt; controller / peripheral</td>
<td>The Open Source Hardware Association has selected these replacement terms. See OSHWA Resolution to Redefine SPI Signal Names</td>
</tr>
<tr>
<td></td>
<td>• MOSI / MISO / SS =&gt; SDO / SDI / CS</td>
<td></td>
</tr>
<tr>
<td>Test Runner (Twister)</td>
<td>• platform_whitelist =&gt; platform_allow</td>
<td></td>
</tr>
<tr>
<td></td>
<td>• sanitycheck =&gt; twister</td>
<td></td>
</tr>
</tbody>
</table>

**Rule A.3: Macro name collisions**

**Severity** Required

**Description** Macros with commonly used names such as MIN, MAX, ARRAY_SIZE, must not be modified or protected to avoid name collisions with other implementations. In particular, they must not be prefixed to place them in a Zephyr-specific namespace, re-defined using #undef, or conditionally excluded from compilation using #ifndef. Instead, if a conflict arises with an existing definition originating from a *module*, the module's code itself needs to be modified (ideally upstream, alternatively via a change in Zephyr's own fork). This rule applies to Zephyr as
a project in general, regardless of the time of introduction of the macro or its current name in the tree. If a macro name is commonly used in several other well-known open source projects then the implementation in Zephyr should use that name. While there is a subjective and non-measurable component to what “commonly used” means, the ultimate goal is to offer users familiar macros. Finally, this rule applies to inter-module name collisions as well: in that case both modules, prior to their inclusion, should be modified to use module-specific versions of the macro name that collides.

Rationale  Zephyr is an RTOS that comes with additional functionality and dependencies in the form of modules. Those modules are typically independent projects that may use macro names that can conflict with other modules or with Zephyr itself. Since, in the context of this documentation, Zephyr is considered the central or main project, it should implement the non-namespaced versions of the macros. Given that Zephyr uses a fork of the corresponding upstream for each module, it is always possible to patch the macro implementation in each module to avoid collisions.

Rule A.4: C Standard Library Usage Restrictions in Zephyr Kernel

Severity  Required

Description  The use of the C standard library functions and macros in the Zephyr kernel shall be limited to the following functions and macros from the ISO/IEC 9899:2011 standard, also known as C11, and their extensions:

Table 2: List of allowed libc functions and macros in the Zephyr kernel

<table>
<thead>
<tr>
<th>Function</th>
<th>Source</th>
</tr>
</thead>
<tbody>
<tr>
<td>abort()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>abs()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>aligned_alloc()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>assert()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>atoi()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>bsearch()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>calloc()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>exit()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>fprintf()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>fputc()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>fputs()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>free()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>fwrite()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>gmtime()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>isalnum()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>isalpha()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>iscntrl()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>isdigit()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>isgraph()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>isprint()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>isupperr()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>isxdigit()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>labs()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>llabs()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
</tbody>
</table>

continues on next page
All of the functions listed above must be implemented by the *minimal libc* to ensure that the Zephyr kernel can build with the minimal libc.

In addition, any functions from the above list that are not part of the ISO/IEC 9899:2011 standard must be implemented by the *common libc* to ensure their availability across multiple C standard libraries.

Introducing new C standard library functions to the Zephyr kernel is allowed with justification given that the above requirements are satisfied.

Note that the use of the functions listed above are subject to secure and safe coding practices and it should not be assumed that their use in the Zephyr kernel is unconditionally permitted by

---

<table>
<thead>
<tr>
<th>Function</th>
<th>Source</th>
</tr>
</thead>
<tbody>
<tr>
<td>malloc()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>memchr()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>memcmp()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>memcpy()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>memmove()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>memset()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>perror()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>printf()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>putc()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>putchar()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>puts()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>qsort()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>rand()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>realloc()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>sprintf()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>sqrt()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>sqrtf()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>rand()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strcat()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strchr()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strcmp()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strcpy()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strcspn()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strerror()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strlen()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strncat()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strncmp()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strncpy()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strnlen()</td>
<td>POSIX.1-2008</td>
</tr>
<tr>
<td>strchr()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strspn()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strstr()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strtol()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strtoll()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strtoul()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>strtoull()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>time()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>tolower()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>toupper()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>vfprintf()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>vprintf()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>vsnprintf()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
<tr>
<td>vsprintf()</td>
<td>ISO/IEC 9899:2011</td>
</tr>
</tbody>
</table>
being listed in this rule.

The “Zephyr kernel” in this context consists of the following components:

- Kernel (kernel)
- OS Library (lib/os)
- Architecture Port (arch)
- Logging Subsystem (subsys/logging)

Rationale  Zephyr kernel must be able to build with the minimal libc, a limited C standard library implementation that is part of the Zephyr RTOS and maintained by the Zephyr Project, to allow self-contained testing and verification of the kernel and core OS services.

In order to ensure that the Zephyr kernel can build with the minimal libc, it is necessary to restrict the use of the C standard library functions and macros in the Zephyr kernel to the functions and macros that are available as part of the minimal libc.

**Rule A.5: C Standard Library Usage Restrictions in Zephyr Codebase**

**Severity**  Required

**Description**  The use of the C standard library functions and macros in the Zephyr codebase shall be limited to the functions, excluding the Annex K “Bounds-checking interfaces”, from the ISO/IEC 9899:2011 standard, also known as C11, unless exempted by this rule.

The “Zephyr codebase” in this context refers to all embedded source code files committed to the main Zephyr repository, except the Zephyr kernel as defined by the Rule A.4: C Standard Library Usage Restrictions in Zephyr Kernel. With embedded source code we refer to code which is meant to be executed in embedded targets, and therefore excludes host tooling, and code specific for the native test targets.

The following non-ISO 9899:2011, hereinafter referred to as non-standard, functions and macros are exempt from this rule and allowed to be used in the Zephyr codebase:

<table>
<thead>
<tr>
<th>Function</th>
<th>Source</th>
</tr>
</thead>
<tbody>
<tr>
<td>strlen()</td>
<td>POSIX.1-2008</td>
</tr>
<tr>
<td>strtok_r()</td>
<td>POSIX.1-2001</td>
</tr>
</tbody>
</table>

All non-standard functions and macros listed above must be implemented by the common libc in order to make sure that these functions can be made available when using a C standard library that does not implement these functions.

Adding a new non-standard function from common C standard libraries to the above list is allowed with justification, given that the above requirement is satisfied. However, when there exists a standard function that is functionally equivalent, the standard function shall be used.

Rationale  Some C standard libraries, such as Newlib and Picolibc, include additional functions and macros that are defined by the standards and de-facto standards that extend the ISO C standard (e.g. POSIX, Linux).

The ISO/IEC 9899:2011 standard does not require C compiler toolchains to include the support for these non-standard functions, and therefore using these functions can lead to compatibility issues with the third-party toolchains that come with their own C standard libraries.
8.1.3 Proposals and RFCs

Many changes, including bug fixes and documentation improvements can be implemented and reviewed via the normal GitHub pull request workflow.

Many changes however are “substantial” and need to go through a design process and produce a consensus among the project stakeholders.

The “RFC” (request for comments) process is intended to provide a consistent and controlled path for new features to enter the project.

Contributors and project stakeholders should consider using this process if they intend to make “substantial” changes to Zephyr or its documentation. Some examples that would benefit from an RFC are:

- A new feature that creates new API surface area, and would require a feature flag if introduced.
- The modification of an existing stable API.
- The removal of features that already shipped as part of Zephyr.
- The introduction of new idiomatic usage or conventions, even if they do not include code changes to Zephyr itself.

The RFC process is a great opportunity to get more eyeballs on proposals coming from contributors before it becomes a part of Zephyr. Quite often, even proposals that seem “obvious” can be significantly improved once a wider group of interested people have a chance to weigh in.

The RFC process can also be helpful to encourage discussions about a proposed feature as it is being designed, and incorporate important constraints into the design while it’s easier to change, before the design has been fully implemented.

Some changes do not require an RFC:

- Rephrasing, reorganizing or refactoring
- Addition or removal of warnings
- Addition of new boards, SoCs or drivers to existing subsystems
- ...

The process in itself consists in creating a GitHub issue with the RFC label that documents the proposal thoroughly. There is an RFC template included in the main Zephyr GitHub repository that serves as a guideline to write a new RFC.

As with Pull Requests, RFCs might require discussion in the context of one of the Zephyr meetings in order to move it forward in cases where there is either disagreement or not enough voiced opinions in order to proceed. Make sure to either label it appropriately or include it in the corresponding GitHub project in order for it to be examined during the next meeting.

8.1.4 Contributor Expectations

The Zephyr project encourages contributors to submit changes as smaller pull requests. Smaller pull requests (PRs) have the following benefits:

- Reviewed more quickly and reviewed more thoroughly. It’s easier for reviewers to set aside a few minutes to review smaller changes several times than it is to allocate large blocks of time to review a large PR.
- Less wasted work if reviewers or maintainers reject the direction of the change.
- Easier to rebase and merge. Smaller PRs are less likely to conflict with other changes in the tree.
- Easier to revert if the PR breaks functionality.
**Note:** This page does not apply to draft PRs which can have any size, any number of commits and any combination of smaller PRs for testing and preview purposes. Draft PRs have no review expectation and PRs created as drafts from the start do not notify anyone by default.

### Defining Smaller PRs

- Smaller PRs should encompass one self-contained logical change.
- When adding a new large feature or API, the PR should address only one part of the feature. In this case create an RFC proposal to describe the additional parts of the feature for reviewers.
- PRs should include tests or samples under the following conditions:
  - Adding new features or functionality.
  - Modifying a feature, especially for API behavior contract changes.
  - Fixing a hardware agnostic bug. The test should fail without the bug fixed and pass with the fix applied.
- PRs must update any documentation affected by a functional code change.
- If introducing a new API, the PR must include an example usage of the API. This provides context to the reviewer and prevents submitting PRs with unused APIs.

### Multiple Commits on a Single PR

Contributors are further encouraged to break up PRs into multiple commits. Keep in mind each commit in the PR must still build cleanly and pass all the CI tests.

For example, when introducing an extension to an API, contributors can break up the PR into multiple commits targeting these specific changes:

1. Introduce the new APIs, including shared devicetree bindings
2. Update driver implementation X, with driver specific devicetree bindings
3. Update driver implementation Y
4. Add tests for the new API
5. Add a sample using the API
6. Update the documentation

### Large Changes

Large changes to the Zephyr project must submit an RFC proposal describing the full scope of change and future work. The RFC proposal provides the required context to reviewers, but allows for smaller, incremental, PRs to get reviewed and merged into the project. The RFC should also define the minimum viable implementation.

Changes which require an RFC proposal include:

- Submitting a new feature.
- Submitting a new API.
- Treewide Changes.
- Other large changes that can benefit from the RFC proposal process.
Maintainers have the discretion to request that contributors create an RFC for PRs that are too large or complicated.

**PR Requirements**

- Each commit in the PR must provide a commit message following the [Commit Message Guidelines](#).
- All files in the PR must comply with [Licensing Requirements](#).
- Follow the Zephyr [Coding Style](#) and [Coding Guidelines](#).
- PRs must pass all CI checks. This is a requirement to merge the PR. Contributors may mark a PR as draft and explicitly request reviewers to provide early feedback, even with failing CI checks.
- When breaking a PR into multiple commits, each commit must build cleanly. The CI system does not enforce this policy, so it is the PR author's responsibility to verify.
- When major new functionality is added, tests for the new functionality shall be added to the automated test suite. All API functions should have test cases and there should be tests for the behavior contracts of the API. Maintainers and reviewers have the discretion to determine if the provided tests are sufficient. The examples below demonstrate best practices on how to test APIs effectively.
  - **Kernel timer tests** provide around 85% test coverage for the kernel timer, measured by lines of code.
  - **Emulators for off-chip peripherals** are an effective way to test driver APIs. The fuel gauge tests use the smart battery emulator, providing test coverage for the fuel gauge API and the smart battery driver.
  - Code coverage reports for the Zephyr project are available on Codecov.
- Incompatible changes to APIs must also update the release notes for the next release detailing the change. APIs marked as experimental are excluded from this requirement.
- Changes to APIs must increment the API version number according to the API version rules.
- PRs must also satisfy all [Merge Criteria](#) before a member of the release engineering team merges the PR into the zephyr tree.

Maintainers may request that contributors break up a PR into smaller PRs and may request that they create an [RFC proposal](#).

**Workflow Suggestions That Help Reviewers**

- Unless they applied the reviewer's recommendation exactly, authors must not resolve and hide comments, they must let the initial reviewer do it. The Zephyr project does not require all comments to be resolved before merge. Leaving some completed discussions open can sometimes be useful to understand the greater picture.
- Respond to comments using the “Start Review” and “Add Review” green buttons in the “Files changed” view. This allows responding to multiple comments and publishing the responses in bulk. This reduces the number of emails sent to reviewers.
- As GitHub does not implement `git range-diff`, try to minimize rebases in the middle of a review. If a rebase is required, push this as a separate update with no other changes since the last push of the PR. When pushing a rebase only, add a comment to the PR indicating which commit is the rebase.
PR Review Escalation The Zephyr community is a diverse group of individuals, with different levels of commitment and priorities. As such, reviewers and maintainers may not get to a PR right away.

The Zephyr Dev Meeting performs a triage of PRs missing reviewer approval, following this process:

1. Identify and update PRs missing an Assignee.
2. Identify PRs without any comments or reviews, ping the PR Assignee to start a review or assign to a different maintainer.
3. For PRs that have otherwise stalled, the Zephyr Dev Meeting pings the Assignee and any reviewers that have left comments on the PR.

Contributors may escalate PRs outside of the Zephyr Dev Meeting triage process as follows:

• After 1 week of inactivity, ping the Assignee or reviewers on the PR by adding a comment to the PR.
• After 2 weeks of inactivity, post a message on the #pr-help channel on Discord linking to the PR.
• After 2 weeks of inactivity, add the dev-review label to the PR. This explicitly adds the PR to the agenda for the next Zephyr Dev Meeting independent of the triage process. Not all contributors have the required privileges to add labels to PRs, in this case the contributor should request help on Discord or send an email to the Zephyr devel mailing list.

Note that for new PRs, contributors should generally wait for at least one Zephyr Dev Meeting before escalating the PR themselves.

PR Technical Escalation In cases where a contributor objects to change requests from reviewers, Zephyr defines the following escalation process for resolving technical disagreements.

Before escalation of technical disagreements, follow the steps below:

• Resolve in the PR among assignee, maintainers and reviewer:
  – Assignee to act as moderator if applicable.
• Optionally resolve in the next Zephyr Dev Meeting meeting with more Maintainers and project stakeholders.
  – The involved parties and the Assignee to be present when the issue is discussed.
• If no progress is made, the assignee (maintainer) has the right to dismiss stale, unrelated or irrelevant change requests by reviewers giving the reviewers a minimum of 1 business day to respond and revisit their initial change requests or start the escalation process.

The assignee has the responsibility to document the reasoning for dismissing any reviews in the PR and should notify the reviewer about their review being dismissed.

To give the reviewers time to respond and escalate, the assignee is expected to block the PR from being merged either by not approving the PR or by setting the DNM label.

Escalation can be triggered by any party participating in the review process (assignee, reviewers or the original author of the change) following the steps below:

• Escalate to the Architecture Working Group by adding the Architecture Review label on the PR. Beside the weekly meeting where such escalations are processed, the Architecture Working Group shall facilitate an offline review of the escalation if requested, especially if any of the parties can’t attend the meeting.
• If all avenues of resolution and escalation have failed, assignees can escalate to the TSC and get a binding resolution in the TSC by adding the TSC label on the PR.
• The Assignee is expected to ensure the resolution of the escalation and the outcome is documented in the related pull request or issues on Github.

8.1. General Guidelines
Reviewer Expectations

- Be respectful when commenting on PRs. Refer to the Zephyr Code of Conduct for more details.

- The Zephyr Project recognizes that reviewers and maintainers have limited bandwidth. As a reviewer, prioritize review requests in the following order:
  1. PRs related to items in the Zephyr Release Plan or those targeting the next release during the stabilization period (after RC1).
  2. PRs where the reviewer has requested blocking changes.
  3. PRs assigned to the reviewer as the area maintainer.
  4. All other PRs.

- Try to provide feedback on the entire PR in one shot. This provides the contributor an opportunity to address all comments in the next PR update.

- Partial reviews are permitted, but the reviewer must add a comment indicating what portion of the PR they reviewed. Examples of useful partial reviews include:
  - Domain specific reviews (e.g. Devicetree).
  - Code style changes that impact the readability of the PR.
  - Reviewing commits separately when the requested changes cascade into the later commits.

- Avoid increasing scope of the PR by requesting new features, especially when there is a corresponding RFC associated with the PR. Instead, reviewers should add suggestions as a comment to the RFC. This also encourages more collaboration as it is easier for multiple contributors to work on a feature once the minimum implementation has merged.

- When using the “Request Changes” option, mark trivial, non-functional, requests as “Non-blocking” in the comment. Reviewers should approve PRs once only non-blocking changes remain. The PR author has discretion as to whether they address all non-blocking comments. PR authors should acknowledge every review comment in some way, even if it’s just with an emoticon.

- Reviewers shall be clear and concise what changes they are requesting when the “Request Changes” option is used. Requested changes shall be in the scope of the PR in question and following the contribution and style guidelines of the project.

Contribution Guidelines

Learn about the overall process and guidelines for contributing to the Zephyr project.

This page is a mandatory read for first-time contributors as it contains important information on how to ensure your contribution can be considered for inclusion in the project and potentially merged.

Contributor Expectations

This document is another mandatory read that describes the expected behavior of all contributors to the project.

Coding Guidelines

Code contributions are expected to follow a set of coding guidelines to ensure consistency and readability across the code base.

This page describes these guidelines and introduces important considerations regarding the use of inclusive language.

Proposals and RFCs

Learn when and how to submit RFCs (Request for Comments) for new features and changes to the project.
8.2  Documentation

The Zephyr project thrives on good documentation. Whether it is as part of a code contribution or as a standalone effort, contributing documentation is particularly valuable to the project.

8.2.1  Documentation Guidelines

Note: For instructions on building the documentation, see Documentation Generation.

Zephyr Project content is written using the reStructuredText markup language (.rst file extension) with Sphinx extensions, and processed using Sphinx to create a formatted standalone website. Developers can view this content either in its raw form as .rst markup files, or (with Sphinx installed) they can build the documentation locally to generate the documentation in HTML or PDF format. The HTML content can then be viewed using a web browser. This same .rst content is served by the Zephyr documentation website.

You can read details about reStructuredText and about Sphinx extensions from their respective websites.

This document provides a quick reference for commonly used reST and Sphinx-defined directives and roles used to create the documentation you’re reading.

Headings

While reST allows use of both and overline and matching underline to indicate a heading, we only use an underline indicator for headings.

- Document title (h1) use “#” for the underline character
- First section heading level (h2) use “**”
- Second section heading level (h3) use “=”
- Third section heading level (h4) use “-”

The heading underline must be at least as long as the title it’s under.

For example:

```
This is a title heading
#######################
some content goes here
First section heading
*********************
```

Content Highlighting

Some common reST inline markup samples:

- one asterisk: *text* for emphasis (italics),
- two asterisks: **text** for strong emphasis (boldface), and
- two backquotes: `text` for inline code samples.

If asterisks or backquotes appear in running text and could be confused with inline markup delimiters, you can eliminate the confusion by adding a backslash (\) before it.
Lists

For bullet lists, place an asterisk (*) or hyphen (-) at the start of a paragraph and indent continuation lines with two spaces.

The first item in a list (or sublist) must have a blank line before it and should be indented at the same level as the preceding paragraph (and not indented itself).

For numbered lists start with a 1. or a. for example, and continue with autonumbering by using a # sign. Indent continuation lines with three spaces:

* This is a bulleted list.
  * It has two items, the second
    item and has more than one line of reST text. Additional lines
    are indented to the first character of the
    text of the bullet list.

1. This is a new numbered list. If the wasn't a blank line before it, it would be a continuation of the previous list (or paragraph).
   #. It has two items too.

a. This is a numbered list using alphabetic list headings
   #. It has three items (and uses autonumbering for the rest of the list)
   #. Here's the third item

#. This is an autonumbered list (default is to use numbers starting with 1).
   #. This is a second-level list under the first item (also autonumbered). Notice the indenting.
   #. And a second item in the nested list.
   #. And a second item back in the containing list. No blank line needed, but it wouldn't hurt for readability.

Definition lists (with a term and its definition) are a convenient way to document a word or phrase with an explanation. For example this reST content:

The Makefile has targets that include:

html
  Build the HTML output for the project

clean
  Remove all generated output, restoring the folders to a clean state.

Would be rendered as:

The Makefile has targets that include:

html
  Build the HTML output for the project

clean
  Remove all generated output, restoring the folders to a clean state.

Multi-column lists

If you have a long bullet list of items, where each item is short, you can indicate the list items should be rendered in multiple columns with a special .. rst-class:: rst-columns directive. The directive will apply to the next non-comment element (e.g., paragraph), or to content indented under the directive. For example, this unordered list:
.. rst-class:: rst-columns

* A list of
* short items
* that should be
* displayed
* horizontally
* so it doesn’t
* use up so much
* space on
* the page

would be rendered as:

- A list of
  - short items
  - that should be
  - displayed
  - horizontally
  - so it doesn’t
  - use up so much
  - space on
  - the page

A maximum of three columns will be displayed, and change based on the available width of the display window, reducing to one column on narrow (phone) screens if necessary. We’ve deprecated use of the hlist directive because it misbehaves on smaller screens.

## Tables

There are a few ways to create tables, each with their limitations or quirks. Grid tables offer the most capability for defining merged rows and columns, but are hard to maintain:

<table>
<thead>
<tr>
<th>Header row, column 1</th>
<th>Header 2</th>
<th>Header 3</th>
<th>Header 4</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>-------</td>
<td>--------</td>
<td>--------</td>
</tr>
<tr>
<td></td>
<td>-------</td>
<td>--------</td>
<td>--------</td>
</tr>
<tr>
<td>body row 1, column 1</td>
<td>column 2</td>
<td>column 3</td>
<td>column 4</td>
</tr>
<tr>
<td></td>
<td>-------</td>
<td>--------</td>
<td>--------</td>
</tr>
<tr>
<td></td>
<td>-------</td>
<td>--------</td>
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<td></td>
<td>-------</td>
<td>--------</td>
<td>--------</td>
</tr>
<tr>
<td></td>
<td>-------</td>
<td>--------</td>
<td>--------</td>
</tr>
</tbody>
</table>

This example would render as:

<table>
<thead>
<tr>
<th>Header row, column 1 (header rows optional)</th>
<th>Header 2</th>
<th>Header 3</th>
<th>Header 4</th>
</tr>
</thead>
<tbody>
<tr>
<td>body row 1, column 1</td>
<td>column 2</td>
<td>column 3</td>
<td>column 4</td>
</tr>
<tr>
<td>body row 2</td>
<td>...</td>
<td>...</td>
<td>you can easily span rows too</td>
</tr>
<tr>
<td>body row 3 with a two column span</td>
<td>...</td>
<td>span</td>
<td>rows</td>
</tr>
<tr>
<td>body row 4</td>
<td>...</td>
<td>...</td>
<td>too</td>
</tr>
</tbody>
</table>
List tables are much easier to maintain, but don’t support row or column spans:

```plaintext
.. list-table:: Table title
   :widths: 15 20 40
   :header-rows: 1

   * - Heading 1
     - Heading 2
     - Heading 3
   * - body row 1, column 1
     - body row 1, column 2
     - body row 1, column 3
   * - body row 2, column 1
     - body row 2, column 2
     - body row 2, column 3

This example would render as:

<table>
<thead>
<tr>
<th>Heading 1</th>
<th>Heading 2</th>
<th>Heading 3</th>
</tr>
</thead>
<tbody>
<tr>
<td>body row 1, column 1</td>
<td>body row 1, column 2</td>
<td>body row 1, column 3</td>
</tr>
<tr>
<td>body row 2, column 1</td>
<td>body row 2, column 2</td>
<td>body row 2, column 3</td>
</tr>
</tbody>
</table>
```

The :widths: parameter lets you define relative column widths. The default is equal column widths. If you have a three-column table and you want the first column to be half as wide as the other two equal-width columns, you can specify :widths: 1 2 2. If you’d like the browser to set the column widths automatically based on the column contents, you can use :widths: auto.

### File names and Commands

Sphinx extends reST by supporting additional inline markup elements (called “roles”) used to tag text with special meanings and allow style output formatting. (You can refer to the Sphinx Inline Markup documentation for the full list).

For example, there are roles for marking filenames (:file:`name`) and command names such as `make` (:command:`make`). You can also use the “inline code“ markup (double backticks) to indicate a filename.

For references to files that are in the Zephyr GitHub tree, a special role can be used that creates a hyperlink to that file. For example a reference to the reST file used to create this document can be generated using :zephyr_file:`doc/contribute/documentation/index.rst` that will show up as `doc/contribute/documentation/index.rst`, a link to the “blob” file in the github repo. There's also a :zephyr_raw:`doc/guides/documentation/index.rst` role that will link to the “raw” content, `doc/contribute/documentation/index.rst`. (You can click on these links to see the difference.)

### Internal Cross-Reference Linking

Traditional ReST links are only supported within the current file using the notation:

```
Refer to the `internal-linking` page
```

which renders as,

Refer to the `internal-linking` page
Note the use of a trailing underscore to indicate an outbound link. In this example, the label was added immediately before a heading, so the text that's displayed is the heading text itself. You can change the text that's displayed as the link writing this as:

Refer to the `show this text instead <internal-linking_>` page

which renders as,

Refer to the show this text instead page

**External Cross-Reference Linking**

With Sphinx's help, we can create link-references to any tagged text within the Zephyr Project documentation.

Target locations in a document are defined with a label directive:

```
.. _my label name:

Heading
=======
```

Note the leading underscore indicating an inbound link. The content immediately following this label must be a heading, and is the target for a `:ref:`my label name` reference from anywhere within the Zephyr documentation. The heading text is shown when referencing this label. You can also change the text that's displayed for this link, such as:

```
:ref:`some other text <my label name>`
```

To enable easy cross-page linking within the site, each file should have a reference label before its title so it can be referenced from another file. These reference labels must be unique across the whole site, so generic names such as “samples” should be avoided. For example the top of this document's .rst file is:

```
.. _doc_guidelines:

Documentation Guidelines for the Zephyr Project
#################################################
```

Other .rst documents can link to this document using the `:ref:`doc_guidelines` tag and it will show up as Documentation Guidelines. This type of internal cross reference works across multiple files, and the link text is obtained from the document source so if the title changes, the link text will update as well.

You can also define links to any URL and then reference it in your document. For example, with this label definition in the document:

```
.. _Zephyr Wikipedia Page:

https://en.wikipedia.org/wiki/Zephyr_(operating_system)
```

you can reference it with:

```
Read the `Zephyr Wikipedia Page`_ for more information about the project.
```

**any** links

Within the Zephyr project, we've defined the default role to be “any”, meaning if you just write a phrase in back-ticks, e.g., `doc_guidelines`, Sphinx will search through all domains looking for something called doc_guidelines to link to. In this case it will find the label at the top of this
Non-ASCII Characters

You can insert non-ASCII characters such as a Trademark symbol (™), by using the notation \[trade\]. Available replacement names are defined in an include file used during the Sphinx processing of the reST files. The names of these replacement characters are the same as used in HTML entities used to insert characters in HTML, e.g., &trade; and are defined in the file sphinx_build/substitutions.txt as listed here:

```
.. |br| raw:: html .. force a line break in HTML output (blank lines needed here)
  <br />
.. |p| raw:: html .. force a blank line in HTML output (blank lines needed here)
  <p></p>
.. These are replacement strings for non-ASCII characters used within the project using the same name as the html entity names (e.g., &copy;) for that character

.. |copy| unicode:: U+000A9 .. COPYRIGHT SIGN
  :ltrim:
.. |trade| unicode:: U+02122 .. TRADEMARK SIGN
  :ltrim:
.. |reg| unicode:: U+000AE .. REGISTERED TRADEMARK SIGN
  :ltrim:
.. |deg| unicode:: U+00B0 .. DEGREE SIGN
  :ltrim:
.. |plusminus| unicode:: U+00B1 .. PLUS-MINUS SIGN
  :rtrim:
.. |micro| unicode:: U+00B5 .. MICRO SIGN
  :rtrim:
.. |sup2| unicode:: U+00B2 .. SUPERSCRIPT TWO
  :ltrim:
```

We've kept the substitutions list small but others can be added as needed by submitting a change to the substitutions.txt file.

Code and Command Examples

Use the reST code-block directive to create a highlighted block of fixed-width text, typically used for showing formatted code or console commands and output. Smart syntax highlighting is also supported (using the Pygments package). You can also directly specify the highlighting language. For example:

```
.. code-block:: c

  struct k_object {
    char *name;
    uint8_t perms[CONFIG_MAX_THREAD_BYTES];
    uint8_t type;
    uint8_t flags;
  };
```

(continues on next page)
Note the blank line between the code-block directive and the first line of the code-block body, and the body content is indented three spaces (to the first non-white space of the directive name).

This would be rendered as:

```c
struct k_object {
    char *name;
    uint8_t perms[CONFIG_MAX_THREAD_BYTES];
    uint8_t type;
    uint8_t flags;
    uint32_t data;
} __packed;
```

Other languages are of course supported (see languages supported by Pygments), and in particular, you are encouraged to make use of the following when appropriate:

- `c` for C code
- `cpp` for C++ code
- `python` for Python code
- `console` for console output, i.e. interactive shell sessions where commands are prefixed by a prompt (ex. `$` for Linux, or `uart:~$` for Zephyr's shell), and where the output is also shown. The commands will be highlighted, and the output will not. What's more, copying code block using the “copy” button will automatically copy just the commands, excluding the prompt and the outputs of the commands.
- `shell` or `bash` for shell commands. Both languages get highlighted the same but you may use `bash` for conveying that the commands are bash-specific, and `shell` for generic shell commands.

**Note:** Do not use `bash` or `shell` if your code block includes a prompt, use `console` instead. Reciprocally, do not use `console` if your code block does not include a prompt and is not showcasing an interactive session with command(s) and their output.

### Table 5: When to use bash/shell vs. console

<table>
<thead>
<tr>
<th>Use case</th>
<th>code-block snippet</th>
<th>Expected output</th>
</tr>
</thead>
</table>
| One or several commands, no output                    | `.. code-block:: shell
echo "Hello World!"
` | `echo "Hello World!"` |
| An interactive shell session with command(s) and their output | `.. code-block:: console
$ echo "Hello World!"
Hello World!` | `$ echo "Hello World!"
Hello World!` |
| An interactive Zephyr shell session, with commands and their outputs | `.. code-block:: console
uart:~$ version
Zephyr version 3.5.99
uart:~$ kernel uptime
Uptime: 20970 ms` | `uart:~$ version
Zephyr version 3.5.99
uart:~$ kernel uptime
Uptime: 20970 ms` |
• bat for Windows batch files
• cfg for config files with “KEY=value” entries (ex. Kconfig .conf files)
• cmake for CMake
• devicetree for Devicetree
• kconfig for Kconfig
• yaml for YAML
• rst for reStructuredText

When no language is specified, the language is set to none and the code block is not highlighted. You may also use none explicitly to achieve the same result; for example:

```
.. code-block:: none

This would be a block of text styled with a background and box, but with no syntax highlighting.
```

Would display as:

```
This would be a block of text styled with a background and box, but with no syntax highlighting.
```

There's a shorthand for writing code blocks too: end the introductory paragraph with a double colon (::) and indent the code block content that follows it by three spaces. On output, only one colon will be shown. The code block will have no highlighting (i.e. none). You may however use the .. highlight:: directive to customize the default language used in your document (see for example how this is done at the beginning of this very document).

**Images**

Images are included in documentation by using an image directive:

```
.. image:: ../images/doc-gen-flow.png
   :align: center
   :alt: alt text for the image
```

or if you'd like to add an image caption, use:

```
.. figure:: ../images/doc-gen-flow.png
   :alt: image description

   Caption for the figure
```

The file name specified is relative to the document source file, and we recommend putting images into an images folder where the document source is found. The usual image formats handled by a web browser are supported: JPEG, PNG, GIF, and SVG. Keep the image size only as large as needed, generally at least 500 px wide but no more than 1000 px, and no more than 250 KB unless a particularly large image is needed for clarity.

**Tabs, spaces, and indenting**

Indenting is significant in reST file content, and using spaces is preferred. Extra indenting can (unintentionally) change the way content is rendered too. For lists and directives, indent the content text to the first non-white space in the preceding line. For example:
Refer to the Zephyr Coding Style for additional requirements.

**zephyr-app-commands Directive**

This is a Zephyr directive for generating consistent documentation of the shell commands needed to manage (build, flash, etc.) an application.

For example, to generate commands to build samples/hello_world for qemu_x86 use:

```
.. zephyr-app-commands::
   :zephyr-app: samples/hello_world
   :board: qemu_x86
   :goals: build
```

Directive options:

- **:tool:**
  which tool to use. Valid options are currently ‘cmake’, ‘west’ and ‘all’. The default is ‘west’.

- **:app:**
  path to the application to build.

- **zephyr-app:**
  path to the application to build, this is an app present in the upstream zephyr repository. Mutually exclusive with :app:

- **:cd-into:**
  if set, build instructions are given from within the :app: folder, instead of outside of it.

- **:generator:**
  which build system to generate. Valid options are currently ‘ninja’ and ‘make’. The default is ‘ninja’. This option is not case sensitive.

- **:host-os:**
  which host OS the instructions are for. Valid options are ‘unix’, ‘win’ and ‘all’. The default is ‘all’.

- **:board:**
  if set, the application build will target the given board.

- **:shield:**
  if set, the application build will target the given shield.

- **:conf:**
  if set, the application build will use the given configuration file. If multiple conf files are provided, enclose the space-separated list of files with quotes, e.g., “a.conf b.conf”.

- **:gen-args:**
  if set, additional arguments to the CMake invocation
:build-args:
if set, additional arguments to the build invocation

:build-dir:
if set, the application build directory will *APPEND* this (relative, Unix-separated) path to the standard build directory. This is mostly useful for distinguishing builds for one application within a single page.

:build-dir-fmt:
if set, assume that “west config build.dir-fmt” has been set to this path. Exclusive with ‘build-dir’ and depends on ‘tool=west’.

:goals:
a whitespace-separated list of what to do with the app (in ‘build’, ‘flash’, ‘debug’, ‘debugserver’, ‘run’). Commands to accomplish these tasks will be generated in the right order.

:maybe-skip-config:
if set, this indicates the reader may have already created a build directory and changed there, and will tweak the text to note that doing so again is not necessary.

:compact:
if set, the generated output is a single code block with no additional comment lines

:west-args:
if set, additional arguments to the west invocation (ignored for CMake)

:flash-args:
if set, additional arguments to the flash invocation

For example, the .. zephyr-app-commands listed above would render like this in the generated HTML output:

```
# From the root of the zephyr repository
west build -b qemu_x86 samples/hello_world
```

Alternative Tabbed Content

As introduced in the *Getting Started Guide*, you can provide alternative content to the reader via a tabbed interface. When the reader clicks on a tab, the content for that tab is displayed, for example:

```
.. tabs::
    .. tab:: Apples
        Apples are green, or sometimes red.
    .. tab:: Pears
        Pears are green.
    .. tab:: Oranges
        Oranges are orange.
```

will display as:

Apples
Apples are green, or sometimes red.
Pears
Pears are green.

Oranges

Oranges are orange.

Tabs can also be grouped, so that changing the current tab in one area changes all tabs with the same name throughout the page. For example:

Linux
Linux Line 1
macOS
macOS Line 1
Windows
Windows Line 1
Linux
Linux Line 2
macOS
macOS Line 2
Windows
Windows Line 2

In this latter case, we're using `.. group-tab::` instead of simply `.. tab::`. Under the hood, we're using the `sphinx-tabs` extension that's included in the Zephyr setup. Within a tab, you can have most any content *other than a heading* (code-blocks, ordered and unordered lists, pictures, paragraphs, and such). You can read more about `sphinx-tabs` from the link above.

### 8.2.2 Documentation Generation

These instructions will walk you through generating the Zephyr Project's documentation on your local system using the same documentation sources as we use to create the online documentation found at [https://docs.zephyrproject.org](https://docs.zephyrproject.org)

**Documentation overview**

Zephyr Project content is written using the `reStructuredText` markup language (.rst file extension) with Sphinx extensions, and processed using Sphinx to create a formatted stand-alone website. Developers can view this content either in its raw form as .rst markup files, or you can generate the HTML content and view it with a web browser directly on your workstation. This same .rst content is also fed into the Zephyr Project's public website documentation area (with a different theme applied).

You can read details about `reStructuredText`, and `Sphinx` from their respective websites.

The project's documentation contains the following items:

- ReStructuredText source files used to generate documentation found at the [https://docs.zephyrproject.org](https://docs.zephyrproject.org) website. Most of the reStructuredText sources are found in the `/doc` directory, but others are stored within the code source tree near their specific component (such as `/samples` and `/boards`)
- Doxygen-generated material used to create all API-specific documents also found at [https://docs.zephyrproject.org](https://docs.zephyrproject.org)
Script-generated material for kernel configuration options based on Kconfig files found in the source code tree

The reStructuredText files are processed by the Sphinx documentation system, and make use of the breathe extension for including the doxygen-generated API material. Additional tools are required to generate the documentation locally, as described in the following sections.

**Installing the documentation processors**

Our documentation processing has been tested to run with:

- Doxygen version 1.8.13
- Graphviz 2.43
- Latexmk version 4.56
- All Python dependencies listed in the repository file `doc/requirements.txt`

In order to install the documentation tools, first install Zephyr as described in *Getting Started Guide*. Then install additional tools that are only required to generate the documentation, as described below:

**Linux**

Common to all Linux installations, install the Python dependencies required to build the documentation:

```bash
pip install -r ~/zephyrproject/zephyr/doc/requirements.txt
```

**On Ubuntu Linux:**

```bash
sudo apt-get install --no-install-recommends doxygen graphviz librsvg2-bin \
texlive-latex-base texlive-latex-extra latexmk texlive-fonts-recommended
```

**On Fedora Linux:**

```bash
sudo dnf install doxygen graphviz texlive-latex latexmk \
texlive-collection-fontsrecommended librsvg2-tools
```

**On Clear Linux:**

```bash
```

Fig. 1: Schematic of the documentation build process
On Arch Linux:

```
sudo pacman -S graphviz doxygen librsvg texlive-core texlive-bin \
texlive-latexextra texlive-fontsextra
```

**macOS**

Install the Python dependencies required to build the documentation:

```
pip install -r ~/zephyrproject/zephyr/doc/requirements.txt
```

Use brew and tlmgr to install the tools:

```
brew install doxygen graphviz mactex librsvg
tlmgr install latexmk
tlmgr install collection-fontsrecommended
```

**Windows**

Install the Python dependencies required to build the documentation:

```
pip install -r %HOMEPATH%\zephyrproject\zephyr\doc\requirements.txt
```

Open a cmd.exe window as **Administrator** and run the following command:

```
choco install doxygen.install graphviz strawberryperl miktex rsvg-convert
```

**Note:** On Windows, the Sphinx executable `sphinx-build.exe` is placed in the **Scripts** folder of your Python installation path. Depending on how you have installed Python, you might need to add this folder to your **PATH** environment variable. Follow the instructions in **Windows Python Path** to add those if needed.

---

**Documentation presentation theme**

Sphinx supports easy customization of the generated documentation appearance through the use of themes. Replace the theme files and do another `make html` and the output layout and style is changed. The **read-the-docs** theme is installed as part of the **Get Zephyr and install Python dependencies** step you took in the getting started guide.

**Running the documentation processors**

The `/doc` directory in your cloned copy of the Zephyr project git repo has all the .rst source files, extra tools, and Makefile for generating a local copy of the Zephyr project's technical documentation. Assuming the local Zephyr project copy is in a folder `zephyr` in your home folder, here are the commands to generate the html content locally:

```
# On Linux/macOS
cd ~/zephyr/doc
# On Windows
cd %userprofile%\zephyr\doc
# Use cmake to configure a Ninja-based build system:
cmake -GNinja -B_build .
# Enter the build directory
```

(continues on next page)
cd _build

# To generate HTML output, run ninja on the generated build system:
ninja html
# If you modify or add .rst files, run ninja again:
ninja html

# To generate PDF output, run ninja on the generated build system:
ninja pdf

**Warning:** The documentation build system creates copies in the build directory of every .rst file used to generate the documentation, along with dependencies referenced by those .rst files.

This means that Sphinx warnings and errors refer to the copies, and not the version-controlled original files in Zephyr. Be careful to make sure you don’t accidentally edit the copy of the file in an error message, as these changes will not be saved.

Depending on your development system, it will take up to 15 minutes to collect and generate the HTML content. When done, you can view the HTML output with your browser started at doc/_build/html/index.html and if generated, the PDF file is available at doc/_build/latex/zephyr.pdf.

If you want to build the documentation from scratch just delete the contents of the build folder and run cmake and then ninja again.

**Note:** If you add or remove a file from the documentation, you need to re-run CMake.

On Unix platforms a convenience doc/Makefile can be used to build the documentation directly from there:

cd ~/zephyr/doc

# To generate HTML output
make html

# To generate PDF output
make pdf

**Filtering expected warnings**

There are some known issues with Sphinx/Breathe that generate Sphinx warnings even though the input is valid C code. While these issues are being considered for fixing we have created a Sphinx extension that allows to filter them out based on a set of regular expressions. The extension is named zephyr.warnings_filter and it is located at doc/_extensions/zephyr/warnings_filter.py. The warnings to be filtered out can be added to the doc/known-warnings.txt file.

The most common warning reported by Sphinx/Breathe is related to duplicate C declarations. This warning may be caused by different Sphinx/Breathe issues:

- Multiple declarations of the same object are not supported
- Different objects (e.g. a struct and a function) can not share the same name
- Nested elements (e.g. in a struct or union) can not share the same name
Developer-mode Document Building

When making and testing major changes to the documentation, we provide an option to temporarily stub-out the auto-generated Devicetree bindings documentation so the doc build process runs faster.

To enable this mode, set the following option when invoking cmake:

```
-DT_TURBO_MODE=1
```

or invoke make with the following target:

```
cd ~/zephyr
# To generate HTML output without detailed Kconfig
make html-fast
```

Viewing generated documentation locally

The generated HTML documentation can be hosted locally with python for viewing with a web browser:

```
$ python3 -m http.server -d _build/html
```

**Note:** WSL2 users may need to explicitly bind the address to `127.0.0.1` in order to be accessible from the host machine:

```
$ python3 -m http.server -d _build/html --bind 127.0.0.1
```

Linking external Doxygen projects against Zephyr

External projects that build upon Zephyr functionality and wish to refer to Zephyr documentation in Doxygen (through the use of @ref), can utilize the tag file exported at `zephyr.tag`

Once downloaded, the tag file can be used in a custom `doxygenfile.in` as follows:

```
TAGFILES = "*/path/to/zephyr.tag=https://docs.zephyrproject.org/latest/doxygen/html/"
```

For additional information refer to Doxygen External Documentation.

**Documentation Guidelines**

This page provides some simple guidelines for writing documentation using the reStructuredText (reST) markup language and Sphinx documentation generator.

**Documentation Generation**

As you write documentation, it can be helpful to see how it will look when rendered.

This page describes how to build the Zephyr documentation locally.

8.3 Dealing with external components
8.3.1 Contributing External Components

In some cases it is desirable to leverage existing, external source code in order to avoid re-implementing basic functionality or features that are readily available in other open source projects.

This section describes the circumstances under which external source code can be imported into Zephyr, and the process that governs the inclusion.

There are three main factors that will be considered during the inclusion process in order to determine whether it will be accepted. These will be described in the following sections.

Note that most of this page deals with external components that end up being compiled and linked into the final image, and programmed into the target hardware. For external tooling that is only used during compilation, code analysis, testing or simulation please refer to the Contributing External Tooling section at the end of the page.

Software License

Note: External source code licensed under the Apache-2.0 license is not subject to this section.

Integrating code into the Zephyr Project from other projects that use a license other than the Apache 2.0 license needs to be fully understood in context and approved by the Zephyr governing board, as described in the Zephyr project charter. The board will automatically reject licenses that have not been approved by the Open Source Initiative (OSI). See the Submission and review process section for more details.

By carefully reviewing potential contributions and also enforcing a Developer Certification of Origin (DCO) for contributed code, we ensure that the Zephyr community can develop products with the Zephyr Project without concerns over patent or copyright issues.

Merit

Just like with any other regular contribution, one that contains external code needs to be evaluated for merit. However, in the particular case of code that comes from an existing project, there are additional questions that must be answered in order to accept the contribution. More specifically, the following will be considered by the Technical Steering Committee and evaluated carefully before the external source code is accepted into the project:

- Is this the most optimal way to introduce the functionality to the project? Both the cost of implementing this internally and the one incurred in maintaining an externally developed codebase need to be evaluated.
- Is the external project being actively maintained? This is particularly important for source code that deals with security or cryptography.
- Have alternatives to the particular implementation proposed been considered? Are there other open source project that implement the same functionality?

Mode of integration

There are two ways of integrating external source code into the Zephyr Project, and careful consideration must be taken to choose the appropriate one for each particular case.
**Integration in the main tree**  
The first way to integrate external source code into the project is to simply import the source code files into the main zephyr repository. This automatically implies that the imported source code becomes part of the “mainline” codebase, which in turn requires that:

- The code is formatted according to the Zephyr *Coding Style*
- The code adheres to the project's *Coding Guidelines*
- The code is subject to the same checks and verification requirements as the rest of the code in the main tree, including static analysis
- All files contain an SPDX tag if not already present
- If the source is not Apache 2.0 licensed, an entry is added to the licensing page.

This mode of integration can be applicable to both small and large external codebases, but it is typically used more commonly with the former.

**Integration as a module**  
The second way of integrating external source code into the project is to import the whole or parts of the third-party open source project into a separate repository, and then include it under the form of a module. With this approach the code is considered as being developed externally, and thus it is not automatically subject to the requirements of the previous section.

**Integration in main manifest file (west.yaml)**  
Integrating external code into the main west.yaml manifest file is limited to code that is used by a Zephyr subsystem (libraries), by a platform, drivers (HAL) or tooling needed to test or build Zephyr components.

The integration of modules in this group is validated by the Zephyr project CI, and verified to be working with each Zephyr release.

Integrated modules will not be removed from the tree without a detailed migration plan.

**Integration as optional modules**  
Standalone or loose integration of modules/projects without any incoming dependencies shall be made optional and shall be kept standalone. Optional projects that provide value to users directly and through a Zephyr subsystem or platform shall be added to an optional manifest file that is filtered by default. (submanifests(optional).yml).

Such optional projects might include samples and tests in their own repositories.

There shall not be any direct dependency added in the Zephyr code tree (Git repository) and all sample or test code shall be maintained as part of the module.

**Note:** This is valid for all new optional modules. Existing optional modules with samples and test code in the Zephyr Git repository will be transitioned out over time.

**Integration as external modules**  
Similar to optional modules, but added to the Zephyr project as an entry in the documentation using a pre-defined template. This type of modules exists outside the Zephyr project manifest with documentation instructing users and developers how to integrate the functionality.

**Ongoing maintenance**

Regardless of the mode of integration, external source code that is integrated in Zephyr requires regular ongoing maintenance. The submitter of the proposal to integrate external source code
must therefore commit to maintain the integration of such code for the foreseeable future. This may require adding an entry in the `MAINTAINERS.yml` as part of the process.

**Submission and review process**

Before external source code can be included in the project, it must be reviewed and accepted by the Technical Steering Committee (TSC) and, in some cases, by the Zephyr governing board.

A request for external source code integration must be made by creating a new issue in the Zephyr project issue tracking system on GitHub with details about the source code and how it integrates into the project.

Follow the steps below to begin the submission process:

1. Make sure to read through the *Contributing External Components* section in detail, so that you are informed of the criteria used by the TSC and board in order to approve or reject a request
2. Use the *New External Source Code Issue* to open an issue
3. Fill out all required sections, making sure you provide enough detail for the TSC to assess the merit of the request. Optionally you can also create a Pull Request that demonstrates the integration of the external source code and link to it from the issue
4. Wait for feedback from the TSC, respond to any additional questions added as GitHub issue comments

If, after consideration by the TSC, the conclusion is that integrating external source code is the best solution, and the external source code is licensed under the Apache-2.0 license, the submission process is complete and the external source code can be integrated.

If, however, the external source code uses a license other than Apache-2.0, then these additional steps must be followed:

1. The TSC chair will forward the link to the GitHub issue created during the early submission process to the Zephyr governing board for further review
2. The Zephyr governing board has two weeks to review and ask questions:
   - If there are no objections, the matter is closed. Approval can be accelerated by unanimous approval of the board before the two weeks are up
   - If a governing board member raises an objection that cannot be resolved via email, the board will meet to discuss whether to override the TSC approval or identify other approaches that can resolve the objections
3. On approval of the Zephyr TSC and governing board the submission process is complete

The flowchart below shows an overview of the process:

**Contributing External Tooling**

This section deals exclusively with the inclusion of external tooling in the Zephyr project, where tooling is defined as software that assists the compilation, testing or simulation processes but in no case ends up being part of the code compiled and linked into the final image. “Inclusion” in this context means becoming part of the Zephyr default distribution either in the main tree directly under the `scripts/` folder or indirectly as a west project in the main `west.yml` manifest. Therefore, this section does not apply to 3rd-party tooling such as toolchains, simulators or others, which may still be referenced by the Zephyr build system or docs without being included in Zephyr.

Tooling components must be released under a license approved by the [Open Source Initiative (OSI)](https://osi.org/).
Just like with regular external components, tooling that is imported from another project can be integrated either in the main tree or as a west project. Note that in this case the corresponding west project will not be a module, because tooling does not make use of the Zephyr build system and does not need to be processed by it. Please see Modules vs west projects for additional information on the differences.

If the tool is integrated in the main tree it should be placed under the scripts/ folder. If the tool is integrated as a west project, then the project repository can be hosted outside the zephyrproject-rtos GitHub organization, provided that the project is made optional via the group-filter: field in the main west.yml manifest. More info on optional projects can be found in this section.

The TSC must approve every Pull Request that introduces a new external tooling component. This will be done on a case-by-case, individual analysis of the proposed addition by the TSC representatives.

### Additional considerations about the main manifest

In general, any additions or removals whatsoever to the projects: section of the main manifest file requires TSC approval. This includes, but is not limited to:

- Adding and removing groups and group filters
- Adding and removing projects
- Adding and removing import statements

### 8.3.2 Binary Blobs

In the context of an operating system that supports multiple architectures and many different IC families, some functionality may be unavailable without the help of executable code distributed in binary form. Binary blobs (or blobs for short) are files containing proprietary machine code or data in a binary format, e.g. without corresponding source code released under an OSI approved license.
Zephyr supports downloading and using third-party binary blobs via its built-in mechanisms, with some important caveats, described in the following sections. It is important to note that all the information in this section applies only to upstream (vanilla) Zephyr.

There are no limitations whatsoever (except perhaps license compatibility) in the support for binary blobs in forks or third-party distributions of Zephyr. In fact, Zephyr's build system supports arbitrary use cases related to blobs. This includes linking against libraries, flashing images to targets, etc. Users are therefore free to create Zephyr-based downstream software which uses binary blobs if they cannot meet the requirements described in this page.

Software license

Most binary blobs are distributed under proprietary licenses which vary significantly in nature and conditions. It is up to the vendor to specify the license as part of the blob submission process. Blob vendors may impose a click-through or other EULA-like workflow when users fetch and install blobs.

Hosting

Blobs must be hosted on the Internet and managed by third-party infrastructure. Two potential examples are Git repositories and web servers managed by individual hardware vendors. The Zephyr Project does not host binary blobs in its Git repositories or anywhere else.

Fetching blobs

Blobs are fetched from official third-party sources by the west blobs command.

The blobs themselves must be specified in the module.yml files included in separate Zephyr module repositories maintained by their respective vendors. This means that in order to include a reference to a binary blob to the upstream Zephyr distribution, a module repository must exist first or be created as part of the submission process.

Each blob which may be fetched must be individually identified in the corresponding module.yml file. A specification for a blob must contain:

- An abstract description of the blob itself
- Version information
- A reference to vendor-provided documentation
- The blob's type, which must be one of the allowed types
- A checksum for the blob, which west blobs checks after downloading. This is required for reproducibility and to allow bisecting issues as blobs change using Git and west
- License text applicable to the blob or a reference to such text, in SPDX format

See the corresponding section for a more formal definition of the fields.

The west blobs command can be used to list metadata of available blobs and to fetch blobs from user-selected modules.

The west blobs command only fetches and stores the binary blobs themselves. Any accompanying code, including interface header files for the blobs, must be present in the corresponding module repository.
Tainting

Inclusion of binary blobs will taint the Zephyr build. The definition of tainting originates in the Linux kernel and, in the context of Zephyr, a tainted image will be one that includes binary blobs in it.

Tainting will be communicated to the user in the following manners:

- One or more Kconfig options TAINT_BLOBS_* will be set to y
- The Zephyr build system, during its configuration phase, will issue a warning. It will be possible to disable the warning using Kconfig
- The west spdx command will include the tainted status in its output
- The kernel's default fatal error handler will also explicitly print out the kernel's tainted status

Allowed types

The following binary blob types are acceptable in Zephyr:

- Precompiled libraries: Hardware enablement libraries, distributed in precompiled binary form, typically for SoC peripherals. An example could be an enablement library for a wireless peripheral
- Firmware images: An image containing the executable code for a secondary processor or CPU. This can be full or partial (typically delta or patch data) and is generally copied into RAM or flash memory by the main CPU. An example could be the firmware for the core running a Bluetooth LE Controller
- Miscellaneous binary data files. An example could be pre-trained neural network model data

Hardware agnostic features provided via a proprietary library are not acceptable. For example, a proprietary and hardware agnostic TCP/IP stack distributed as a static archive would be rejected.

Note that just because a blob has an acceptable type does not imply that it will be unconditionally accepted by the project; any blob may be rejected for other reasons on a case by case basis (see library-specific requirements below). In case of disagreement, the TSC is the arbiter of whether a particular blob fits in one of the above types.

Precompiled library-specific requirements

This section contains additional requirements specific to precompiled library blobs.

Any person who wishes to submit a precompiled library must represent that it meets these requirements. The project may remove a blob from the upstream distribution if it is discovered that the blob fails to meet these requirements later on.

Interface header files  The precompiled library must be accompanied by one or more header files, distributed under a non-copyleft OSI approved license, that define the interface to the library.

Allowed dependencies  This section defines requirements related to external symbols that a library blob requires the build system to provide.
• The blob must not depend on Zephyr APIs directly. In other words, it must have been possible to build the binary without any Zephyr source code present at all. This is required for loose coupling and maintainability, since Zephyr APIs may change and such blobs cannot be modified by all project maintainers.

• Instead, if the code in the precompiled library requires functionality provided by Zephyr (or an RTOS in general), an implementation of an OS abstraction layer (aka porting layer) can be provided alongside the library. The implementation of this OS abstraction layer must be in source code form, released under an OSI approved license and documented using Doxygen.

**Toolchain requirements** Precompiled library blobs must be in a data format which is compatible with and can be linked by a toolchain supported by the Zephyr Project. This is required for maintainability and usability. Use of such libraries may require special compiler and/or linker flags, however. For example, a porting layer may require special flags, or a static archive may require use of specific linker flags.

**Limited scope** Allowing arbitrary library blobs carries a risk of degrading the degree to which the upstream Zephyr software distribution is open source. As an extreme example, a target with a zephyr kernel clock driver that is just a porting layer around a library blob would not be bootable with open source software.

To mitigate this risk, the scope of upstream library blobs is limited. The project maintainers define an open source test suite that an upstream target must be able to pass using only open source software included in the mainline distribution and its modules. The open source test suite currently consists of:

- samples/philosophers
- tests/kernel

The scope of this test suite may grow over time. The goal is to specify tests for a minimal feature set which must be supported via open source software for any target with upstream Zephyr support.

At the discretion of the release team, the project may remove support for a hardware target if it cannot pass this test suite.

**Support and maintenance**

The Zephyr Project is not expected to be responsible for the maintenance and support of contributed binary blobs. As a consequence, at the discretion of the Zephyr Project release team, and on a case-by-case basis:

- GitHub issues reported on the zephyr repository tracker that require use of blobs to reproduce may not be treated as bugs

- Such issues may be closed as out of scope of the Zephyr project

This does not imply that issues which require blobs to reproduce will be closed without investigation. For example, the issue may be exposing a bug in a Zephyr code path that is difficult or impossible to trigger without a blob. Project maintainers may accept and attempt to resolve such issues.

However, some flexibility is required because project maintainers may not be able to determine if a given issue is due to a bug in Zephyr or the blob itself, may be unable to reproduce the bug due to lack of hardware, etc.

Blobs must have designated maintainers that must be responsive to issue reports from users and provide updates to the blobs to address issues. At the discretion of the Zephyr Project release team, module revisions referencing blobs may be removed from zephyr/west.yml at any time.
due to lack of responsiveness or support from their maintainers. This is required to maintain project control over bit-rot, security issues, etc. 

The submitter of the proposal to integrate a binary blob must commit to maintaining the integration of such blob for the foreseeable future.

Regarding Continuous Integration, binary blobs will not be fetched in the project’s CI infrastructure that builds and optionally executes tests and samples to prevent regressions and issues from entering the codebase. This includes both CI ran when a new GitHub Pull Request is opened as well as any other regularly scheduled execution of the CI infrastructure.

Submission and review process

For references to binary blobs to be included in the project, they must be reviewed and accepted by the Technical Steering Committee (TSC). This process is only required for new binary blobs, updates to binary blobs follow the module update procedure.

A request for integration with binary blobs must be made by creating a new issue in the Zephyr project issue tracking system on GitHub with details about the blobs and the functionality they provide to the project.

Follow the steps below to begin the submission process:

1. Make sure to read through the Binary Blobs section in detail, so that you are informed of the criteria used by the TSC in order to approve or reject a request
2. Use the New Binary Blobs Issue to open an issue
3. Fill out all required sections, making sure you provide enough detail for the TSC to assess the merit of the request. Additionally you must also create a Pull Request that demonstrates the integration of the binary blobs and then link to it from the issue
4. Wait for feedback from the TSC, respond to any additional questions added as GitHub issue comments

If, after consideration by the TSC, the submission of the binary blob(s) is approved, the submission process is complete and the binary blob(s) can be integrated.

Contributing External Components

Basic functionality or features that would make useful addition to Zephyr might be readily available in other open source projects, and it is recommended and encouraged to reuse such code. This page describes in more details when and how to import external source code into Zephyr.

Contributing External Tooling

Similarly, external tooling used during compilation, code analysis, testing or simulation, can be beneficial and is covered in this section.

Binary Blobs

As some functionality might only be made available with the help of executable code distributed in binary form, this page describes the process and guidelines for contributing binary blobs to the project.

8.4 Zephyr Contributor Badge

When your first contribution to the Zephyr project gets merged, you’ll become eligible to claim your Zephyr Contributor Badge. This digital badge can be displayed on your website, blog, social media profile, etc. It will allow you to showcase your involvement in the Zephyr project and help raise its awareness.

You may apply for your Contributor Badge by filling out the Zephyr Contributor Badge form.
8.5 Need help along the way?

If you have questions related to the contribution process, the Zephyr community is here to help. You may join our Discord channel or use the Developer Mailing List.
Chapter 9

Project and Governance

9.1 TSC Project Roles

9.1.1 Main Roles

TSC projects generally will involve Maintainers, Collaborators, and Contributors:

Maintainer: lead Collaborators on an area identified by the TSC (e.g. Architecture, code sub-systems, etc.). Maintainers shall also serve as the area's representative on the TSC as needed. Maintainers may become voting members of the TSC under the guidelines stated in the project Charter.

Collaborator: A highly involved Contributor in one or more areas. May become a Maintainer with approval of existing TSC voting members.

Contributor: anyone in the community that contributes code or documentation to the project. Contributors may become Collaborators by approval of the existing Collaborators and Maintainers of the particular code base areas or subsystems.

Contributor

A Contributor is a developer who wishes to contribute to the project, at any level. Contributors are granted the following rights and responsibilities:

- Right to contribute code, documentation, translations, artwork, etc.
- Right to report defects (bugs) and suggestions for enhancement.
- Right to participate in the process of reviewing contributions by others.
- Right to initiate and participate in discussions in any communication methods.
- Right to approach any member of the community with matters they believe to be important.
- Right to participate in the feature development process.
- Responsibility to abide by decisions, once made. They are welcome to provide new, relevant information to reopen decisions.
- Responsibility for issues and bugs introduced by one's own contributions.
- Responsibility to respect the rules of the community.
- Responsibility to provide constructive advice whenever participating in discussions and in the review of contributions.
• Responsibility to follow the project’s code of conduct (https://github.com/zephyrproject-rtos/zephyr/blob/main/CODE_OF_CONDUCT.md)

Contributors are initially only given Read access to the Zephyr GitHub repository. Specifically, at the Read access level, Contributors are not allowed to assign reviewers to their own pull requests. An automated process will assign reviewers. You may also share the pull request on the Zephyr devel mailing list or on the Zephyr Discord Server.

Contributors who show dedication and skill are granted the Triage permission level to the Zephyr GitHub repository.

You may nominate yourself, or another GitHub user, for promotion to the Triage permission level by creating a GitHub issue, using the nomination template.

Contributors granted the Triage permission level are permitted to add reviewers to a pull request and can be added as a reviewer by other GitHub users. Contributor change requests or approval on pull requests are not counted with respect to accepting and merging a pull request. However, Contributors comments and requested changes should still be considered by the pull request author.

**Collaborator**

A **Collaborator** is a Contributor who is also responsible for the maintenance of Zephyr source code. Their opinions weigh more when decisions are made, in a fully meritocratic fashion.

Collaborators have the following rights and responsibilities, in addition to those listed for Contributors:

• Right to set goals for the short and medium terms for the project being maintained, alongside the Maintainer.
• Responsibility to participate in the feature development process.
• Responsibility to review relevant code changes within reasonable time.
• Responsibility to ensure the quality of the code to expected levels.
• Responsibility to participate in community discussions.
• Responsibility to mentor new contributors when appropriate
• Responsibility to participate in the quality verification and release process, when those happen.

Contributors are promoted to the Collaborator role by adding the GitHub user name to one or more collaborators sections of the MAINTAINERS File in the Zephyr repository.

Collaborator change requests on pull requests should be addressed by the original submitter. In cases where the changes requested do not follow the expectations and the guidelines of the project or in cases of disagreement, it is the responsibility of the assignee to advance the review process and resolve any disagreements.

Collaborator approval of pull requests are counted toward the minimum required approvals needed to merge a PR. Other criteria for merging may apply.

**Maintainer**

A **Maintainer** is a Collaborator who is also responsible for knowing, directing and anticipating the needs of a given zephyr source code area.

Maintainers have the following rights and responsibilities, in addition to those listed for Contributors and Collaborators:

• Right to set the overall architecture of the relevant subsystems or areas of involvement.
• Right to make decisions in the relevant subsystems or areas of involvement, in conjunction with the collaborators and submitters. See PR Technical Escalation.
• Responsibility to convey the direction of the relevant subsystem or areas to the TSC
• Responsibility to ensure all contributions of the project have been reviewed within reasonable time.
• Responsibility to enforce the code of conduct.
• Responsibility to triage static analysis issues in their code area. See Static Code Analysis.
Contributors or Collaborators are promoted to the Maintainer role by adding the GitHub user name to one or more maintainers sections of the MAINTAINERS File in the Zephyr repository. Maintainer approval of pull requests are counted toward the minimum required approvals needed to merge a PR. Other criteria for merging may apply.

9.1.2 Role Retirement

• Individuals elected to the following Project roles, including, Maintainer, Release Engineering Team member, Release Manager, but are no longer engaged in the project as described by the rights and responsibilities of that role, may be requested by the TSC to retire from the role they are elected.
• Such a request needs to be raised as a motion in the TSC and be approved by the TSC voting members. By approval of the TSC the individual is considered to be retired from the role they have been elected.
• The above applies to elected TSC Project roles that may be defined in addition.

9.1.3 Teams and Supporting Activities

Assignee

An Assignee is one of the maintainers of a subsystem or code being changed. Assignees are set either automatically based on the code being changed or set by the other Maintainers, the Release Engineering team can set an assignee when the latter is not possible.
• Right to dismiss stale and unrelated reviews or reviews not following expectations from reviewers and seek reviews from additional maintainers, developers and contributors
• Right to block pull requests from being merged until issues or changes requested are addressed
• Responsibility to re-assign a pull request if they are the original submitter of the code
• Responsibility to drive the pull request to a mergeable state
• Solicit approvals from maintainers of the subsystems affected
• Responsibility to drive the PR Technical Escalation process

Static Analysis Audit Team

The Static Analysis Audit team works closely with the release engineering team to ensure that static analysis defects opened during a release cycle are properly addressed. The team has the following rights and responsibilities:
• Right to revert any triage in a static analysis tool (e.g: Coverity) that does not follow the project expectations.
• Responsibility to inform code owners about improper classifications.
• Responsibility to alert TSC if any issues are not adequately addressed by the responsible code owners.

Joining the Static Analysis Audit team
• Contributors highly involved in the project with some expertise in static analysis.

Release Engineering Team

A team of active Maintainers involved in multiple areas.
• The members of the Release Engineering team are expected to fill the Release Manager role based on a defined cadence and selection process.
• The cadence and selection process are defined by the Release Engineering team and are approved by the TSC.
• The team reports directly into the TSC.

Release Engineering team has the following rights and responsibilities:
• Right to merge code changes to the zephyr tree following the project rules.
• Right to revert any changes that have broken the code base
• Right to close any stale changes after <N> months of no activity
• Responsibility to take directions from the TSC and follow them.
• Responsibility to coordinate code merges with maintainers.
• Responsibility to merge all contributions regardless of their origin and area if they have been approved by the respective maintainers and follow the merge criteria of a change.
• Responsibility to keep the Zephyr code base in a working and passing state (as per CI)

Joining the Release Engineering team
• Maintainers highly involved in the project may be nominated by a TSC voting member to join the Release Engineering team. Nominees may become members of the team by approval of the existing TSC voting members.
• To ensure a functional Release Engineering team the TSC shall periodically review the team’s followed processes, the appropriate size, and the membership composition (ensure, for example, that team members are geographically distributed across multiple locations and time-zones).

Release Manager

A Maintainer responsible for driving a specific release to completion following the milestones and the roadmap of the project for this specific release.
• TSC has to approve a release manager.

A Release Manager is a member of the Release Engineering team and has the rights and responsibilities of that team in addition to the following:
• Right to manage and coordinate all code merges after the code freeze milestone (M3, see program management overview.)
• Responsibility to drive and coordinate the triaging process for the release
• Responsibility to create the release notes of the release
• Responsibility to notify all stakeholders of the project, including the community at large about the status of the release in a timely manner.
• Responsibility to coordinate with QA and validation and verify changes either directly or through QA before major changes and major milestones.

Roles / Permissions

Table 1: Project Roles vs GitHub Permissions

<table>
<thead>
<tr>
<th>Role</th>
<th>Admin Merge Rights</th>
<th>Member</th>
<th>Owner</th>
<th>Collaborator</th>
</tr>
</thead>
<tbody>
<tr>
<td>Main Roles</td>
<td></td>
<td></td>
<td></td>
<td>x</td>
</tr>
<tr>
<td>Contributor</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Collaborator</td>
<td></td>
<td></td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>Maintainer</td>
<td></td>
<td></td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>Supportive Roles</td>
<td>QA/Validation</td>
<td>x</td>
<td></td>
<td>x</td>
</tr>
<tr>
<td>DevOps</td>
<td></td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
<tr>
<td>System Admin</td>
<td></td>
<td>x</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Release Engineering</td>
<td></td>
<td>x</td>
<td>x</td>
<td></td>
</tr>
</tbody>
</table>

9.1.4 MAINTAINERS File

Generic guidelines for deciding and filling in the Maintainers’ list

• The MAINTAINERS.yml file shall replace the CODEOWNERS file and will be used for both setting assignees and reviewers.
• We should keep the granularity of code maintainership at a manageable level
• We should be looking for maintainers for areas of code that are orphaned (i.e. without an explicit maintainer)
  – Un-maintained areas should be indicated clearly in the MAINTAINERS file
• All submitted pull requests should have an assignee
• We Introduce an area/subsystem hierarchy to address the above point
  – Parent-area maintainer should be acting as default substitute/fallback assignee for un-maintained sub-areas
  – Area maintainer gets precedence over parent-area maintainer
• Pull requests may be re-assigned if this is needed or more appropriate
  – Re-assigned by original assignee
• In general, updates to the MAINTAINERS file should be in a standalone commit alongside other changes introducing new files and directories to the tree.
• Major changes to the file, including the addition of new areas with new maintainers should come in as standalone pull requests and require TSC review.
• If additional review by the TSC is required, the maintainers of the file should send the requested changes to the TSC and give members of the TSC two (2) days to object to any of the changes to maintainership of areas or the addition of new maintainers or areas.
• Path, collaborator and name changes do not require a review by the TSC.
• Addition of new areas without a maintainer do not require review by the TSC.
• The MAINTAINERS file itself shall have a maintainer

9.1. TSC Project Roles
- Architectures, core components, sub-systems, samples, tests
  - Each area shall have an explicit maintainer
- Boards (incl relevant samples, tests), SoCs (incl DTS) * May have a maintainer, shall have a higher-level platform maintainer
- Drivers
  - Shall have a driver-area (and API) maintainer
  - Could have individual driver implementation maintainers but preferably collaborator/contributors
  - In the above case, platform-specific PRs may be re-assigned to respective collaborator/contributor of driver implementation

9.1.5 Release Activity

Merge Criteria

- Minimal of 2 approvals, including an approval by the designated assignee.
- Pull requests should be reviewed by at least a maintainer or collaborator of each affected area; Unless the changes to a given area are considered trivial enough, in which case approvals by other affected subsystems maintainers/collaborators would suffice.
- Four eye principle on the organisation level. We already require at least 2 approvals (basic four eye principle), however, such reviews and approvals might be unintentionally biased in the case where the submitter is from the same organisation as the approvers. To allow
for project wide review and approvals, the merge criteria is extended with the guidelines below:

- Changes or additions to common and shared code shall have approvals from different organisations (at least one approval from an organisation different than the submitters'). Common and shared code is defined as anything that does not fall under soc, boards and drivers/*/*/.

- Changes or additions to hardware support (driver, SoC, boards) shall at least have the merger be from a different organisation. This applies only to implementation of an API supporting vendor specific hardware and not the APIs.

- Release engineers may make exceptions for areas with contributions primarily coming from one organisation and where reviews from other organisations are not possible, however, merges shall be completed by a person from a different organisation. In such cases, the minimum review period of at least 2 days shall be strictly followed to allow for additional reviews.

- Release engineers shall not merge code changes originating and reviewed only by their own organisation. To be able to merge such changes, at least one review shall be from a different organisation.

- A minimum review period of 2 business days, 4 hours for trivial changes (see Give reviewers time to review before code merge).

- Hotfixes can be merged at any time after CI has passed and are excluded from most of the conditions listed above.

- All required checks are passing:
  
  - Codeowners
  - Device Tree
  - Documentation
  - Gittlint
  - Identity/Emails
  - Kconfig
  - License checks
  - Checkpatch (Coding Style)
  - Pylint
  - Integration Tests (Via twister) on emulation/simulation platforms
  - Simulated Bluetooth Tests

- Planned
  
  - Footprint
  - Code coverage
  - Coding Guidelines
  - Static Analysis (Coverity)
  - Documentation coverage (APIs)

## 9.2 Release Process

The Zephyr project releases on a time-based cycle, rather than a feature-driven one. Zephyr releases represent an aggregation of the work of many contributors, companies, and individuals
from the community.

A time-based release process enables the Zephyr project to provide users with a balance of the latest technologies and features and excellent overall quality. A roughly 4-month release cycle allows the project to coordinate development of the features that have actually been implemented, allowing the project to maintain the quality of the overall release without delays because of one or two features that are not ready yet.

The Zephyr release model was loosely based on the Linux kernel model:

- Release tagging procedure:
  - linear mode on main branch,
  - release branches for maintenance after release tagging.
- Each release period will consist of a development phase followed by a stabilization phase. Release candidates will be tagged during the stabilization phase. During the stabilization phase, only stabilization changes such as bug fixes and documentation will be merged unless granted a special exemption by the Technical Steering Committee.
  - Development phase: all changes are considered and merged, subject to approval from the respective maintainers.
  - Stabilization phase: the release manager creates a vN-rc1 tag and the tree enters the stabilization phase
  - CI sees the tag, builds and runs tests; Test teams analyse the report from the build and test run and give an ACK/NAK to the build
  - The release owner, with test teams and any other needed input, determines if the release candidate is a go for release
  - If it is a go for a release, the release owner lays a tag release vN at the same point

![Release Cycle Diagram](image-url)

**Fig. 1: Release Cycle**

**Note:** The milestones for the current major version can be found on the [Official GitHub Wiki](https://github.com/zephyrproject/zephyr/wiki). Information on previous releases can be found [here](https://zephyrproject.org/releases/).

### 9.2.1 Development Phase

A relatively straightforward discipline is followed with regard to the merging of patches for each release. At the beginning of each development cycle, the main branch is said to be open for development. At that time, code which is deemed to be sufficiently stable (and which is accepted by the maintainers and the wide community) is merged into the mainline tree. The bulk of changes for a new development cycle (and all of the major changes) will be merged during this time.

The development phase lasts for approximately three months. At the end of this time, the release owner will declare that the development phase is over and releases the first of the release candidates. For the codebase release which is destined to be 3.1.0, for example, the release which
happens at the end of the development phase will be called 3.1.0-rc1. The -rc1 release is the signal that the time to merge new features has passed, and that the time to stabilize the next release of the code base has begun.

9.2.2 Stabilization Phase

Over the next weeks, only patches which fix problems should be submitted to the mainline. On occasion, a more significant change will be allowed, but such occasions are rare and require a TSC approval (Change Control Board). As a general rule, if you miss submitting your code during the development phase for a given feature, the best thing to do is to wait for the next development cycle. (An occasional exception is made for drivers for previously unsupported hardware; if they do not touch any other in-tree code, they cannot cause regressions and should be safe to add at any time).

As fixes make their way into the mainline, the patch rate will slow over time. The mainline release owner releases new -rc drops once or twice a week; a normal series will get up to somewhere between -rc4 and -rc6 before the code base is considered to be sufficiently stable and the release criteria have been achieved at which point the final 3.1.0 release is made.

At that point, the whole process starts over again.

9.2.3 Release Quality Criteria

The current backlog of prioritized bugs shall also be used as a quality metric to gate the final release. The following counts shall be used:

<table>
<thead>
<tr>
<th></th>
<th>High</th>
<th>Medium</th>
<th>Low</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>0</td>
<td>&lt;20</td>
<td>&lt;50</td>
</tr>
</tbody>
</table>

**Note:** The “low” bug count target of <50 will be a phased approach starting with 150 for release 2.4.0, 100 for release 2.5.0, and 50 for release 2.6.0

The final release must not contain any static analysis high-critical issues that can potentially compromise the functionality, security, or reliability of our software. High-critical issues represent vulnerabilities that, if left unresolved, could have severe consequences.
9.2.4 Release Milestones

Table 3: Release Milestones

<table>
<thead>
<tr>
<th>Timeline</th>
<th>Checkpoint</th>
<th>Description</th>
<th>Owner</th>
</tr>
</thead>
<tbody>
<tr>
<td>T-5M</td>
<td>Planning</td>
<td>Finalize dates for release, Assign release owner and agree on project wide goals for this release.</td>
<td>TSC</td>
</tr>
<tr>
<td>T-7W</td>
<td>Review target milestones</td>
<td>Finalize target milestones for features in flight.</td>
<td>Release Engineering</td>
</tr>
<tr>
<td>T-4W</td>
<td>Release Announcement</td>
<td>Release owner announces feature freeze and timeline for release.</td>
<td>Release Manager</td>
</tr>
<tr>
<td>T-3W</td>
<td>Feature Freeze (RC1)</td>
<td>No new features, ONLY stabilization and cosmetic changes, bug and doc fixes are allowed.</td>
<td>Release Engineering</td>
</tr>
<tr>
<td>T-2W</td>
<td>2nd Release Candidate</td>
<td>No new features, ONLY stabilization and cosmetic changes, bug and doc fixes are allowed.</td>
<td>Release Manager</td>
</tr>
<tr>
<td>T-1W</td>
<td>Hard Freeze (RC3)</td>
<td>Only blocker bug fixes, documentation and changes to release notes are allowed. Release notes need to be complete by this checkpoint. Release Criteria is met.</td>
<td>Release Manager</td>
</tr>
<tr>
<td>T-0W</td>
<td>Release</td>
<td></td>
<td>Release Manager</td>
</tr>
</tbody>
</table>

9.2.5 Releases

The following syntax should be used for releases and tags in Git:

- Release [Major].[Minor].[Patch Level]
- Release Candidate [Major].[Minor].[Patch Level]-rc[RC Number]
- Tagging:
  - v[Major].[Minor].[Patch Level]-rc[RC Number]
  - v[Major].[Minor].[Patch Level]
  - v[Major].[Minor].99 - A tag applied to main branch to signify that work on v[Major].[Minor+1] has started. For example, v1.7.99 will be tagged at the start of v1.8 process. The tag corresponds to VERSION_MAJOR/VERSION_MINOR/PATCHLEVEL macros as defined for a work-in-progress main branch version. Presence of this tag allows generation of sensible output for “git describe” on main branch, as typically used for automated builds and CI tools.

Long Term Support (LTS)

Long-term support releases are designed to be supported and maintained for an extended period and is the recommended release for products and the auditable branch used for certification.

An LTS release is defined as:

- Product focused
- **Extended Stabilisation period**: Allow for more testing and bug fixing
- Stable APIs
- Quality Driven Process
• **Long Term**: Maintained for an extended period of time (at least 2.5 years) overlapping previous LTS release for at least half a year.

**Product Focused**  Zephyr LTS is the recommended release for product makers with an extended support and maintenance which includes general stability and bug fixes, security fixes. An LTS includes both mature and new features. API and feature maturity is documented and tracked. The footprint and scope of mature and stable APIs expands as we move from one LTS to the next giving users access to bleeding edge features and new hardware while keeping a stable foundation that evolves over time.

**Extended Stabilisation Period**  Zephyr LTS development cycle differs from regular releases and has an extended stabilization period. Feature freeze of regular releases happens 3-4 weeks before the scheduled release date. The stabilization period for LTS is extended by 3 weeks with the feature freeze occurring 6-7 weeks before the anticipated release date. The time between code freeze and release date is extended in this case.

**Stable APIs**  Zephyr LTS provides a stable and long-lived foundation for developing products. To guarantee stability of the APIs and the implementation of such APIs it is required that any release software that makes the core of the OS went through the Zephyr API lifecycle and stabilized over at least 2 releases. This guarantees that we release many of the highlighted and core features with mature and well-established implementations with stable APIs that are supported during the lifetime of the release LTS.

• **API Freeze (LTS - 2)**
  – All stable APIs need to be frozen 2 releases before an LTS. APIs can be extended with additional features, but the core implementation is not modified. This is valid for the following subsystems for example:
    * Device Drivers (i2c.h, spi.h)...
    * Kernel (k_*):
    * OS services (logging, debugging, ..)
    * DTS: API and bindings stability
    * Kconfig
New APIs for experimental features can be added at any time as long as they are standalone and documented as experimental or unstable features/APIs.

- Feature Freeze (LTS - 1) - No new features or overhaul/restructuring of code covering major LTS features.
  - Kernel + Base OS
  - Additional advertised LTS features
  - Auxiliary features on top of and/or extending the base OS and advertised LTS features can be added at any time and should be marked as experimental if applicable

**Quality Driven Process** The Zephyr project follows industry standards and processes with the goal of providing a quality oriented releases. This is achieved by providing the following products to track progress, integrity and quality of the software components provided by the project:

- Compliance with published coding guidelines, style guides and naming conventions and documentation of deviations.
- Static analysis reports
  - Regular static analysis on the complete tree using available commercial and open-source tools, and documentation of deviations and false positives.
- Documented components and APIs
- Requirements Catalog
- Verification Plans
- Verification Reports
- Coverage Reports
- Requirements Traceability Matrix (RTM)
- SPDX License Reports

Each release is created with the above products to document the quality and the state of the software when it was released.

**Long Term Support and Maintenance** A Zephyr LTS release is published every 2 years and is branched and maintained independently from the main tree for at least 2.5 years after it was released. Support and maintenance for an LTS release stops at least half a year after the following LTS release is published.

Changes and fixes flow in both directions. However, changes from main branch to an LTS branch will be limited to fixes that apply to both branches and for existing features only.

All fixes for an LTS branch that apply to the mainline tree shall be submitted to mainline tree as well.
Auditble Code Base

An auditable code base is to be established from a defined subset of Zephyr OS features and will be limited in scope. The LTS, development tree, and the auditable code bases shall be kept in sync after the audit branch is created, but with a more rigorous process in place for adding new features into the audit branch used for certification.

This process will be applied before new features move into the auditable code base.

The initial and subsequent certification targets will be decided by the Zephyr project governing board.

Processes to achieve selected certification will be determined by the Security and Safety Working Groups and coordinated with the TSC.

9.2.6 Release Procedure

This section documents the Release manager responsibilities so that it serves as a knowledge repository for Release managers.

Release Checklist

Each release has a GitHub issue associated with it that contains the full checklist. After a release is complete, a checklist for the next release is created.

Tagging

The final release and each release candidate shall be tagged using the following steps:

Note: Tagging needs to be done via explicit git commands and not via GitHub’s release interface. The GitHub release interface does not generate annotated tags (it generates ‘lightweight’ tags regardless of release or pre-release). You should also upload your gpg public key to your GitHub account, since the instructions below involve creating signed tags. However, if you do not have a gpg public key you can opt to remove the -s option from the commands below.

Release Candidate

Note: This section uses tagging 1.11.0-rc1 as an example, replace with the appropriate release candidate version.

1. Update the version variables in the VERSION file located in the root of the Git repository to match the version for this release candidate. The EXTRAVERSION variable is used to identify the rc[RC Number] value for this candidate:

\[
\text{EXTRAVERSION} = \text{rc1}
\]

2. Post a PR with the updated VERSION file using release: Zephyr 1.11.0-rc1 as the commit subject. Merge the PR after successful CI.

3. Tag and push the version, using an annotated tag:

\[
\text{git pull} \\
\text{git tag -s -m "Zephyr 1.11.0-rc1" v1.11.0-rc1} \\
\text{git push git@github.com:zephyrproject-rtos/zephyr.git v1.11.0-rc1}
\]
4. Send an email to the mailing lists (announce and devel) with a link to the release

Final Release

**Note:** This section uses tagging 1.11.0 as an example, replace with the appropriate final release version.

When all final release criteria has been met and the final release notes have been approved and merged into the repository, the final release version will be set and repository tagged using the following procedure:

1. Update the version variables in the `VERSION` file located in the root of the Git repository. Set `EXTRAVERSION` variable to an empty string to indicate final release:

   ```
   EXTRAVERSION =
   ```

2. Post a PR with the updated `VERSION` file using release: Zephyr 1.11.0 as the commit subject. Merge the PR after successful CI.

3. Tag and push the version, using two annotated tags:

   ```
   $ git pull
   $ git tag -s -m "Zephyr 1.11.0" v1.11.0
   $ git push git@github.com:zephyrproject-rtos/zephyr.git v1.11.0
   ```

4. Find the new v1.11.0 tag at the top of the releases page and edit the release with the Edit tag button with the following:

   - Copy the overview of `docs/releases/release-notes-1.11.rst` into the release notes textbox and link to the full release notes file on docs.zephyrproject.org.

5. Send an email to the mailing lists (announce and devel) with a link to the release

### 9.3 Feature Tracking

For feature tracking we use Github labels to classify new features and enhancements. The following is the description of each category:

**Enhancement**  
Changes to existing features that are not considered a bug and would not block a release. This is an incremental enhancement to a feature that already exists in Zephyr.

**Feature request**  
A request for the implementation or inclusion of a new unit of functionality that is not part of any release plans yet, that has not been vetted, and needs further discussion and details.

**Feature**  
A committed and planned unit of functionality with a detailed design and implementation proposal and an owner. Features must go through an RFC process and must be vetted and discussed in the TSC before a target milestone is set.

**Hardware Support**  
A request or plan to port an existing feature or enhancement to a particular hardware platform. This ranges from porting Zephyr itself to a new architecture, SoC or board to adding an implementation of a peripheral driver API for an existing hardware platform.

**Meta**  
A label to group other GitHub issues that are part of a single feature or unit of work.

The following workflow should be used to process features:
This is the formal way for asking for a new feature in Zephyr and indicating its importance to the project. Often, the requester may have a readiness and willingness to drive implementation of the feature in an upcoming release, and should assign the request to themselves. If not though, an owner will be assigned after evaluation by the TSC. A feature request can also have a companion RFC with more details on the feature and a proposed design or implementation.

- Label new features requests as `feature-request`
- The TSC discusses new `feature-request` items regularly and triages them. Items are examined for similarity with existing features, how they fit with the project goals and other timeline considerations. The priority is determined as follows:
  - High = Next milestone
  - Medium = As soon as possible
  - Low = Best effort
- After the initial discussion and triaging, the label is moved from `feature-request` to `feature` with the target milestone and an assignee.

All items marked as `feature-request` are non-binding and those without an assignee are open for grabs, meaning that they can be picked up and implemented by any project member or the community. You should contact an assigned owner if you'd like to discuss or contribute to that feature's implementation.

### 9.3.1 Roadmap and Release Plans

Project roadmaps and release plans are both important tools for the project, but they have very different purposes and should not be confused. A project roadmap communicates the high-level overview of a project's strategy, while a release plan is a tactical document designed to capture and track the features planned for upcoming releases.

- The project roadmap communicates the why; a release plan details the what
- A release plan spans only a few months; a product roadmap might cover a year or more

#### Project Roadmap

The project roadmap should serve as a high-level, visual summary of the project’s strategic objectives and expectations.

If built properly, the roadmap can be a valuable tool for several reasons. It can help the project present its plan in a compelling way to existing and new stakeholders, to help recruit new members and it can be a helpful resource the team and community can refer to throughout the project's development, to ensure they are still executing according to plan.

As such, the roadmap should contain only strategic-level details, major project themes, epics, and goals.

#### Release Plans

The release plan comes into play when the project roadmap's high-level strategy is translated into an actionable plan built on specific features, enhancements, and fixes that need to go into a specific release or milestone.

The release plan communicates those features and enhancements slated for your project' next release (or the next few releases). So it acts as more of a project plan, breaking the big ideas down into smaller projects the community and main stakeholders of the project can make progress on.
Items labeled as features are short or long term release items that shall have an assignee and a milestone set.

## 9.4 Code Flow and Branches

### 9.4.1 Introduction

The zephyr Git repository has three types of branches:

- **main**
  - Which contains the latest state of development

- **collab-***
  - Collaboration branches that are used for shared development of new features to be introduced into the main branch when ready. Creating a new collaboration branch requires a justification and TSC approval. Collaboration branches shall be based off the main branch and any changes developed in the collab branch shall target the main development branch. For released versions of Zephyr, the introduction of fixes and new features, if approved by the TSC, shall be done using backport pull requests.

- **vx.y-branch**
  - Branches which track maintenance releases based on a major release

Development in collaboration branches before features go to mainline allows teams to work independently on a subsystem or a feature, improves efficiency and turnaround time, and encourages collaboration and streamlines communication between developers.

Changes submitted to a collaboration branch can evolve and improve incrementally in a branch, before they are submitted to the mainline tree for final integration.

By dedicating an isolated branch to complex features, it's possible to initiate in-depth discussions around new additions before integrating them into the official project.

Collaboration branches are ephemeral and shall be removed once the collaboration work has been completed. When a branch is requested, the proposal should include the following:

- Define exit criteria for merging the collaboration branch changes back into the main branch.
- Define a timeline for the expected life cycle of the branch. It is recommended to select a Zephyr release to set the timeline. Extensions to this timeline requires TSC approval.

### 9.4.2 Roles and Responsibilities

Collaboration branch owners have the following responsibilities:

- Use the infrastructure and tools provided by the project (GitHub, Git)
- All changes to collaboration branches shall come in form of github pull requests.
- Force pushing a collaboration branch is only allowed when rebasing against the main branch.
- Review changes coming from team members and request review from branch owners when submitting changes.
- Keep the branch in sync with upstream and update on a regular basis.
- Push changes frequently to upstream using the following methods:
  - GitHub pull requests: for example, when reviews have not been done in the local branch (one-man branch).
– Merge requests: When a set of changes has been done in a local branch and has been reviewed and tested in a collaboration branch.

9.5 Modifying Contributions made by other developers

9.5.1 Scenarios

Zephyr contributors and collaborators are encouraged to assist as reviewers in pull requests, so that patches may be approved and merged to Zephyr’s main branch as part of the original pull requests. The authors of the pull requests are responsible for amending their original commits following the review process.

There are occasions, however, when a contributor might need to modify patches included in pull requests that are submitted by other Zephyr contributors. For instance, this is the case when:

• a developer cherry-picks commits submitted by other contributors into their own pull requests in order to:
  – integrate useful content which is part of a stale pull request, or
  – get content merged to the project’s main branch as part of a larger patch

• a developer pushes to a branch or pull request opened by another contributor in order to:
  – assist in updating pull requests in order to get the patches merged to the project’s main branch
  – drive stale pull requests to completion so they can be merged

9.5.2 Accepted policies

A developer who intends to cherry-pick and potentially modify patches sent by another contributor shall:

• clarify in their pull request the reason for cherry-picking the patches, instead of assisting in getting the patches merged in their original pull request, and

• invite the original author of the patches to their pull request review.

A developer who intends to force-push to a branch or pull request of another Zephyr contributor shall clarify in the pull request the reason for pushing and for modifying the existing patches (e.g. stating that it is done to drive the pull request review to completion, when the pull request author is not able to do so).

Note: Developers should try to limit the above practice to pull requests identified as stale. Read about how to identify pull requests as stale in development processes and tools

If the original patches are substantially modified, the developer can either:

• (preferably) reach out to the original author and request them to acknowledge that the modified patches may be merged while having the original sign-off line and author identity, or

• submit the modified patches as their own work (i.e. with their own sign-off line and author identity). In this case, the developer shall identify in the commit message(s) the original source the submitted work is based on (mentioning, for example, the original PR number).
9.6 Development Environment and Tools

9.6.1 Code Review

GitHub is intended to provide a framework for reviewing every commit before it is accepted into the code base. Changes, in the form of Pull Requests (PR) are uploaded to GitHub but don't actually become a part of the project until they've been reviewed, passed a series of checks (CI), and are approved by maintainers. GitHub is used to support the standard open source practice of submitting patches, which are then reviewed by the project members before being applied to the code base.

Pull requests should be appropriately labeled, and linked to any relevant bug or feature tracking issues.

The Zephyr project uses GitHub for code reviews and Git tree management. When submitting a change or an enhancement to any Zephyr component, a developer should use GitHub. GitHub Actions automatically assigns a responsible reviewer on a component basis, as defined in the MAINTAINERS.yml file stored with the code tree in the Zephyr project repository. A limited set of release managers are allowed to merge a pull request into the main branch once reviews are complete.

Give reviewers time to review before code merge

The Zephyr project is a global project that is not tied to a certain geography or timezone. We have developers and contributors from across the globe. When changes are proposed using pull request, we need to allow for a minimal review time to give developers and contributors the opportunity to review and comment on changes. There are different categories of changes and we know that some changes do require reviews by subject matter experts and owners of the subsystem being changed. Many changes fall under the “trivial” category that can be addressed with general reviews and do not need to be queued for a maintainer or code-owner review. Additionally, some changes might require further discussions and a decision by the TSC or the Security working group. To summarize the above, the diagram below proposes minimal review times for each category:

Workflow

- An author of a change can suggest in his pull-request which category a change should belong to. A project maintainers or TSC member monitoring the inflow of changes can change the label of a pull request by adding a comment justifying why a change should belong to another category.
- The project will use the label system to categorize the pull requests.
- Changes should not be merged before the minimal time has expired.

Categories/Labels
Fig. 4: Pull request classes
Hotfix  Any change that is a fix to an issue that blocks developers from doing their daily work, for example CI breakage, Test breakage, Minor documentation fixes that impact the user experience.

Such fixes can be merged at any time after they have passed CI checks. Depending on the fix, severity, and availability of someone to review them (other than the author) they can be merged with justification without review by one of the project owners.

Trivial  Trivial changes are those that appear obvious enough and do not require maintainer or code-owner involvement. Such changes should not change the logic or the design of a subsystem or component. For example a trivial change can be:

- Documentation changes
- Configuration changes
- Minor Build System tweaks
- Minor optimization to code logic without changing the logic
- Test changes and fixes
- Sample modifications to support additional configuration or boards etc.

Maintainer  Any changes that touch the logic or the original design of a subsystem or component will need to be reviewed by the code owner or the designated subsystem maintainer. If the code changes is initiated by a contributor or developer other than the owner the pull request needs to be assigned to the code owner who will have to drive the pull request to a mergeable state by giving feedback to the author and asking for more reviews from other developers.

Security  Changes that appear to have an impact to the overall security of the system need to be reviewed by a security expert from the security working group.

TSC and Working Groups  Changes that introduce new features or functionality or change the way the overall system works need to be reviewed by the TSC or the responsible Working Group. For example for breaking API changes, the proposal needs to be presented in the Architecture meeting so that the relevant stakeholders are made aware of the change.

A Pull-Request should have an Assignee

- An assignee to a pull request should not be the same as the author of the pull-request
- An assignee to a pull request is responsible for driving the pull request to a mergeable state
- An assignee is responsible for dismissing stale reviews and seeking reviews from additional developers and contributors
- Pull requests should not be merged without an approval by the assignee.

Pull Request should not be merged by author without review

All pull requests need to be reviewed and should not be merged by the author without a review. The following exceptions apply:

- Hot fixes: Fixing CI issues, reverts, and system breakage
- Release related changes: Changing version file, applying tags and release related activities without any code changes.
Developers and contributors should always seek review, however there are cases when reviewers are not available and there is a need to get a code change into the tree as soon as possible.

**Reviewers shall not ‘Request Changes’ without comments or justification**

Any change requests (-1) on a pull request have to be justified. A reviewer should avoid blocking a pull-request with no justification. If a reviewer feels that a change should not be merged without their review, then: Request change of the category: for example:

- Trivial -> Maintainer
- Assign Pull Request to yourself, this will mean that a pull request should not be merged without your approval.

**Pull Requests should have at least 2 approvals before they are merged**

A pull-request shall be merged only with two positive reviews (approval). Beside the person merging the pull-request (merging != approval), two additional approvals are required to be able to merge a pull request. The person merging the request can merge without approving or approve and merge to get to the 2 approvals required.

**Reviewers should keep track of pull requests they have provided feedback to**

If a reviewer has requested changes in a pull request, he or she should monitor the state of the pull request and/or respond to mention requests to see if his feedback has been addressed. Failing to do so, negative reviews shall be dismissed by the assignee or an owner of the repository. Reviews will be dismissed following the criteria below:

- The feedback or concerns were visibly addressed by the author
- The reviewer did not revisit the pull request after 2 week and multiple pings by the author
- The review is unrelated to the code change or asking for unjustified structural changes such as:
  - Split the PR
  - Can you fix this unrelated code that happens to appear in the diff
  - Can you fix unrelated issues
  - Etc.

**Closing Stale Issues and Pull Requests**

- The Pull requests and issues sections on Github are NOT discussion forums. They are items that we need to execute and drive to closure. Use the mailing lists for discussions.
- In case of both issues and pull-requests the original poster needs to respond to questions and provide clarifications regarding the issue or the change. After one week without a response to a request, a second attempt to elicit a response from the contributor will be made. After one more week without a response the item may be closed (draft and DNM tagged pull requests are excluded).
9.6.2 Continuous Integration

All changes submitted to GitHub are subject to tests that are run on emulated platforms and architectures to identify breakage and regressions that can be immediately identified. Testing using Twister additionally performs build tests of all boards and platforms. Documentation changes are also verified through review and build testing to verify doc generation will be successful.

Any failures found during the CI test run will result in a negative review assigned automatically by the CI system. Developers are expected to fix issues and rework their patches and submit again.

The CI infrastructure currently runs the following tests:

- Run “checkpatch” for code style issues (can vote -1 on errors; see note)
- Gitlint: Git commit style based on project requirements
- License Check: Check for conflicting licenses
- Run “twister” script
  - Run kernel tests in QEMU (can vote -1 on errors)
  - Build various samples for different boards (can vote -1 on errors)
- Verify documentation builds correctly.

**Note:** “checkpatch” is a Perl script that uses regular expressions to extract information that requires a C language parser to process accurately. As such it sometimes issues false positives. Known cases include constructs like:

```
static uint8_t __aligned(PAGE_SIZE) page_pool[PAGE_SIZE * POOL_PAGES];
IOPCTL_Type *base = config->base;
```

Both lines produce a diagnostic regarding spaces around the * operator: the first is misidentified as a pointer type declaration that would be correct as PAGE_SIZE * POOL_PAGES while the second is misidentified as a multiplication expression that would be correct as IOPCTL_Type * base.

Maintainers can override the -1 in cases where the CI infrastructure gets the wrong answer.

9.6.3 Labeling issues and pull requests in GitHub

The project uses GitHub issues and pull requests (PRs) to track and manage daily and long-term work and contributions to the Zephyr project. We use GitHub **labels** to classify and organize these issues and PRs by area, type, priority, and more, making it easier to find and report on relevant items.

All GitHub issues or pull requests must be appropriately labeled. Issues and PRs often have multiple labels assigned, to help classify them in the different available categories. When reviewing a PR, if it has missing or incorrect labels, maintainers shall fix it.

This saves us all time when searching, reduces the chances of the PR or issue being forgotten, speeds up reviewing, avoids duplicate issue reports, etc.

These are the labels we currently have, grouped by applicability:

**Labels applicable to issues only**

- **priority:** {high | medium | low}
To classify the impact and importance of a bug or feature.

Note: Issue priorities are generally set or changed during the bug-triage or TSC meetings.

- **Regression**
  
  Something, which was working, but does not anymore (bug subtype).

- **Enhancement**
  
  Changes/Updates/Additions to existing features.

- **Feature request**
  
  A request for a new feature.

- **Feature**
  
  A planned feature with a milestone.

- **Hardware Support**
  
  Covers porting an existing feature (including Zephyr itself) to new hardware.

- **Duplicate**
  
  This issue is a duplicate of another issue (please specify).

- **Good first issue**
  
  Good for a first time contributor to take.

- **Release Notes**
  
  Issues that need to be mentioned in release notes as known issues with additional information.

Any issue must be classified and labeled as either Bug, Enhancement, RFC, Feature, Feature Request or Hardware Support. More information on how feature requests are handled and become features can be found in Feature Tracking.

**Labels applicable to pull requests only**

The issue or PR describes a change to a stable API.

- **Hotfix**
  
  Fix for an issue blocking development.

- **Trivial**
  
  - **Maintainer**
    
    Maintainer review required.

- **Security Review**
  
  To be reviewed by a security expert.

- **DNM**
  
  This PR should not be merged (Do Not Merge). For work in progress, GitHub “draft” PRs are preferred.

- **Needs review**
  
  The PR needs attention from the maintainers.

- **Backport**
  
  The PR is a backport or should be backported.

- **Licensing**
The PR has licensing issues which require a licensing expert to review it.

**Note:** For all labels applicable to PRs: Please note that the label, together with PR complexity, affects how long a merge should be held to ensure proper review. See [review process](#) for details.

### Labels applicable to both pull requests and issues

- **area:** *

Indicates Zephyr subsystems (e.g., area: Kernel, area: I2C, area: Memory Management), project functions (e.g., area: Debugging, area: Documentation, area: Process), or other categories (e.g., area: Coding Style, area: MISRA-C) affected by the bug or the pull request.

An area maintainer should be able to filter by an area label and find all issues and PRs which relate to that area.

- **platform:** *

An issue or PR which affects only a particular platform.

- **dev-review**

The issue is to be discussed in the following dev-review if time permits.

- **TSC**

TSC stands for Technical Steering Committee. The issue is to be discussed in the following TSC meeting if time permits.

- **Breaking API Change**

The issue or PR describes a breaking change to a stable API. See additional information in [Introducing breaking API changes](#).

- **Bug**

The issue is a bug, or the PR is fixing a bug.

- **Coverity**

A Coverity detected issue or its fix.

- **Waiting for response**

The Zephyr developers are waiting for the submitter to respond to a question, or address an issue.

- **Blocked**

Blocked by another PR or issue.

- **Stale**

An issue or a PR which seems abandoned, and requires attention by the author.

- **In progress**

For PRs: is work in progress and should not be merged yet. For issues: Is being worked on.

- **RFC**

The author would like input from the community. For a PR it should be considered a draft.

- **LTS**

Long term release branch related.

- **EXT**

Related to an external component.
9.7 Bug Reporting

To maintain traceability and relation between proposals, changes, features, and issues, it is recommended to cross-reference source code commits with the relevant GitHub issues and vice versa. Any changes that originate from a tracked feature or issue should contain a reference to the feature by mentioning the corresponding issue or pull-request identifiers.

At any time it should be possible to establish the origin of a change and the reason behind it by following the references in the code.

9.7.1 Reporting a regression issue

It could happen that the issue being reported is identified as a regression, as the use case is known to be working on earlier commit or release. In this case, providing directly the guilty commit when submitting the bug gains a lot of time in the eventual bug fixing.

To identify the commit causing the regression, several methods could be used, but tree bisecting method is an efficient one that doesn’t require deep code expertise and can be used by everyone.

For this, `git bisect` is the recommended tool.

Recommendations on the process:

- Run `west update` on each bisection step.
- Once the bisection is over and a culprit identified, verify manually the result.

9.8 Communication and Collaboration

The Zephyr Discord Server is the primary chat forum used by Zephyr developers, contributors, and users.

The Zephyr project mailing lists are used as an additional communication tool by project members, contributors, and the community. There are specialized mailing lists for specific interests. Several lists are public and open. Mailing lists are always available for use in situations where Discord is unavailable or an unsuitable forum.

In general, bug reports and other issues should be reported as GitHub Issues and not broadcasted to the mailing list. The same applies to code reviews.

9.9 Code Documentation

9.9.1 API Documentation

Well documented APIs enhance the experience for developers and are an essential requirement for defining an API's success. Doxygen is a general purpose documentation tool that the zephyr project uses for documenting APIs. It generates either an on-line documentation browser (in HTML) and/or provides input for other tools that is used to generate a reference manual from documented source files. In particular, doxygen's XML output is used as an input when producing the Zephyr project's online documentation.
9.9.2 Reference to Requirements

APIs for the most part document the implementation of requirements or advertised features and can be traced back to features. We use the API documentation as the main interface to trace implementation back to documented features. This is done using custom _doxygen_ tags that reference requirements maintained somewhere else in a requirement catalogue.

9.9.3 Test Documentation

To help understand what each test does and which functionality it tests we also document all test code using the same tools and in the same context and generate documentation for all unit and integration tests maintained in the same environment. Tests are documented using references to the APIs or functionality they validate by creating a link back to the APIs and by adding a reference to the original requirements.

9.9.4 Documentation Guidelines

Test Code

The Zephyr project uses several test methodologies, the most common being the Ztest framework. Test documentation should only be done on the entry test functions (usually prefixed with test_) and those that are called directly by the Ztest framework. Those tests are going to appear in test reports and using their name and identifier is the best way to identify them and trace back to them from requirements.

Test documentation should not interfere with the actual API documentation and needs to follow a new structure to avoid confusion. Using a consistent naming scheme and following a well-defined structure we will be able to group this documentation in its own module and identify it uniquely when parsing test data for traceability reports. Here are a few guidelines to be followed:

- All test code documentation should be grouped under the all_tests doxygen group
- All test documentation should be under doxygen groups that are prefixed with tests_

The custom doxygen @verify directive signifies that a test verifies a requirement:

```c
/**
 * @brief Tests for the Semaphore kernel object
 * @defgroup kernel_semaphore_tests Semaphore
 * @ingroup all_tests
 * @{
 * @
 */
...
/**
 * @brief A brief description of the tests
 * @Some details about the test
 * @more details
 * @verify{@req{1111}}
 */
void test_sema_thread2thread(void)
{
...
}
...
/**
(continues on next page)```
To get coverage of how an implementation or a piece of code satisfies a requirements, we use the `satisfy` alias in doxygen:

```c
/**
 * @brief Give a semaphore.
 *
 * This routine gives @a sem, unless the semaphore is already at its maximum
 * permitted count.
 *
 * @note Can be called by ISRs.
 *
 * @param sem Address of the semaphore.
 *
 * @satisfy{@req{015}}
 */
__syscall void k_sem_give(struct k_sem *sem);
```

To generate the matrix, you will first need to build the documentation, specifically you will need to build the doxygen XML output:

```bash
$ make doxygen
```

Parse the generated XML data from doxygen to generate the traceability matrix.

The Zephyr project defines a development process workflow using GitHub Issues to track feature, enhancement, and bug reports together with GitHub Pull Requests (PRs) for submitting and reviewing changes. Zephyr community members work together to review these Issues and PRs, managing feature enhancements and quality improvements of Zephyr through its regular releases, as outlined in the program management overview.

We can only manage the volume of Issues and PRs, by requiring timely reviews, feedback, and responses from the community and contributors, both for initial submissions and for follow-up questions and clarifications. Read about the project's development processes and tools and specifics about review timelines to learn about the project's goals and guidelines for our active developer community.

**TSC Project Roles** describes in detail the Zephyr project roles and associated permissions with respect to the development process workflow.

### 9.10 Terminology

- **mainline**: The main tree where the core functionality and core features are being developed.
- **subsystem/feature branch**: is a branch within the same repository. In our case, we will use the term branch also when referencing branches not in the same repository, which are a copy of a repository sharing the same history.
- **upstream**: A parent branch the source code is based on. This is the branch you pull from and push to, basically your upstream.
- **LTS**: Long Term Support
Chapter 10

Security

These documents describe the requirements, processes, and developer guidelines for ensuring security is addressed within the Zephyr project.

10.1 Zephyr Security Overview

10.1.1 Introduction

This document outlines the steps of the Zephyr Security Subcommittee towards a defined security process that helps developers build more secure software while addressing security compliance requirements. It presents the key ideas of the security process and outlines which documents need to be created. After the process is implemented and all supporting documents are created, this document is a top-level overview and entry point.

Overview and Scope

We begin with an overview of the Zephyr development process, which mainly focuses on security functionality.

In subsequent sections, the individual parts of the process are treated in detail. As depicted in Figure 1, these main steps are:

1. **Secure Development**: Defines the system architecture and development process that ensures adherence to relevant coding principles and quality assurance procedures.

2. **Secure Design**: Defines security procedures and implement measures to enforce them. A security architecture of the system and relevant sub-modules is created, threats are identified, and countermeasures designed. Their correct implementation and the validity of the threat models are checked by code reviews. Finally, a process shall be defined for reporting, classifying, and mitigating security issues.

3. **Security Certification**: Defines the certifiable part of the Zephyr RTOS. This includes an evaluation target, its assets, and how these assets are protected. Certification claims shall be determined and backed with appropriate evidence.

Intended Audience

This document is a guideline for the development of a security process by the Zephyr Security Subcommittee and the Zephyr Technical Steering Committee. It provides an overview of the Zephyr security process for (security) engineers and architects.
Nomenclature

In this document, the keywords “MUST”, “MUST NOT”, “REQUIRED”, “SHALL”, “SHALL NOT”, “SHOULD”, “SHOULD NOT”, “RECOMMENDED”, “MAY”, and “OPTIONAL” are to be interpreted as described in [?]. These words are used to define absolute requirements (or prohibitions), highly recommended requirements, and truly optional requirements. As noted in RFC-2119, “These terms are frequently used to specify behavior with security implications. The effects on security of not implementing a MUST or SHOULD, or doing something the specification says MUST NOT or SHOULD NOT be done may be very subtle. Document authors should take the time to elaborate the security implications of not following recommendations or requirements as most implementors will not have had the benefit of the experience and discussion that produced the specification.”

Security Document Update

This document is a living document. As new requirements, features, and changes are identified, they will be added to this document through the following process:

1. Changes will be submitted from the interested party(ies) via pull requests to the Zephyr documentation repository.
2. The Zephyr Security Subcommittee will review these changes and provide feedback or acceptance of the changes.
3. Once accepted, these changes will become part of the document.

10.1.2 Current Security Definition

This section recapitulates the current status of secure development within the Zephyr RTOS. Currently, focus is put on functional security and code quality assurance, although additional security features are scoped.

The three major security measures currently implemented are:

- **Security Functionality** with a focus on cryptographic algorithms and protocols. Support for cryptographic hardware is scoped for future releases. The Zephyr runtime architecture
is a monolithic binary and removes the need for dynamic loaders, thereby reducing the exposed attack surface.

- **Quality Assurance** is driven by using a development process that requires all code to be reviewed before being committed to the common repository. Furthermore, the reuse of proven building blocks such as network stacks increases the overall quality level and guarantees stable APIs. Static code analyses provide additional quality checks.

- **Execution Protection** including thread separation, stack and memory protection is currently available in the upstream Zephyr RTOS starting with version 1.9.0 (stack protection). Memory protection and thread separation were added in version 1.10.0 for X86 and in version 1.11.0 for ARM and ARC.

These topics are discussed in more detail in the following subsections.

### Security Functionality

The security functionality in Zephyr hinges mainly on the inclusion of cryptographic algorithms, and on its monolithic system design.

The cryptographic features are provided through a set of cryptographic libraries. Applications can choose TinyCrypt2 or Mbed TLS based on their needs. TinyCrypt2 supports key cryptographic algorithms required by the connectivity stacks. TinyCrypt2, however, only provides a limited set of algorithms. Mbed TLS supports a wider range of algorithms, but at the cost of additional requirements such as malloc support. Applications can choose the solution that matches their individual requirements. Future work may include APIs to abstract the underlying crypto library choice.

APIs for vendor specific cryptographic IPs in both hardware and software are planned, including secure key storage in the form of secure access modules (SAMs), Trusted Platform Modules (TPMs), and Trusted Execution Environments (TEEs).

The security architecture is based on a monolithic design where the Zephyr kernel and all applications are compiled into a single static binary. System calls are implemented as function calls without requiring context switches. Static linking eliminates the potential for dynamically loading malicious code.

Additional protection features are available in later releases. Stack protection mechanisms are provided to protect against stack overruns. In addition, applications can take advantage of thread separation features to split the system into privileged and unprivileged execution environments. Memory protection features provide the capability to partition system resources (memory, peripheral address space, etc.) and assign resources to individual threads or groups of threads. Stack, thread execution level, and memory protection constraints are enforced at the time of context switch.

### Quality Assurance

The Zephyr project uses an automated quality assurance process. The goal is to have a process including mandatory code reviews, feature and issue management/tracking, and static code analyses.

Code reviews are documented and enforced using a voting system before getting checked into the repository by the responsible subsystem's maintainer. The main goals of the code review are:

- Verifying correct functionality of the implementation
- Increasing the readability and maintainability of the contributed source code
- Ensuring appropriate usage of string and memory functions
- Validation of the user input
• Reviewing the security relevant code for potential issues

The current coding principles focus mostly on coding styles and conventions. Functional correctness is ensured by the build system and the experience of the reviewer. Especially for security relevant code, concrete and detailed guidelines need to be developed and aligned with the developers (see: Secure Coding).

Static code analyses are run on the Zephyr code tree on a regular basis, see Static Code Analysis.

Bug and issue tracking and management is performed using Github. The term “survivability” was coined to cover pro-active security tasks such as security issue categorization and management. A problem identified as vulnerability is managed within Github security advisories.

Issues determined by static analyses should have more stringent reviews before they are closed as non-issues (at least another person educated in security processes need to agree on non-issue before closing).

A security subcommittee has been formed to develop a security process in more detail; this document is part of that process.

Execution Protection

Execution protection is supported and can be categorized into the following tasks:

• **Memory separation**: Memory will be partitioned into regions and assigned attributes based on the owner of that region of memory. Threads will only have access to regions they control.

• **Stack protection**: Stack guards would provide mechanisms for detecting and trapping stack overruns. Individual threads should only have access to their own stacks.

• **Thread separation**: Individual threads should only have access to their own memory resources. As threads are scheduled, only memory resources owned by that thread will be accessible. Topics such as program flow protection and other measures for tamper resistance are currently not in scope.

System Level Security (Ecosystem, …)

System level security encompasses a wide variety of categories. Some examples of these would be:

• Secure/trusted boot
• Over the air (OTA) updates
• External Communication
• Device authentication
• Access control of onboard resources
  – Flash updating
  – Secure storage
  – Peripherals
• Root of trust
• Reduction of attack surface

Some of these categories are interconnected and rely on multiple pieces to be in place to produce a full solution for the application.
10.1.3 Secure Development Process

The development of secure code shall adhere to certain criteria. These include coding guidelines and development processes that can be roughly separated into two categories related to software quality and related to software security. Furthermore, a system architecture document shall be created and kept up-to-date with future development.

System Architecture

![Zephyr System Architecture Diagram](image)

A high-level schematic of the Zephyr system architecture is given in Figure 2. It separates the architecture into an OS part (kernel + OS Services) and a user-specific part (Application Services). The OS part itself contains low-level, platform specific drivers and the generic implementation of I/O APIs, file systems, kernel-specific functions, and the cryptographic library.

A document describing the system architecture and design choices shall be created and kept up to date with future development. This document shall include the base architecture of the Zephyr OS and an overview of important submodules. For each of the modules, a dedicated architecture document shall be created and evaluated against the implementation. These documents shall serve as an entry point to new developers and as a basis for the security architecture. Please refer to the Zephyr subsystem documentation for detailed information.
Secure Coding

Designing an open software system such as Zephyr to be secure requires adhering to a defined set of design standards. These standards are included in the Zephyr Project documentation, specifically in its Secure Coding section. In [?], the following, widely accepted principles for protection mechanisms are defined to prevent security violations and limit their impact:

- **Open design** as a design principle incorporates the maxim that protection mechanisms cannot be kept secret on any system in widespread use. Instead of relying on secret, custom-tailored security measures, publicly accepted cryptographic algorithms and well established cryptographic libraries shall be used.

- **Economy of mechanism** specifies that the underlying design of a system shall be kept as simple and small as possible. In the context of the Zephyr project, this can be realized, e.g., by modular code [?] and abstracted APIs.

- **Complete mediation** requires that each access to every object and process needs to be authenticated first. Mechanisms to store access conditions shall be avoided if possible.

- **Fail-safe defaults** defines that access is restricted by default and permitted only in specific conditions defined by the system protection scheme, e.g., after successful authentication. Furthermore, default settings for services shall be chosen in a way to provide maximum security. This corresponds to the “Secure by Default” paradigm [?].

- **Separation of privilege** is the principle that two conditions or more need to be satisfied before access is granted. In the context of the Zephyr project, this could encompass split keys [?].

- **Least privilege** describes an access model in which each user, program and thread shall have the smallest possible subset of permissions in the system required to perform their task. This positive security model aims to minimize the attack surface of the system.

- **Least common mechanism** specifies that mechanisms common to more than one user or process shall not be shared if not strictly required. The example given in [?] is a function that should be implemented as a shared library executed by each user and not as a supervisor procedure shared by all users.

- **Psychological acceptability** requires that security features are easy to use by the developers in order to ensure its usage and the correctness of its application.

In addition to these general principles, the following points are specific to the development of a secure RTOS:

- **Complementary Security/Defense in Depth**: do not rely on a single threat mitigation approach. In case of the complementary security approach, parts of the threat mitigation are performed by the underlying platform. In case such mechanisms are not provided by the platform, or are not trusted, a defense in depth [?] paradigm shall be used.

- **Less commonly used services off by default**: to reduce the exposure of the system to potential attacks, features or services shall not be enabled by default if they are only rarely used (a threshold of 80% is given in [?]). For the Zephyr project, this can be realized using the configuration management. Each functionality and module shall be represented as a configuration option and needs to be explicitly enabled. Then, all features, protocols, and drivers not required for a particular use case can be disabled. The user shall be notified if low-level options and APIs are enabled but not used by the application.

- **Change management**: to guarantee a traceability of changes to the system, each change shall follow a specified process including a change request, impact analysis, ratification, implementation, and validation phase. In each stage, appropriate documentation shall be provided. All commits shall be related to a bug report or change request in the issue tracker. Commits without a valid reference shall be denied.

Based on these design principles and commonly accepted best practices, a secure development guide shall be developed, published, and implemented into the Zephyr development process.
Further details on this are given in the *Secure Design* section.

**Quality Assurance**

The quality assurance part encompasses the following criteria:

- **Adherence to the Coding Conventions** with respect to coding style, naming schemes of modules, functions, variables, and so forth. This increases the readability of the Zephyr code base and eases the code review. These coding conventions are enforced by automated scripts prior to check-in.

- **Adherence to Deployment Guidelines** is required to ensure consistent releases with a well-documented feature set and a trackable list of security issues.

- **Code Reviews** ensure the functional correctness of the code base and shall be performed on each proposed code change prior to check-in. Code reviews shall be performed by at least one independent reviewer other than the author(s) of the code change. These reviews shall be performed by the subsystem maintainers and developers on a functional level and are to be distinguished from security reviews as laid out in the *Secure Design* section. Refer to the *Project and Governance* documentation for more information.

- **Static Code Analysis** tools efficiently detect common coding mistakes in large code bases. All code shall be analyzed using an appropriate tool prior to merges into the main repository. This is not per individual commit, but is to be run on some interval on specific branches. It is mandatory to remove all findings or waive potential false-positives before each release. Waivers shall be documented centrally and in the form of a comment inside the source code itself. The documentation shall include the employed tool and its version, the date of the analysis, the branch and parent revision number, the reason for the waiver, the author of the respective code, and the approver(s) of the waiver. This shall as a minimum run on the main release branch and on the security branch. It shall be ensured that each release has zero issues with regard to static code analysis (including waivers). Refer to the *Project and Governance* documentation for more information.

- **Complexity Analyses** shall be performed as part of the development process and metrics such as cyclomatic complexity shall be evaluated. The main goal is to keep the code as simple as possible.

- **Automation**: the review process and checks for coding rule adherence are a mandatory part of the precommit checks. To ensure consistent application, they shall be automated as part of the precommit procedure. Prior to merging large pieces of code in from subsystems, in addition to review process and coding rule adherence, all static code analysis must have been run and issues resolved.

**Release and Lifecycle Management**

Lifecycle management contains several aspects:

- **Device management** encompasses the possibility to update the operating system and/or security related sub-systems of Zephyr enabled devices in the field.

- **Lifecycle management**: system stages shall be defined and documented along with the transactions between the stages in a system state diagram. For security reasons, this shall include locking of the device in case an attack has been detected, and a termination if the end of life is reached.

- **Release management** describes the process of defining the release cycle, documenting releases, and maintaining a record of known vulnerabilities and mitigations. Especially for certification purposes the integrity of the release needs to be ensured in a way that later manipulation (e.g., inserting of backdoors, etc.) can be easily detected.
• **Rights management and NDAs:** if required by the chosen certification, the confidentiality and integrity of the system needs to be ensured by an appropriate rights management (e.g., separate source code repository) and non-disclosure agreements between the relevant parties. In case of a repository shared between several parties, measures shall be taken that no malicious code is checked in.

These points shall be evaluated with respect to their impact on the development process employed for the Zephyr project.

### 10.1.4 Secure Design

In order to obtain a certifiable system or product, the security process needs to be clearly defined and its application needs to be monitored and driven. This process includes the development of security related modules in all of its stages and the management of reported security issues. Furthermore, threat models need to be created for currently known and future attack vectors, and their impact on the system needs to be investigated and mitigated. Please refer to the **Secure Coding** outlined in the Zephyr project documentation for detailed information.

The software security process includes:

• **Adherence to the Secure Development Coding** is mandatory to avoid that individual components breach the system security and to minimize the vulnerability of individual modules. While this can be partially achieved by automated tests, it is inevitable to investigate the correct implementation of security features such as countermeasures manually in security-critical modules.

• **Security Reviews** shall be performed by a security architect in preparation of each security-targeted release and each time a security-related module of the Zephyr project is changed. This process includes the validation of the effectiveness of implemented security measures, the adherence to the global security strategy and architecture, and the preparation of audits towards a security certification if required.

• **Security Issue Management** encompasses the evaluation of potential system vulnerabilities and their mitigation as described in **Security Issue Management**.

These criteria and tasks need to be integrated into the development process for secure software and shall be automated wherever possible. On system level, and for each security related module of the secure branch of Zephyr, a directly responsible security architect shall be defined to guide the secure development process.

### Security Architecture

The general guidelines above shall be accompanied by an architectural security design on system- and module-level. The high level considerations include:

• The identification of **security and compliance requirements**

• **Functional security** such as the use of cryptographic functions whenever applicable

• Design of **countermeasures** against known attack vectors

• Recording of security relevant **auditable events**

• Support for **Trusted Platform Modules (TPM)** and **Trusted Execution Environments (TEE)**

• Mechanisms to allow for **in-the-field updates** of devices using Zephyr

• Task scheduler and separation

The security architecture development is based on assets derived from the structural overview of the overall system architecture. Based on this, the individual steps include:
1. **Identification of assets** such as user data, authentication and encryption keys, key generation data (obtained from RNG), security relevant status information.

2. **Identification of threats** against the assets such as breaches of confidentiality, manipulation of user data, etc.

3. **Definition of requirements** regarding security and protection of the assets, e.g., countermeasures or memory protection schemes.

The security architecture shall be harmonized with the existing system architecture and implementation to determine potential deviations and mitigate existing weaknesses. Newly developed sub-modules that are integrated into the secure branch of the Zephyr project shall provide individual documents describing their security architecture. Additionally, their impact on the system level security shall be considered and documented.

**Security Vulnerability Reporting**

Please see [Security Vulnerability Reporting](#) for information on reporting security vulnerabilities.

**Threat Modeling and Mitigation**

The modeling of security threats against the Zephyr RTOS is required for the development of an accurate security architecture and for most certification schemes. The first step of this process is the definition of assets to be protected by the system. The next step then models how these assets are protected by the system and which threats against them are present. After a threat has been identified, a corresponding threat model is created. This model contains the asset and system vulnerabilities, as well as the description of the potential exploits of these vulnerabilities. Additionally, the impact on the asset, the module it resides in, and the overall system is to be estimated. This threat model is then considered in the module and system security architecture and appropriate countermeasures are defined to mitigate the threat or limit the impact of exploits.

In short, the threat modeling process can be separated into these steps (adapted from [?]):

1. Definition of assets
2. Application decomposition and creation of appropriate data flow diagrams (DFDs)
3. Threat identification and categorization using the [?] and [?] approaches
4. Determination of countermeasures and other mitigation approaches

This procedure shall be carried out during the design phase of modules and before major changes of the module or system architecture. Additionally, new models shall be created, or existing ones shall be updated whenever new vulnerabilities or exploits are discovered. During security reviews, the threat models and the mitigation techniques shall be evaluated by the responsible security architect.

From these threat models and mitigation techniques tests shall be derived that prove the effectiveness of the countermeasures. These tests shall be integrated into the continuous integration workflow to ensure that the security is not impaired by regressions.

**Vulnerability Analyses**

In order to find weak spots in the software implementation, vulnerability analyses (VA) shall be performed. Of special interest are investigations on cryptographic algorithms, critical OS tasks, and connectivity protocols.

On a pure software level, this encompasses

- **Penetration testing** of the RTOS on a particular hardware platform, which involves testing the respective Zephyr OS configuration and hardware as one system.
• **Side channel attacks** (timing invariance, power invariance, etc.) should be considered. For instance, ensuring **timing invariance** of the cryptographic algorithms and modules is required to reduce the attack surface. This applies to both the software implementations and when using cryptographic hardware.

• **Fuzzing tests** shall be performed on both exposed APIs and protocols.

The list given above serves primarily illustration purposes. For each module and for the complete Zephyr system (in general on a particular hardware platform), a suitable VA plan shall be created and executed. The findings of these analyses shall be considered in the security issue management process, and learnings shall be formulated as guidelines and incorporated into the secure coding guide.

If possible (as in case of fuzzing analyses), these tests shall be integrated into the continuous integration process.

### 10.1.5 Security Certification

One goal of creating a secure branch of the Zephyr RTOS is to create a certifiable system or certifiable submodules thereof. The certification scope and scheme are yet to be decided. However, many certifications such as Common Criteria [?] require evidence that the evaluation claims are indeed fulfilled, so a general certification process is outlined in the following. Based on the final choices for the certification scheme and evaluation level, this process needs to be refined.

**Generic Certification Process**

In general, the steps towards a certification or precertification (compare [?]) are:

1. The **definition of assets** to be protected within the Zephyr RTOS. Potential candidates are confidential information such as cryptographic keys, user data such as communication logs, and potentially IP of the vendor or manufacturer.

2. Developing a **threat model** and **security architecture** to protect the assets against exploits of vulnerabilities of the system. As a complete threat model includes the overall product including the hardware platform, this might be realized by a split model containing a precertified secure branch of Zephyr which the vendor could use to certify their Zephyr-enabled product.

3. Formulating an **evaluation target** that includes the **certification claims** on the security of the assets to be evaluated and certified, as well as assumptions on the operating conditions.

4. Providing **proof** that the claims are fulfilled. This includes consistent documentation of the security development process, etc.

These steps are partially covered in previous sections as well. In contrast to these sections, the certification process only requires to consider those components that shall be covered by the certification. The security architecture, for example, considers assets on system level and might include items not relevant for the certification.

**Certification Options**

For the security certification as such, the following options can be pursued:

1. **Abstract precertification of Zephyr as a pure software system**: this option requires assumptions on the underlying hardware platform and the final application running on top of Zephyr. If these assumptions are met by the hardware and the application, a full certification can be more easily achieved. This option is the most flexible approach but puts the largest burden on the product vendor.
2. **Certification of Zephyr on specific hardware platform without a specific application in mind:** this scenario describes the enablement of a secure platform running the Zephyr RTOS. The hardware manufacturer certifies the platform under defined assumptions on the application. If these are met, the final product can be certified with little effort.

3. **Certification of an actual product:** in this case, a full product including a specific hardware, the Zephyr RTOS, and an application is certified.

In all three cases, the certification scheme (e.g., FIPS 140-2 [?] or Common Criteria [?]), the scope of the certification (main-stream Zephyr, security branch, or certain modules), and the certification/assurance level need to be determined.

In case of partial certifications (options 1 and 2), assumptions on hardware and/or software are required for certifications. These can include [?]

- **Appropriate physical security** of the hardware platform and its environment.
- **Sufficient protection of storage and timing channels** on the hardware platform itself and all connected devices. (No mentioning of remote connections.)
- Only **trusted/assured applications** running on the device
- The device and its software stack is configured and operated by **properly trained and trusted individuals** with no malicious intent.

These assumptions shall be part of the security claim and evaluation target documents.

### 10.2 Security Vulnerability Reporting

#### 10.2.1 Introduction

Vulnerabilities to the Zephyr project may be reported via email to the vulnerabilities@zephyrproject.org mailing list. These reports will be acknowledged and analyzed by the security response team within 1 week. Each vulnerability will be entered into the Zephyr Project security advisory GitHub. The original submitter will be granted permission to view the issues that they have reported.

#### 10.2.2 Security Issue Management

Issues within this bug tracking system will transition through a number of states according to this diagram:
- **New**: This state represents new reports that have been entered directly by a reporter. When entered by the response team in response to an email, the issue shall be transitioned directly to Triage.

- **Triage**: This issue is awaiting Triage by the response team. The response team will analyze the issue, determine a responsible entity, assign it to that individual, and move the issue to the Assigned state. Part of triage will be to set the issue's priority.

- **Assigned**: The issue has been assigned, and is awaiting a fix by the assignee.

- **Review**: Once there is a Zephyr pull request for the issue, the PR link will be added to a comment in the issue, and the issue moved to the Review state.

- **Accepted**: Indicates that this issue has been merged into the appropriate branch within Zephyr.

- **Public**: The embargo period has ended. The issue will be made publicly visible, the associ-
ated CVE updated, and the vulnerabilities page in the docs updated to include the detailed information.

The security advisories created are kept private, due to the sensitive nature of security reports. The issues are only visible to certain parties:

- Members of the PSIRT mailing list
- the reporter
- others, as proposed and ratified by the Zephyr Security Subcommittee. In the general case, this will include:
  - The code owner responsible for the fix.
  - The Zephyr release owners for the relevant releases affected by this vulnerability.

The Zephyr Security Subcommittee shall review the reported vulnerabilities during any meeting with more than three people in attendance. During this review, they shall determine if new issues need to be embargoed.

The guideline for embargo will be based on: 1. Severity of the issue, and 2. Exploitability of the issue. Issues that the subcommittee decides do not need an embargo will be reproduced in the regular Zephyr project bug tracking system.

Security sensitive vulnerabilities shall be made public after an embargo period of at most 90 days. The intent is to allow 30 days within the Zephyr project to fix the issues, and 60 days for external parties building products using Zephyr to be able to apply and distribute these fixes.

Fixes to the code shall be made through pull requests PR in the Zephyr project github. Developers shall make an attempt to not reveal the sensitive nature of what is being fixed, and shall not refer to CVE numbers that have been assigned to the issue. The developer instead should merely describe what has been fixed.

The security subcommittee will maintain information mapping embargoed CVEs to these PRs (this information is within the Github security advisories), and produce regular reports of the state of security issues.

Each issue that is considered a security vulnerability shall be assigned a CVE number. As fixes are created, it may be necessary to allocate additional CVE numbers, or to retire numbers that were assigned.

### 10.2.3 Vulnerability Notification

Each Zephyr release shall contain a report of CVEs that were fixed in that release. Because of the sensitive nature of these vulnerabilities, the release shall merely include a list of CVEs that have been fixed. After the embargo period, the vulnerabilities page shall be updated to include additional details of these vulnerabilities. The vulnerability page shall give credit to the reporter(s) unless a reporter specifically requests anonymity.

The Zephyr project shall maintain a vulnerability-alerts mailing list. This list will be seeded initially with a contact from each project member. Additional parties can request to join this list by filling out the form at the Vulnerability Registry. These parties will be vetted by the project director to determine that they have a legitimate interest in knowing about security vulnerabilities during the embargo period.

Periodically, the security subcommittee will send information to this mailing list describing known embargoed issues, and their backport status within the project. This information is intended to allow them to determine if they need to backport these changes to any internal trees.

When issues have been triaged, this list will be informed of:

- The Zephyr Project security advisory link (GitHub).
- The CVE number assigned.
10.2.4 Backporting of Security Vulnerabilities

Each security issue fixed within Zephyr shall be backported to the following releases:

- The current Long Term Stable (LTS) release.
- The most recent two releases.

The developer of the fix shall be responsible for any necessary backports, and apply them to any of the above listed release branches, unless the fix does not apply (the vulnerability was introduced after this release was made). All recommendations for vulnerability fixes apply for backport pull requests (and associated issues). Additionally, it is recommended that the developer privately informs the responsible release manager that the backport pull request and issue are addressing a vulnerability.

Backports will be tracked on the security advisory.

10.2.5 Need to Know

Due to the sensitive nature of security vulnerabilities, it is important to share details and fixes only with those parties that have a need to know. The following parties will need to know details about security vulnerabilities before the embargo period ends:

- Maintainers will have access to all information within their domain area only.
- The current release manager, and the release manager for historical releases affected by the vulnerability (see backporting above).
- The Project Security Incident Response (PSIRT) team will have full access to information. The PSIRT is made up of representatives from platinum members, and volunteers who do work on triage from other members.
- As needed, release managers and maintainers may be invited to attend additional security meetings to discuss vulnerabilities.

10.3 Secure Coding

Traditionally, microcontroller-based systems have not placed much emphasis on security. They have usually been thought of as isolated, disconnected from the world, and not very vulnerable, just because of the difficulty in accessing them. The Internet of Things has changed this. Now, code running on small microcontrollers often has access to the internet, or at least to other devices (that may themselves have vulnerabilities). Given the volume they are often deployed at, uncontrolled access can be devastating.\(^1\)

This document describes the requirements and process for ensuring security is addressed within the Zephyr project. All code submitted should comply with these principles.

Much of this document comes from \[?\].

\(^1\) An attack resulted in a significant portion of DNS infrastructure being taken down.
10.3.1 Introduction and Scope

This document covers guidelines for the Zephyr Project, from a security perspective. Many of the ideas contained herein are captured from other open source efforts.

We begin with an overview of secure design as it relates to Zephyr. This is followed by a section on Secure development knowledge, which gives basic requirements that a developer working on the project will need to have. This section gives references to other security documents, and full details of how to write secure software are beyond the scope of this document. This section also describes vulnerability knowledge that at least one of the primary developers should have. This knowledge will be necessary for the review process described below this.

Following this is a description of the review process used to incorporate changes into the Zephyr codebase. This is followed by documentation about how security-sensitive issues are handled by the project.

Finally, the document covers how changes are to be made to this document.

10.3.2 Secure Coding

Designing an open software system such as Zephyr to be secure requires adhering to a defined set of design standards. In [?], the following, widely accepted principles for protection mechanisms are defined to help prevent security violations and limit their impact:

- **Open design** as a design guideline incorporates the maxim that protection mechanisms cannot be kept secret on any system in widespread use. Instead of relying on secret, custom-tailored security measures, publicly accepted cryptographic algorithms and well established cryptographic libraries shall be used.

- **Economy of mechanism** specifies that the underlying design of a system shall be kept as simple and small as possible. In the context of the Zephyr project, this can be realized, e.g., by modular code [?] and abstracted APIs.

- **Complete mediation** requires that each access to every object and process needs to be authenticated first. Mechanisms to store access conditions shall be avoided if possible.

- **Fail-safe defaults** defines that access is restricted by default and permitted only in specific conditions defined by the system protection scheme, e.g., after successful authentication. Furthermore, default settings for services shall be chosen in a way to provide maximum security. This corresponds to the “Secure by Default” paradigm [?].

- **Separation of privilege** is the principle that two conditions or more need to be satisfied before access is granted. In the context of the Zephyr project, this could encompass split keys [?].

- **Least privilege** describes an access model in which each user, program, and thread, shall have the smallest possible subset of permissions in the system required to perform their task. This positive security model aims to minimize the attack surface of the system.

- **Least common mechanism** specifies that mechanisms common to more than one user or process shall not be shared if not strictly required. The example given in [?] is a function that should be implemented as a shared library executed by each user and not as a supervisor procedure shared by all users.

- **Psychological acceptability** requires that security features are easy to use by the developers in order to ensure their usage and the correctness of its application.

In addition to these general principles, the following points are specific to the development of a secure RTOS:

- **Complementary Security/Defense in Depth**: do not rely on a single threat mitigation approach. In case of the complementary security approach, parts of the threat mitigation are
performed by the underlying platform. In case such mechanisms are not provided by the platform, or are not trusted, a defense in depth paradigm shall be used.

- **Less commonly used services off by default:** to reduce the exposure of the system to potential attacks, features or services shall not be enabled by default if they are only rarely used (a threshold of 80% is given in []). For the Zephyr project, this can be realized using the configuration management. Each functionality and module shall be represented as a configuration option and needs to be explicitly enabled. Then, all features, protocols, and drivers not required for a particular use case can be disabled. The user shall be notified if low-level options and APIs are enabled but not used by the application.

- **Change management:** to guarantee a traceability of changes to the system, each change shall follow a specified process including a change request, impact analysis, ratification, implementation, and validation phase. In each stage, appropriate documentation shall be provided. All commits shall be related to a bug report or change request in the issue tracker. Commits without a valid reference shall be denied.

### 10.3.3 Secure development knowledge

**Secure designer**

The Zephyr project must have at least one primary developer who knows how to design secure software.

This requires understanding the following design principles, including the 8 principles from []:

- economy of mechanism (keep the design as simple and small as practical, e.g., by adopting sweeping simplifications)
- fail-safe defaults (access decisions shall deny by default, and projects’ installation shall be secure by default)
- complete mediation (every access that might be limited must be checked for authority and be non-bypassable)
- open design (security mechanisms should not depend on attacker ignorance of its design, but instead on more easily protected and changed information like keys and passwords)
- separation of privilege (ideally, access to important objects should depend on more than one condition, so that defeating one protection system won’t enable complete access. For example, multi-factor authentication, such as requiring both a password and a hardware token, is stronger than single-factor authentication)
- least privilege (processes should operate with the least privilege necessary)
- least common mechanism (the design should minimize the mechanisms common to more than one user and depended on by all users, e.g., directories for temporary files)
- psychological acceptability (the human interface must be designed for ease of use - designing for “least astonishment” can help)
- limited attack surface (the set of the different points where an attacker can try to enter or extract data)
- input validation with whitelists (inputs should typically be checked to determine if they are valid before they are accepted; this validation should use whitelists (which only accept known-good values), not blacklists (which attempt to list known-bad values)).

**Vulnerability Knowledge**

A “primary developer” in a project is anyone who is familiar with the project’s code base, is comfortable making changes to it, and is acknowledged as such by most other participants in the project.
A primary developer would typically make a number of contributions over the past year (via code, documentation, or answering questions). Developers would typically be considered primary developers if they initiated the project (and have not left the project more than three years ago), have the option of receiving information on a private vulnerability reporting channel (if there is one), can accept commits on behalf of the project, or perform final releases of the project software. If there is only one developer, that individual is the primary developer.

At least one of the primary developers **must** know of common kinds of errors that lead to vulnerabilities in this kind of software, as well as at least one method to counter or mitigate each of them.

Examples (depending on the type of software) include SQL injection, OS injection, classic buffer overflow, cross-site scripting, missing authentication, and missing authorization. See the [CWE/SANS top 25](https://cwe.mitre.org/) or [OWASP Top 10](https://www.owasp.org/) for commonly used lists.

**Zephyr Security Subcommittee**

There shall be a “Zephyr Security Subcommittee”, responsible for enforcing this guideline, monitoring reviews, and improving these guidelines.

This team will be established according to the Zephyr Project charter.

### 10.3.4 Code Review

The Zephyr project shall use a code review system that all changes are required to go through. Each change shall be reviewed by at least one primary developer that is not the author of the change. This developer shall determine if this change affects the security of the system (based on their general understanding of security), and if so, shall request the developer with vulnerability knowledge, or the secure designer to also review the code. Any of these individuals shall have the ability to block the change from being merged into the mainline code until the security issues have been addressed.

### 10.3.5 Issues and Bug Tracking

The Zephyr project shall have an issue tracking system (such as GitHub) that can be used to record and track defects that are found in the system.

Because security issues are often sensitive, this issue tracking system shall have a field to indicate a security issue. Setting this field shall result in the issue only being visible to the Zephyr Security Subcommittee. In addition, there shall be a field to allow the Zephyr Security Subcommittee to add additional users that will have visibility to a given issue.

This embargo, or limited visibility, shall only be for a fixed duration, with a default being a project-decided value. However, because security considerations are often external to the Zephyr project itself, it may be necessary to increase this embargo time. The time necessary shall be clearly annotated in the issue itself.

The list of issues shall be reviewed at least once a month by the Zephyr Security Subcommittee. This review should focus on tracking the fixes, determining if any external parties need to be notified or involved, and determining when to lift the embargo on the issue. The embargo should **not** be lifted via an automated means, but the review team should avoid unnecessary delay in lifting issues that have been resolved.
10.4 Sensor Device Threat Model

This document describes a threat model for an IoT sensor device. Spelling out a threat model helps direct development effort, and can be used to help prioritize these efforts as well.

This device contains a sensor of some type (for example temperature, or a pressure in a pipe), which sends this data to an SoC running a microcontroller. This microcontroller connects to a cloud service, and relays this sensor data to this service. The cloud service is also able to send configuration data to the device, as well as software update images. A general diagram can be seen in Figure 1:

Fig. 3: Figure 1. Sensor General Diagram

In this sensor device, the sensor connects with the SoC via an SPI bus, and the SoC has a network interface that it uses to communicate with the cloud service. The particulars of these interfaces can impact the threat model in unexpected ways, and variants on this will need to be considered (for example, using a separate network interface SoC connected via some type of bus).

This model also focuses on communicating via the MQTT-over-TLS protocol, as this seems to be in wide use. See https://www.slideshare.net/kartben/iot-developer-survey-2018. As of this writing, the three major cloud IoT service providers, AWS IoT, Google Cloud IoT, and Microsoft Azure IoT all provide MQTT over TLS. Some feedback has suggested that some find difficulty with UDP protocols and routing issues on various networks.

10.4.1 Assets

One aspect of the threat model to consider are assets involved in the operation of the device. The following list enumerates the assets included in this model:

1. **The bootloader.** This is a small code/data image contained in on-device flash that is the first code to run. In order to establish a root of trust, this image must be immutable. This
model assumes that the SoC provides a mechanism to protect a region of the flash from future writes, and that this will be done after this image is programmed into the device, early in production [th-imboot].

2. **The application firmware image.** This asset consists of the remainder of the firmware run by the microcontroller. The distinction is made because this part of the image will need to be updated periodically as security vulnerabilities are discovered. Requirements for updates to this image are:
   a. The image shall only be replaced with an authorized image [th-authrepl].
   b. When an authorized replacement image is available, the update shall be done in a timely manner [th-timely-update].
   c. The image update shall be seen as atomic, meaning that when the image is run, the flash shall contain either the update image in its entirety, or the old image in its entirety [th-atomic-update].

3. **Root certificate list.** In order to authenticate the cloud service (server), the IoT device must have a list of root certificates that are allowed to sign the certificate on the server. For cloud-provider based services, this list will generally be provided by the service provider. Because the root certificates can expire, and possibly be revoked, this list will need to be periodically updated [th-root-certs], [th-root-check].

4. **Client secrets.** To authenticate the client to the service, the client must possess some kind of secret. This is generally a private key, usually either an RSA key or an EC private key. When establishing communication with the server, the device will use this secret either as part of the TLS establishment, or to sign a message used in the communication.

   This secret is generally generated by the service provider, or by software running elsewhere, and must be securely installed on the device. Policy may dictate that this secret be replaced periodically, which will require a way to update the client secret. Typically, the service will allow two or three active keys to allow this update to proceed while the old key is used.

   These secrets must be protected from read, and the smallest amount of code necessary shall have access to them. [th-secret-storage]

5. **Current date/time.** TLS certificate verification requires knowledge of the current date and time in order to determine if the current time falls within the certificate's current validity time. Also, token based client authentication will generally require the client to sign a message containing a time window that the token is valid. Certificate validation requires the device's notion of date and time to be accurate within a day or so. Token generation generally requires the time to be accurate within 5-10 minutes.

   It may be possible to approximate secure time by querying an external time server. Secure NTP is possibly beyond the capabilities of an IoT device. The main risks of having incorrect time are denial of service (the device rejects valid certificates), and the generation of tokens with invalid times. It could be possible to trick the device into generating tokens that are valid in the future, but the attacker would also have to spoof the server's certificate to be able to intercept this. [th-time]

6. **Sensor data.** The data received from the sensor itself, and delivered to the service shall be delivered without modification or tampering.

7. **Device configuration.** Various configuration data, such as the hostname of the service to connect to, the address of a time server, frequency and parameters of when sensor data is sent to the service, and other need to be kept by the device. This configuration data will need to be updated periodically as the configuration changes. Updates should be allowed only from authorized parties. [th-conf]

8. **Logs.** In order to assist with analysis of security issues, the device shall log information about security-pertinent events. IoT devices generally have limited storage, and as such, these logs need to be carefully selected. It may also be possible to send these log events
to the cloud service where they can be stored in a more resource-available environment. Types of events that should be logged include:

a. **Firmware image updates.** The system should log the download of new images, and when an image is successfully updated.

b. **Client secret changes.** Changes and new client secrets should be logged.

c. **Changes to the device configuration.**

[th-logs]

### 10.4.2 Communication

In addition to assets, the threat model also considers the locations where data or assets are communicated between entities of the system.

1. **Flash contents.** The flash device contains several regions. The contents of flash can be modified programmatically by the SoC's CPU.

   a. **The bootloader.** As described in the Assets section, the bootloader is a small section of the flash device containing the code initially run. This section shall be written early in the lifecycle of the device, and the flash device then configured to permanently disallow modification of this section. This configuration should also prevent modification via external interfaces, such as JTAG or SWD debuggers.

   The bootloader is responsible for verifying the signature of the application image as well as updating the application image from the update image when an update is needed.

   The bootloader shall verify the signature of the update image before installing it.

   The bootloader shall only accept an update image with a newer version number than the current image.

   b. **The application image.** The application image contains the code executed during normal operation of the device. Before running this image, the bootloader shall verify a digital signature of the image, to avoid running an image that has been tampered with. The flash/system shall be configured such that after the bootloader has completed, the CPU will be unable to write to the application image.

   c. **The update image.** This is an area of flash that holds a new version of the application image. This image will be downloaded and stored by the application during normal operation. When this has completed, the application can trigger a reboot, and the bootloader can install the new image.

   d. **Secret storage.** An area of the flash will be used to store client secrets. This area is written and read by a subset of the application image. The application shall be configured to protect this area from both reads and writes by code that does not need to have access to it, giving consideration to possible exploits found within a majority of the application code. Revealing the contents of the secrets would allow the attacker to spoof this device.

   Initial secrets shall be placed in the device during a provisioning activity, distinct from normal operation of the device. Later updates can be made under the direction of communication received over a secured channel to the service.

   e. **Configuration storage.** There shall be an area to store other configuration information. On resource-constrained devices, it is allowed for this to be stored in the same region as the secret storage, however, this adds additional code that has access to the secret storage area, and as such, more code that must be scrutinized.

   f. **Log storage.** The device may have an area of flash where log events can be written.
2. **Sensor/Actuator interface.** In this design, the sensor or actuator communicates with the SoC via a bus, such as SPI. The hardware design shall be made to make intercepting this bus difficult for an attack. Required techniques depend on the sensitivity and use of the sensor data, and can range from having the sensor mounted on the same PCB as the MCU to epoxy potting the entire device.

3. **Communication with cloud service.** Communication between the device, and the cloud service will be done over the general internet. As such, it shall be assumed that an attacker can arbitrarily intercept this channel and, for example, return spoofed DNS results or attempt man-in-the-middle attacks against communication with cloud services.

The device shall use TLS for all communication with the cloud service [th-all-tls]. The TLS stack shall be configured to use only cipher suites that are generally considered secure\(^2\), including forward secrecy. The communication shall be secured by the following:

a. **Cipher suite selection.** The device shall only allow communication with generally agreed secure cipher suites [th-tls-ciphers].

b. **Server certificate verification.** The server presented by the server shall be verified [th-root-check].

   i. **Naming.** The certificate shall name the host and service the cloud service server is providing. RFC6125 describes best practices for this. It is permissible for the device to require the certificate to be more restrictive than as described in this RFC, provided the service can use a certificate that can comply.

   ii. **Path validation.** The device shall verify that the certificate chain has a valid signature path from a root certificate contained within the device, to the certificate presented by the service. RFC4158 describes this is general. The device is permitted to require a more restricted path, provided the server certificate used complies with this restriction.

   iii. **Validity period.** The validity period of all presented certificates shall be checked against the device's best notion of the current time.

c. **Client authentication.** The client shall authenticate itself to the service using a secret known only to that particular device. There are several options, and the technique used is generally mandated by the particular service provider being used [th-tls-client-auth].

   i. **TLS client certificates.** The TLS protocol allows the client to present a certificate, and assert its knowledge of the secret described by that certificate. Generally, these certificates will be stored within the service provider. These certificates can be self-signed, or signed by a CA. Since the service provider maintains a list of valid certificates (mapping them to a device identity), having these certificates signed by a CA does not add any additional security, but may be useful in the management of these certificates.

   ii. **Token-based authentication.** It is also possible for the client to authenticate itself using the password field of the MQTT CONNECT packet. However, the secret itself must not be transmitted in this packet. Instead, a token-based protocol, such as RFC7519’s JSON Web Token (JWT) can be used. These tokens will generally have a small validity period (e.g. 1 hour), to prevent them from being reused if they are intercepted. The token shall not be sent until the device has verified the identity of the server.

d. **Random/Entropy source.** Cryptographic communication requires the generation of secure pseudorandom numbers. The device shall use a modern, accepted cryptographic random-bit generator to generate these random numbers. It shall use either a Non-Deterministic Random Bit Generator (True RBG) implemented in hardware within the SoC, or a Deterministic Random Bit Generator (Pseudo RBG) seeded by

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\(^2\) As new exploits are discovered, what is considered secure can change. Organizations such as [https://www.ssllabs.com/](https://www.ssllabs.com/) provide information on current ideas of how TLS must be configured to be secure.
an entropy source within the SoC. Please see NIST SP 800-90A for information on approved RBGs and NIST SP 800-90B for information on testing a device's entropy source [th-entropy].

4. **Communication with the time service.** Ideally, the device shall contain hardware that maintains a secure time. However, most SoCs in use do not have support for this, and it will be necessary to consult an external time service. RFC4330 and referenced RFCs describe the Simple Network Time Protocol that can be used to query the current time from a network time server.

5. **Device lifecycle.** An IoT device will have a lifecycle from production to destruction and disposal of the device. Aspects of this lifecycle that impact security include initial provisioning, normal operation, re-provisioning, and destruction.

   a. **Initial provisioning.** During the initial provisioning stage, it is necessary to program the bootloader, an initial application image, a device secret, and initial configuration data [th-initial-provision]. In addition, the bootloader flash protection shall be installed. Of this information, only the device secret needs to differ per device. This secret shall be securely maintained, and destroyed in all locations outside of the device once it has been programmed [th-initial-secret].

   b. **Normal operation.** Normal operation includes the behavior described by the rest of this document.

   c. **Re-provisioning.** Sometimes it is necessary to re-provision a device, such as for a different application. One way to do this is to keep the same device secret, and replace the configuration data, as well as the cloud service data associated with the device. It is also possible to program a new device secret, but if this is done it shall be done securely, and the new secret destroyed externally once programmed into the device [th-reprovision].

   d. **Destruction.** To prevent the device secret from being used to spoof the device, upon decommissioning, the secret for a particular device shall be rendered ineffective [th-destruction]. Possibilities include:

      - i. Hardware destruction of the device.
      - ii. Securely wiping the flash area containing the secret.
      - iii. Removing the device identity and certificate from the service.

10.4.3 **Other Considerations**

In addition to the above, network connected devices generally will need a way to configure them to connect to the network environment they are placed in. There are numerous ways of doing this, and it is important for these configuration methods to not circumvent the security requirements described above.

10.4.4 **Threats**

10.4.5 **Notes**

10.5 **Hardening Tool**

Before launching a product, it’s crucial to ensure that your software is as secure as possible. This process, known as “hardening”, involves strengthening the security of a system to protect it from potential threats and vulnerabilities.

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3 Note that merely erasing this flash area is unlikely to be sufficient.
At a high-level, hardening a Zephyr application can be seen as a two-fold process:

1. Disabling features and compilation flags that might lead to security vulnerabilities (ex. making sure that no “experimental” features are being used, disabling features typically used for debugging purposes such as assertions, shell, etc.).

2. Enabling optional features that can lead to improve security (ex. stack sentinel, hardware stack protection, etc.). Some of these features might be hardware-dependent.

To simplify this process, Zephyr offers a **hardening tool** designed to analyze an application’s configuration against a set of hardening preferences defined by the **Security Working Group**. The tool looks at the KConfig options in the build target and provides tailored suggestions and recommendations to adjust security-related options.

### 10.5.1 Usage

Using west:

```bash
west build -b reel_board samples/hello_world
west build -t hardenconfig
```

Using CMake and ninja:

```bash
# Use cmake to configure a Ninja-based build system:
cmake -Bbuild -GNinja -DBOARD=reel_board samples/hello_world

# Now run the build tool on the generated build system:
ninja -Cbuild hardenconfig
```

The output should be similar to the table below. For each configuration option set to a value that could lead to a security vulnerability, the table will propose a recommended value that should be used instead.

<table>
<thead>
<tr>
<th>name</th>
<th>current</th>
<th>recommended</th>
<th>check result</th>
</tr>
</thead>
<tbody>
<tr>
<td>CONFIG_BOOT_BANNER</td>
<td>y</td>
<td>n</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_BUILD_OUTPUT_STRIPPED</td>
<td>n</td>
<td>y</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_FAULT_DUMP</td>
<td>2</td>
<td>0</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_HW_STACK_PROTECTION</td>
<td>n</td>
<td>y</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_MPU_STACK_GUARD</td>
<td>n</td>
<td>y</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG.Override_FRAME_POINTER_DEFAULT</td>
<td>n</td>
<td>y</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_STACK_SENTINEL</td>
<td>n</td>
<td>y</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_EARLY_CONSOLE</td>
<td>y</td>
<td>n</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_PRINTK</td>
<td>y</td>
<td>n</td>
<td>FAIL</td>
</tr>
</tbody>
</table>

### 10.6 Vulnerabilities

This page collects all of the vulnerabilities that are discovered and fixed in each release. It will also often have more details than is available in the releases. Some vulnerabilities are deemed to be sensitive, and will not be publicly discussed until there is sufficient time to fix them. Because the release notes are locked to a version, the information here can be updated after the embargo is lifted.

#### 10.6.1 CVE-2017
**CVE-2017-14199**

Buffer overflow in `getaddrinfo()`.

- CVE-2017-14199
- Zephyr project bug tracker ZEPSEC-12
- PR6158 fix for 1.11.0

**CVE-2017-14201**

The shell DNS command can cause unpredictable results due to misuse of stack variables. Use After Free vulnerability in the Zephyr shell allows a serial or telnet connected user to cause denial of service, and possibly remote code execution.

This has been fixed in release v1.14.0.

- CVE-2017-14201
- Zephyr project bug tracker ZEPSEC-17
- PR13260 fix for v1.14.0

**CVE-2017-14202**

The shell implementation does not protect against buffer overruns resulting in unpredictable behavior. Improper Restriction of Operations within the Bounds of a Memory Buffer vulnerability in the shell component of Zephyr allows a serial or telnet connected user to cause a crash, possibly with arbitrary code execution.

This has been fixed in release v1.14.0.

- CVE-2017-14202
- Zephyr project bug tracker ZEPSEC-18
- PR13048 fix for v1.14.0

**10.6.2 CVE-2019**

**CVE-2019-9506**

The Bluetooth BR/EDR specification up to and including version 5.1 permits sufficiently low encryption key length and does not prevent an attacker from influencing the key length negotiation. This allows practical brute-force attacks (aka “KNOB”) that can decrypt traffic and inject arbitrary ciphertext without the victim noticing.

- CVE-2019-9506
- Zephyr project bug tracker ZEPSEC-20
- PR18702 fix for v1.14.0
- PR18659 fix for v2.0.0
10.6.3 CVE-2020

CVE-2020-10019
Buffer Overflow vulnerability in USB DFU of zephyr allows a USB connected host to cause possible remote code execution.
This has been fixed in releases v1.14.2, v2.2.0, and v2.1.1.

• CVE-2020-10019
• Zephyr project bug tracker ZEPSEC-25
• PR23460 fix for 1.14.x
• PR23457 fix for 2.1.x
• PR23190 fix in 2.2.0

CVE-2020-10021
Out-of-bounds write in USB Mass Storage with unaligned sizes
Out-of-bounds Write in the USB Mass Storage memoryWrite handler with unaligned Sizes.
See NCC-ZEP-024, NCC-ZEP-025, NCC-ZEP-026
This has been fixed in releases v1.14.2, and v2.2.0.

• CVE-2020-10021
• Zephyr project bug tracker ZEPSEC-26
• PR23455 fix for v1.14.2
• PR23456 fix for the v2.1 branch
• PR23240 fix for v2.2.0

CVE-2020-10022
UpdateHub Module Copies a Variable-Size Hash String Into a Fixed-Size Array
A malformed JSON payload that is received from an UpdateHub server may trigger memory corruption in the Zephyr OS. This could result in a denial of service in the best case, or code execution in the worst case.
See NCC-ZEP-016
This has been fixed in the below pull requests for main, branch from v2.1.0, and branch from v2.2.0.

• CVE-2020-10022
• Zephyr project bug tracker ZEPSEC-28
• PR24154 fix for main
• PR24065 fix for branch from v2.1.0
• PR24066 fix for branch from v2.2.0
CVE-2020-10023

Shell Subsystem Contains a Buffer Overflow Vulnerability In shell_spaces_trim

The shell subsystem contains a buffer overflow, whereby an adversary with physical access to the device is able to cause a memory corruption, resulting in denial of service or possibly code execution within the Zephyr kernel.

See NCC-ZEP-019

This has been fixed in releases v1.14.2, v2.2.0, and in a branch from v2.1.0,

- CVE-2020-10023
- Zephyr project bug tracker ZEPSEC-29
- PR23646 fix for v1.14.2
- PR23649 fix for branch from v2.1.0
- PR23304 fix for v2.2.0

CVE-2020-10024

ARM Platform Uses Signed Integer Comparison When Validating Syscall Numbers

The arm platform-specific code uses a signed integer comparison when validating system call numbers. An attacker who has obtained code execution within a user thread is able to elevate privileges to that of the kernel.

See NCC-ZEP-001

This has been fixed in releases v1.14.2, and v2.2.0, and in a branch from v2.1.0,

- CVE-2020-10024
- Zephyr project bug tracker ZEPSEC-30
- PR23535 fix for v1.14.2
- PR23498 fix for branch from v2.1.0
- PR23323 fix for v2.2.0

CVE-2020-10027

ARC Platform Uses Signed Integer Comparison When Validating Syscall Numbers

An attacker who has obtained code execution within a user thread is able to elevate privileges to that of the kernel.

See NCC-ZEP-001

This has been fixed in releases v1.14.2, and v2.2.0, and in a branch from v2.1.0,

- CVE-2020-10027
- Zephyr project bug tracker ZEPSEC-35
- PR23500 fix for v1.14.2
- PR23499 fix for branch from v2.1.0
- PR23328 fix for v2.2.0
**CVE-2020-10028**

Multiple Syscalls In GPIO Subsystem Performs No Argument Validation

Multiple syscalls with insufficient argument validation

See NCC-ZEP-006

This has been fixed in releases v1.14.2, and v2.2.0, and in a branch from v2.1.0.

- CVE-2020-10028
- Zephyr project bug tracker ZEPSEC-32
- PR23733 fix for v1.14.2
- PR23737 fix for branch from v2.1.0
- PR23308 fix for v2.2.0 (gpio patch)

**CVE-2020-10058**

Multiple Syscalls In kscan Subsystem Performs No Argument Validation

Multiple syscalls in the Kscan subsystem perform insufficient argument validation, allowing code executing in userspace to potentially gain elevated privileges.

See NCC-ZEP-006

This has been fixed in a branch from v2.1.0, and release v2.2.0.

- CVE-2020-10058
- Zephyr project bug tracker ZEPSEC-34
- PR23748 fix for branch from v2.1.0
- PR23308 fix for v2.2.0 (kscan patch)

**CVE-2020-10059**

UpdateHub Module Explicitly Disables TLS Verification

The UpdateHub module disables DTLS peer checking, which allows for a man in the middle attack. This is mitigated by firmware images requiring valid signatures. However, there is no benefit to using DTLS without the peer checking.

See NCC-ZEP-018

This has been fixed in a PR against Zephyr main.

- CVE-2020-10059
- Zephyr project bug tracker ZEPSEC-36
- PR24954 fix on main (to be fixed in v2.3.0)
- PR24954 fix v2.1.0
- PR24954 fix v2.2.0
CVE-2020-10060

UpdateHub Might Dereference An Uninitialized Pointer

In updatehub_probe, right after JSON parsing is complete, objects[1] is accessed from the output structure in two different places. If the JSON contained less than two elements, this access would reference uninitialized stack memory. This could result in a crash, denial of service, or possibly an information leak.

Recommend disabling updatehub until such a time as a fix can be made available.

See NCC-ZEP-030

This has been fixed in a PR against Zephyr main.

- CVE-2020-10060
- Zephyr project bug tracker ZEPSEC-37
- PR27865 fix on main (to be fixed in v2.4.0)
- PR27865 fix for v2.3.0
- PR27865 fix for v2.2.0
- PR27865 fix for v2.1.0

CVE-2020-10061

Error handling invalid packet sequence

Improper handling of the full-buffer case in the Zephyr Bluetooth implementation can result in memory corruption.

This has been fixed in branches for v1.14.0, v2.2.0, and will be included in v2.3.0.

- CVE-2020-10061
- Zephyr project bug tracker ZEPSEC-75
- PR23516 fix for v2.3 (split driver)
- PR23517 fix for v2.3 (legacy driver)
- PR23091 fix for branch from v1.14.0
- PR23547 fix for branch from v2.2.0

CVE-2020-10062

Packet length decoding error in MQTT

CVE: An off-by-one error in the Zephyr project MQTT packet length decoder can result in memory corruption and possible remote code execution. NCC-ZEP-031

The MQTT packet header length can be 1 to 4 bytes. An off-by-one error in the code can result in this being interpreted as 5 bytes, which can cause an integer overflow, resulting in memory corruption.

This has been fixed in main for v2.3.

- CVE-2020-10062
- Zephyr project bug tracker ZEPSEC-84
- commit 11b7a37d for v2.3
- NCC-ZEP report (NCC-ZEP-031)
CVE-2020-10063

Remote Denial of Service in CoAP Option Parsing Due To Integer Overflow

A remote adversary with the ability to send arbitrary CoAP packets to be parsed by Zephyr is able to cause a denial of service.

This has been fixed in main for v2.3.

- CVE-2020-10063
- Zephyr project bug tracker ZEPSEC-55
- PR24435 fix in main for v2.3
- PR24531 fix for branch from v2.2
- PR24535 fix for branch from v2.1
- PR24530 fix for branch from v1.14
- NCC-ZEP report (NCC-ZEP-032)

CVE-2020-10064

Improper Input Frame Validation in ieee802154 Processing

- CVE-2020-10064
- Zephyr project bug tracker ZEPSEC-65
- PR24971 fix for v2.4
- PR33451 fix for v1.4

CVE-2020-10065

OOB Write after not validating user-supplied length (<= 0xffff) and copying to fixed-size buffer (default: 77 bytes) for HCI_ACL packets in bluetooth HCI over SPI driver.

- CVE-2020-10065
- Zephyr project bug tracker ZEPSEC-66
- This issue has not been fixed.

CVE-2020-10066

Incorrect Error Handling in Bluetooth HCI core

In hci_cmd_done, the buf argument being passed as null causes nullpointer dereference.

- CVE-2020-10066
- Zephyr project bug tracker ZEPSEC-67
- PR24902 fix for v2.4
- PR25089 fix for v1.4
CVE-2020-10067

Integer Overflow In is_in_region Allows User Thread To Access Kernel Memory

A malicious userspace application can cause a integer overflow and bypass security checks performed by system call handlers. The impact would depend on the underlying system call and can range from denial of service to information leak to memory corruption resulting in code execution within the kernel.

See NCC-ZEP-005

This has been fixed in releases v1.14.2, and v2.2.0.

- CVE-2020-10067
- Zephyr project bug tracker ZEPSEC-27
- PR23653 fix for v1.14.2
- PR23654 fix for the v2.1 branch
- PR23239 fix for v2.2.0

CVE-2020-10068

Zephyr Bluetooth DLE duplicate requests vulnerability

In the Zephyr project Bluetooth subsystem, certain duplicate and back-to-back packets can cause incorrect behavior, resulting in a denial of service.

This has been fixed in branches for v1.14.0, v2.2.0, and will be included in v2.3.0.

- CVE-2020-10068
- Zephyr project bug tracker ZEPSEC-78
- PR23707 fix for v2.3 (split driver)
- PR23708 fix for v2.3 (legacy driver)
- PR23091 fix for branch from v1.14.0
- PR23964 fix for v2.2.0

CVE-2020-10069

Zephyr Bluetooth unchecked packet data results in denial of service

An unchecked parameter in bluetooth data can result in an assertion failure, or division by zero, resulting in a denial of service attack.

This has been fixed in branches for v1.14.0, v2.2.0, and will be included in v2.3.0.

- CVE-2020-10069
- Zephyr project bug tracker ZEPSEC-81
- PR23705 fix for v2.3 (split driver)
- PR23706 fix for v2.3 (legacy driver)
- PR23091 fix for branch from v1.14.0
- PR23963 fix for branch from v2.2.0
CVE-2020-10070

MQTT buffer overflow on receive buffer

In the Zephyr Project MQTT code, improper bounds checking can result in memory corruption and possibly remote code execution. NCC-ZEP-031

When calculating the packet length, arithmetic overflow can result in accepting a receive buffer larger than the available buffer space, resulting in user data being written beyond this buffer.

This has been fixed in main for v2.3.
  - CVE-2020-10070
  - Zephyr project bug tracker ZEPSEC-85
  - commit 0b39cbf3 for v2.3
  - NCC-ZEP report (NCC-ZEP-031)

CVE-2020-10071

Insufficient publish message length validation in MQTT

The Zephyr MQTT parsing code performs insufficient checking of the length field on publish messages, allowing a buffer overflow and potentially remote code execution. NCC-ZEP-031

This has been fixed in main for v2.3.
  - CVE-2020-10071
  - Zephyr project bug tracker ZEPSEC-86
  - commit 989c4713 fix for v2.3
  - NCC-ZEP report (NCC-ZEP-031)

CVE-2020-10072

All threads can access all socket file descriptors

There is no management of permissions to network socket API file descriptors. Any thread running on the system may read/write a socket file descriptor knowing only the numerical value of the file descriptor.
  - CVE-2020-10072
  - Zephyr project bug tracker ZEPSEC-87
  - PR25804 fix for v2.4
  - PR27176 fix for v1.4

CVE-2020-10136

IP-in-IP protocol routes arbitrary traffic by default zephyrproject

  - CVE-2020-10136
  - Zephyr project bug tracker ZEPSEC-64
CVE-2020-13598

FS: Buffer Overflow when enabling Long File Names in FAT_FS and calling fs_stat
Performing fs_stat on a file with a filename longer than 12 characters long will cause a buffer overflow.

- CVE-2020-13598
- Zephyr project bug tracker ZEPSEC-88
- PR25852 fix for v2.4
- PR28782 fix for v2.3
- PR33577 fix for v1.4

CVE-2020-13599

Security problem with settings and littlefs
When settings is used in combination with littlefs all security related information can be extracted from the device using MCUmgr and this could be used e.g. in bt-mesh to get the device key, network key, app keys from the device.

- CVE-2020-13599
- Zephyr project bug tracker ZEPSEC-57
- PR26083 fix for v2.4

CVE-2020-13600

Malformed SPI in response for eswifi can corrupt kernel memory

- CVE-2020-13600
- Zephyr project bug tracker ZEPSEC-91
- PR26712 fix for v2.4

CVE-2020-13601

Possible read out of bounds in dns read

- CVE-2020-13601
- Zephyr project bug tracker ZEPSEC-92
- PR27774 fix for v2.4
- PR30503 fix for v1.4

CVE-2020-13602

Remote Denial of Service in LwM2M do_write_op_tlv
In the Zephyr LwM2M implementation, malformed input can result in an infinite loop, resulting in a denial of service attack.

- CVE-2020-13602
- Zephyr project bug tracker ZEPSEC-56
• PR26571 fix for v2.4
• PR33578 fix for v1.4

CVE-2020-13603

Possible overflow in mempool
• Zephyr offers pre-built ‘malloc’ wrapper function instead.
• The ‘malloc’ function is wrapper for the ‘sys_mem_pool_alloc’ function
• sys_mem_pool_alloc allocates ‘size + WB_UP(sizeof(struct sys_mem_pool_block))’ in an un-safe manner.
• Asking for very large size values leads to internal integer wrap-around.
• Integer wrap-around leads to successful allocation of very small memory.
• For example: calling malloc(0xffffffff) leads to successful allocation of 7 bytes.
• That leads to heap overflow.
• CVE-2020-13603
• Zephyr project bug tracker ZEPSEC-111
• PR31796 fix for v2.4
• PR32808 fix for v1.4

10.6.4 CVE-2021

CVE-2021-3319

DOS: Incorrect 802154 Frame Validation for Omitted Source / Dest Addresses
Improper processing of omitted source and destination addresses in ieee802154 frame validation (ieee802154_validate_frame)
This has been fixed in main for v2.5.0
• CVE-2020-3319
• Zephyr project bug tracker GHSA-94jg-2p6q-5364
• PR31908 fix for main

CVE-2021-3320

Mismatch between validation and handling of 802154 ACK frames, where ACK frames are con-sidered during validation, but not during actual processing, leading to a type confusion.
• CVE-2020-3320
• PR31908 fix for main

CVE-2021-3321

Incomplete check of minimum IEEE 802154 fragment size leading to an integer underflow.
• CVE-2020-3321
• Zephyr project bug tracker ZEPSEC-114
• PR33453 fix for v2.4

CVE-2021-3323

Integer Underflow in 6LoWPAN IPHC Header Uncompression
This has been fixed in main for v2.5.0

• CVE-2020-3323
  • Zephyr project bug tracker GHSA-89j6-qpxf-pfpc
  • PR 31971 fix for main

CVE-2021-3430

Assertion reachable with repeated LL_CONNECTION_PARAM_REQ.
This has been fixed in main for v2.6.0

• CVE-2021-3430
  • Zephyr project bug tracker GHSA-46h3-hjcg-2jjr
  • PR 33272 fix for main
  • PR 33369 fix for 2.5
  • PR 33759 fix for 1.14.2

CVE-2021-3431

BT: Assertion failure on repeated LL_FEATURE_REQ
This has been fixed in main for v2.6.0

• CVE-2021-3431
  • Zephyr project bug tracker GHSA-7548-5m6f-mqv9
  • PR 33340 fix for main
  • PR 33369 fix for 2.5

CVE-2021-3432

Invalid interval in CONNECT_IND leads to Division by Zero
This has been fixed in main for v2.6.0

• CVE-2021-3432
  • Zephyr project bug tracker GHSA-7364-p4wc-8mj4
  • PR 33278 fix for main
  • PR 33369 fix for 2.5
CVE-2021-3433

BT: Invalid channel map in CONNECT_IND results to Deadlock
This has been fixed in main for v2.6.0
- CVE-2021-3433
- Zephyr project bug tracker GHSA-3c2f-w4v6-qxrp
- PR 33278 fix for main
- PR 33369 fix for 2.5

CVE-2021-3434

L2CAP: Stack based buffer overflow in le_ecred_conn_req()
This has been fixed in main for v2.6.0
- CVE-2021-3434
- Zephyr project bug tracker GHSA-8w87-6rfp-cfrm
- PR 33305 fix for main
- PR 33419 fix for 2.5
- PR 33418 fix for 1.14.2

CVE-2021-3435

L2CAP: Information leakage in le_ecred_conn_req()
This has been fixed in main for v2.6.0
- CVE-2021-3435
- Zephyr project bug tracker GHSA-xhg3-gvj6-4rqh
- PR 33305 fix for main
- PR 33419 fix for 2.5
- PR 33418 fix for 1.14.2

CVE-2021-3436

Bluetooth: Possible to overwrite an existing bond during keys distribution phase when the identity address of the bond is known
During the distribution of the identity address information we don’t check for an existing bond with the same identity address. This means that a duplicate entry will be created in RAM while the newest entry will overwrite the existing one in persistent storage.
This has been fixed in main for v2.6.0
- CVE-2021-3436
- Zephyr project bug tracker GHSA-j76f-35mc-4h63
- PR 33266 fix for main
- PR 33432 fix for 2.5
- PR 33433 fix for 2.4
• PR 33718 fix for 1.14.2

CVE-2021-3454

Truncated L2CAP K-frame causes assertion failure
For example, sending L2CAP K-frame where SDU length field is truncated to only one byte, causes
assertion failure in previous releases of Zephyr. This has been fixed in master by commit 0ba9437
but has not yet been backported to older release branches.
This has been fixed in main for v2.6.0
  • CVE-2021-3454
  • Zephyr project bug tracker GHSA-fx88-6c29-vrp3
  • PR 32588 fix for main
  • PR 33513 fix for 2.5
  • PR 33514 fix for 2.4

CVE-2021-3455

Disconnecting L2CAP channel right after invalid ATT request leads freeze
When Central device connects to peripheral and creates L2CAP connection for Enhanced ATT,
sending some invalid ATT request and disconnecting immediately causes freeze.
This has been fixed in main for v2.6.0
  • CVE-2021-3455
  • Zephyr project bug tracker GHSA-7g38-3x9v-v7vp
  • PR 35597 fix for main
  • PR 36104 fix for 2.5
  • PR 36105 fix for 2.4

CVE-2021-3510

Zephyr JSON decoder incorrectly decodes array of array
When using JSON_OBJ_DESCR_ARRAY_ARRAY, the subarray is has the token type
JSON_TOK_LIST_START, but then assigns to the object part of the union. arr_parse then
takes the offset of the array-object (which has nothing todo with the list) treats it as relative to
the parent object, and stores the length of the subarray in there.
This has been fixed in main for v2.7.0
  • CVE-2021-3510
  • Zephyr project bug tracker GHSA-289f-7mw3-2qf4
  • PR 36340 fix for main
  • PR 37816 fix for 2.6
CVE-2021-3581

HCI data not properly checked leads to memory overflow in the Bluetooth stack

In the process of setting SCAN_RSP through the HCI command, the Zephyr Bluetooth protocol stack did not effectively check the length of the incoming HCI data. Causes memory overflow, and then the data in the memory is overwritten, and may even cause arbitrary code execution.

This has been fixed in main for v2.6.0

- CVE-2021-3581
- Zephyr project bug tracker GHSA-8q65-5qgf-fmw5
- PR 35935 fix for main
- PR 35984 fix for 2.5
- PR 35985 fix for 2.4
- PR 35985 fix for 1.14

CVE-2021-3625

Buffer overflow in Zephyr USB DFU DNLOAD

This has been fixed in main for v2.6.0

- CVE-2021-3625
- Zephyr project bug tracker GHSA-c3gr-hgvr-f363
- PR 36694 fix for main

CVE-2021-3835

Buffer overflow in Zephyr USB device class

This has been fixed in main for v3.0.0

- CVE-2021-3835
- Zephyr project bug tracker GHSA-fm6v-8625-99jf
- PR 42093 fix for main
- PR 42167 fix for 2.7

CVE-2021-3861

Buffer overflow in the RNDIS USB device class

This has been fixed in main for v3.0.0

- CVE-2021-3861
- Zephyr project bug tracker GHSA-hvfp-w4h8-gxvj
- PR 39725 fix for main
CVE-2021-3966

Usb bluetooth device ACL read cb buffer overflow
This has been fixed in main for v3.0.0
- Zephyr project bug tracker GHSA-hfxq-3w6x-fv2m
- PR 42093 fix for main
- PR 42167 fix for v2.7.0

10.6.5 CVE-2022

CVE-2022-0553

Possible to retrieve unencrypted firmware image
This has been fixed in main for v3.0.0
- Zephyr project bug tracker GHSA-wrj2-9vj9-rrcp
- PR 42424 fix for main

CVE-2022-1041

Out-of-bound write vulnerability in the Bluetooth Mesh core stack can be triggered during provisioning
This has been fixed in main for v3.1.0
- Zephyr project bug tracker GHSA-p449-9hv9-pj38
- PR 45136 fix for main
- PR 45188 fix for v3.0.0
- PR 45187 fix for v2.7.0

CVE-2022-1042

Out-of-bound write vulnerability in the Bluetooth Mesh core stack can be triggered during provisioning
This has been fixed in main for v3.1.0
- Zephyr project bug tracker GHSA-j7v7-w73r-mm5x
- PR 45066 fix for main
- PR 45135 fix for v3.0.0
- PR 45134 fix for v2.7.0

CVE-2022-1841

Out-of-Bound Write in tcp_flags
This has been fixed in main for v3.1.0
- Zephyr project bug tracker GHSA-5c3j-p8cr-2pgh
- PR 45796 fix for main
**CVE-2022-2741**

can: denial-of-service can be triggered by a crafted CAN frame

This has been fixed in main for v3.2.0

  - Zephyr project bug tracker GHSA-hx5v-j59q-c3j8
  - PR 47903 fix for main
  - PR 47957 fix for v3.1.0
  - PR 47958 fix for v3.0.0
  - PR 47959 fix for v2.7.0

**CVE-2022-2993**

bt: host: Wrong key validation check

This has been fixed in main for v3.2.0

  - Zephyr project bug tracker GHSA-3286-jgjx-8cvr
  - PR 48733 fix for main

**CVE-2022-3806**

DoS: Invalid Initialization in le_read_buffer_size_complete()

  - Zephyr project bug tracker GHSA-w525-fm68-ppq3

**10.6.6 CVE-2023**

**CVE-2023-0396**

Buffer Overreads in Bluetooth HCI

  - Zephyr project bug tracker GHSA-8rpp-6vxq-pqg3

**CVE-2023-0397**

DoS: Invalid Initialization in le_read_buffer_size_complete()

  - Zephyr project bug tracker GHSA-wc2h-h868-q7hj

This has been fixed in main for v3.3.0

  - PR 54905 fix for main
  - PR 47957 fix for v3.2.0
  - PR 47958 fix for v3.1.0
  - PR 47959 fix for v2.7.4
CVE-2023-0779
net: shell: Improper input validation

• Zephyr project bug tracker GHSA-9xj8-6989-r549
This has been fixed in main for v3.3.0
  • PR 54371 fix for main
  • PR 54380 fix for v3.2.0
  • PR 54381 fix for v2.7.4

CVE-2023-1901
HCI send_sync Dangling Semaphore Reference Re-use

• Zephyr project bug tracker GHSA-xvvm-8mcm-9cq3
This has been fixed in main for v3.4.0
  • PR 56709 fix for main

CVE-2023-1902
HCI Connection Creation Dangling State Reference Re-use

• Zephyr project bug tracker GHSA-fx9g-8fr2-q899
This has been fixed in main for v3.4.0
  • PR 56709 fix for main

CVE-2023-3725
Potential buffer overflow vulnerability in the Zephyr CANbus subsystem.

• Zephyr project bug tracker GHSA-2g3m-p6c7-8rr3
This has been fixed in main for v3.5.0
  • PR 61502 fix for main
  • PR 61518 fix for 3.4
  • PR 61517 fix for 3.3
  • PR 61516 fix for 2.7

CVE-2023-4257
Unchecked user input length in the Zephyr WiFi shell module can cause buffer overflows.

• Zephyr project bug tracker GHSA-853q-q69w-gf5j
This has been fixed in main for v3.5.0
  • PR 605377 fix for main
  • PR 61383 fix for 3.4
CVE-2023-4258

bt: mesh: vulnerability in provisioning protocol implementation on provisionee side

- Zephyr project bug tracker GHSA-m34c-cp63-rwh7

This has been fixed in main for v3.5.0

- PR 59467 fix for main
- PR 60078 fix for 3.4
- PR 60079 fix for 3.3

CVE-2023-4259

Buffer overflow vulnerabilities in the Zephyr eS-WiFi driver

- Zephyr project bug tracker GHSA-gghm-c696-f4j4

This has been fixed in main for v3.5.0

- PR 63074 fix for main
- PR 63750 fix for main

CVE-2023-4260

Off-by-one buffer overflow vulnerability in the Zephyr FS subsystem

- Zephyr project bug tracker GHSA-gj27-862r-55wh

This has been fixed in main for v3.5.0

- PR 63079 fix for main

CVE-2023-4262

Potential buffer overflow vulnerabilities in the Zephyr Mgmt subsystem

- Zephyr project bug tracker GHSA-56p9-5p3v-hhrc

This issue has not been fixed.

CVE-2023-4263

Potential buffer overflow vulnerability in the Zephyr IEEE 802.15.4 nRF 15.4 driver.

- Zephyr project bug tracker GHSA-rf6q-rhhp-pqhf

This has been fixed in main for v3.5.0

- PR 60528 fix for main
- PR 61384 fix for 3.4
- PR 61216 fix for 2.7
CVE-2023-4264
Potential buffer overflow vulnerabilities in the Zephyr Bluetooth subsystem
  • Zephyr project bug tracker GHSA-rgx6-3w4j-gf5j
This has been fixed in main for v3.5.0
  • PR 58834 fix for main
  • PR 60465 fix for main
  • PR 61845 fix for main
  • PR 61385 fix for 3.4

CVE-2023-4265
Two potential buffer overflow vulnerabilities in Zephyr USB code
  • Zephyr project bug tracker GHSA-4vgv-5r6q-r6xh
This has been fixed in main for v3.4.0
  • PR 59157 fix for main
  • PR 59018 fix for main

CVE-2023-4424
bt: hci: DoS and possible RCE
  • Zephyr project bug tracker GHSA-j4qm-xgpf-qjw3
This has been fixed in main for v3.5.0
  • PR 61651 fix for main
  • PR 61696 fix for 3.4
  • PR 61695 fix for 3.3
  • PR 61694 fix for 2.7

CVE-2023-5055
L2CAP: Possible Stack based buffer overflow in le_ecred_reconf_req()
  • Zephyr project bug tracker GHSA-wr8r-7f8x-24jj
This has been fixed in main for v3.5.0
  • PR 62381 fix for main

CVE-2023-5139
Potential buffer overflow vulnerability in the Zephyr STM32 Crypto driver.
  • Zephyr project bug tracker GHSA-rhrc-pcxp-4453
This has been fixed in main for v3.5.0
  • PR 61839 fix for main
CVE-2023-5184
Potential signed to unsigned conversion errors and buffer overflow vulnerabilities in the Zephyr IPM driver

- Zephyr project bug tracker GHSA-8x3p-q3r5-xh9g

This has been fixed in main for v3.5.0
- PR 63069 fix for main

CVE-2023-5563
The SJA1000 CAN controller driver backend automatically attempts to recover from a bus-off event when built with CONFIG_CAN_AUTO_BUS_OFF_RECOVERY=y. This results in calling k_sleep() in IRQ context, causing a fatal exception.

- Zephyr project bug tracker GHSA-98mc-rj7w-7rpv

This has been fixed in main for v3.5.0
- PR 63713 fix for main
- PR 63718 fix for 3.4
- PR 63717 fix for 3.3

CVE-2023-5753
Potential buffer overflow vulnerabilities in the Zephyr Bluetooth subsystem source code when asserts are disabled.

- Zephyr project bug tracker GHSA-hmpr-px56-rvww

This has been fixed in main for v3.5.0
- PR 63605 fix for main

CVE-2023-5779
Out of bounds issue in remove_rx_filter in multiple can drivers.

- Zephyr project bug tracker GHSA-7cmj-963q-jj47

This has been fixed in main for v3.6.0
- PR 64399 fix for main
- PR 64416 fix for 3.5
- PR 64415 fix for 3.4
- PR 64427 fix for 3.3
- PR 64431 fix for 2.7

CVE-2023-6249
Signed to unsigned conversion problem in esp32_ipm_send may lead to buffer overflow

- Zephyr project bug tracker GHSA-32f5-3p9h-2rqc

This has been fixed in main for v3.6.0
• PR 65546 fix for main

**CVE-2023-6749**

Potential buffer overflow due unchecked data coming from user input in settings shell.

• Zephyr project bug tracker GHSA-757h-rw37-66hw

This has been fixed in main for v3.6.0

• PR 66451 fix for main

• PR 66584 fix for 3.5

**CVE-2023-6881**

Potential buffer overflow vulnerability in Zephyr fuse file system.

• Zephyr project bug tracker GHSA-mh67-4h3q-p437

This has been fixed in main for v3.6.0

• PR 66592 fix for main

**CVE-2024-1638**

Bluetooth characteristic LESC security requirement not enforced without additional flags

• Zephyr project bug tracker GHSA-p6f3-f63q-5mc2

This has been fixed in main for v3.6.0

• PR 69170 fix for main
Chapter 11

Safety

These documents describe the processes, developer guidelines and requirements for ensuring safety is addressed within the Zephyr project.

11.1 Zephyr Safety Overview

11.1.1 Introduction

This document is the safety documentation providing an overview over the safety-relevant activities and what the Zephyr Project and the Zephyr Safety Working Group / Committee try to achieve.

This overview is provided for people who are interested in the functional safety development part of the Zephyr RTOS and project members who want to contribute to the safety aspects of the project.

11.1.2 Overview

In this section we give the reader an overview of what the general goal of the safety certification is, what standard we aim to achieve and what quality standards and processes need to be implemented to reach such a safety certification.

11.1.3 Safety Document update

This document is a living document and may evolve over time as new requirements, guidelines, or processes are introduced.

1. Changes will be submitted from the interested party(ies) via pull requests to the Zephyr documentation repository.
2. The Zephyr Safety Committee will review these changes and provide feedback or acceptance of the changes.
3. Once accepted, these changes will become part of the document.
11.1.4 General safety scope

The general scope of the Safety Committee is to achieve a certification for the IEC 61508 standard and the Safety Integrity Level (SIL) 3 / Systematic Capability (SC) 3 for a limited source scope (see certification scope TBD). Since the code base is pre-existing, we use the route 3s/1s approach defined by the IEC 61508 standard.

Route 3s
Assessment of non-compliant development. Which is basically the route 1s with existing sources.

Route 1s
Compliant development. Compliance with the requirements of this standard for the avoidance and control of systematic faults in software.

Summarization IEC 61508 standard

The IEC 61508 standard is a widely recognized international standard for functional safety of electrical, electronic, and programmable electronic safety-related systems. Here's an overview of some of the key safety aspects of the standard:

1. Hazard and Risk Analysis: The IEC 61508 standard requires a thorough analysis of potential hazards and risks associated with a system in order to determine the appropriate level of safety measures needed to reduce those risks to acceptable levels.

2. Safety Integrity Level (SIL): The standard introduces the concept of Safety Integrity Level (SIL) to classify the level of risk reduction required for each safety function. The higher the SIL, the greater the level of risk reduction required.

3. System Design: The IEC 61508 standard requires a systematic approach to system design that includes the identification of safety requirements, the development of a safety plan, and the use of appropriate safety techniques and measures to ensure that the system meets the required SIL.

4. Verification and Validation: The standard requires rigorous testing and evaluation of the safety-related system to ensure that it meets the specified SIL and other safety requirements. This includes verification of the system design, validation of the system's functionality, and ongoing monitoring and maintenance of the system.

5. Documentation and Traceability: The IEC 61508 standard requires a comprehensive documentation process to ensure that all aspects of the safety-related system are fully documented and that there is full traceability from the safety requirements to the final system design and implementation.

Overall, the IEC 61508 standard provides a framework for the design, development, and implementation of safety-related systems that aims to reduce the risk of accidents and improve overall safety. By following the standard, organizations can ensure that their safety-related systems are designed and implemented to the highest level of safety integrity.

11.1.5 Quality

Quality is a mandatory expectation for software across the industry. The code base of the project must achieve various software quality goals in order to be considered an auditable code base from a safety perspective and to be usable for certification purposes. But software quality is not an additional requirement caused by functional safety standards. Functional safety considers quality as an existing pre-condition and therefore the "quality managed" status should be pursued for any project regardless of the functional safety goals. The following list describes the quality goals which need to be reached to achieve an auditable code base:

1. Basic software quality standards
a. **Coding Guidelines** (including: static code analysis, coding style, etc.)

b. Requirements and requirements tracing

c. Test coverage

2. Software architecture design principles
   a. Layered architecture model
   b. Encapsulated components
   c. Encapsulated single functionality (if not fitable and manageable in safety)

**Basic software quality standards - Safety view**

In this chapter the Safety Committee describes why they need the above listed quality goals as pre-condition and what needs to be done to achieve an auditable code base from the safety perspective. Generally speaking, it can be said that all of these quality measures regarding safety are used to minimize the error rate during code development.

**Coding Guidelines**  The coding guidelines are the basis to a common understanding and a unified ruleset and development style for industrial software products. For safety the coding guidelines are essential and have another purpose beside the fact of a unified ruleset. It is also necessary to prove that the developers follow a unified development style to prevent systematic errors in the process of developing software and thus to minimize the overall error rate of the complete software system.

Also the **IEC 61508 standard** sets a pre-condition and recommendation towards the use of coding standards / guidelines to reduce likelihood of errors.

**Requirements and requirements tracing**  Requirements and requirement management are not only important for software development, but also very important in terms of safety. On the one hand, this specifies and describes in detail and on a technical level what the software should do, and on the other hand, it is an important and necessary tool to verify whether the described functionality is implemented as expected. For this purpose, tracing the requirements down to the code level is used. With the requirements management and tracing in hand, it can now be verified whether the functionality has been tested and implemented correctly, thus minimizing the systematic error rate.

Also the **IEC 61508 standard** highly recommends (which is like a must-have for the certification) requirements and requirements tracing.

**Test coverage**  A high test coverage, in turn, is evidence of safety that the code conforms precisely to what it was developed for and does not execute any unforeseen instructions. If the entire code is tested and has a high (ideally 100%) test coverage, it has the additional advantage of quickly detecting faulty changes and further minimizing the error rate. However, it must be noted that different requirements apply to safety for test coverage, and various metrics must be considered, which are prescribed by the IEC 61508 standard for the SIL 3 / SC3 target. The following must be fulfilled, among other things:

- Structural test coverage (entry points) 100%
- Structural test coverage (statements) 100%
- Structural test coverage (branches) 100%

If the 100% cannot be reached (e.g. statement coverage of defensive code) that part needs to be described and justified in the documentation.
Software architecture design principles

To create and maintain a structured software product it is also necessary to consider individual software architecture designs and implement them in accordance with safety standards because some designs and implementations are not reasonable in safety, so that the overall software and code base can be used as auditable code. However, most of these software architecture designs have already been implemented in the Zephyr project and need to be verified by the Safety Committee / Safety Working Group and the safety architect.

Layered architecture model The IEC 61508 standard strongly recommends a modular approach to software architecture. This approach has been pursued in the Zephyr project from the beginning with its layered architecture. The idea behind this architecture is to organize modules or components with similar functionality into layers. As a result, each layer can be assigned a specific role in the system. This model has the advantage in safety that interfaces between different components and layers can be shown at a very high level, and thus it can be determined which functionalities are safety-relevant and can be limited. Furthermore, various analyses and documentations can be built on top of this architecture, which are important for certification and the responsible certification body.

Encapsulated components Encapsulated components are an essential part of the architecture design for safety at this point. The most important aspect is the separation of safety-relevant components from non-safety-relevant components, including their associated interfaces. This ensures that the components have no repercussions on other components.

Encapsulated single functionality (if not reasonable and manageable in safety) Another requirement for the overall system and software environment is that individual functionalities can be disabled within components. This is because if a function is absolutely unacceptable for safety (e.g. complete dynamic memory management), then these individual functionalities should be able to be turned off. The Zephyr Project already offers such a possibility through the use of Kconfig and its flexible configurability.

11.1.6 Processes and workflow

The diagram describes the rough process defined by the Safety Committee to ensure safety in the development of the Zephyr project. To ensure understanding, a few points need to be highlighted and some details explained regarding the role of the safety architect and the role of the safety committee in the whole process. The diagram only describes the paths that are possible when a change is related to safety.

1. On the main branch, the safety scope of the project should be identified, which typically represents a small subset of the entire code base. This subset should then be made auditable during normal development on “main”, which means that special attention is paid to quality goals (Quality) and safety processes within this scope. The Safety Architect works alongside the Technical Steering Committee (TSC) in this area, monitoring the development process to ensure that the architecture meets the safety requirements.

2. At this point, the safety architect plays an increasingly important role. For PRs/issues that fall within the safety scope, the safety architect should ideally be involved in the discussions and decisions of minor changes in the safety scope to be able to react to safety-relevant changes that are not conformant. If a pull request or issue introduces a significant and influential change or improvement that requires extended discussion or decision-making, the safety architect should bring it to the attention of the Safety Committee or the Technical Steering Committee (TSC) as appropriate, so that they can make a decision on the best course of action.
Fig. 1: Safety process and workflow overview
3. This section describes the certification side. At this point, the code base has to be in an “auditable” state, and ideally no further changes should be necessary or made to the code base. There is still a path from the main branch to this area. This is needed in case a serious bug or important change is found or implemented on the main branch in the safety scope, after the LTS and the auditable branch were created. In this case, the Safety Committee, together with the safety architect, must decide whether this bug fix or change should be integrated into the LTS so that the bug fix or change could also be integrated into the auditable branch. This integration can take three forms: First either as only a code change or second as only an update to the safety documentation or third as both.

4. This describes the necessary safety process required for certification itself. Here, the final analyses, tests, and documents are created and conducted which must be created and conducted during the certification, and which are prescribed by the certifying authority and the standard being certified. If the certification body approves everything at this stage and the safety process is completed, a safety release can be created and published.

5. This transition from the auditable branch to the main branch should only occur in exceptional circumstances, specifically when something has been identified during the certification process that needs to be quickly adapted on the “auditable” branch in order to obtain certification. In order to prevent this issue from arising again during the next certification, there needs to be a path to merge these changes back into the main branch so that they are not lost, and to have them ready for the next certification if necessary.

Important: Safety should not block the project and minimize the room to grow in any way.

Important: TODO: Find and define ways, guidelines and processes which minimally impact the daily work of the maintainers, reviewers and contributors and also the safety architect itself. But which are also suitable for safety.
Chapter 12

Glossary of Terms

API
(Application Program Interface) A defined set of routines and protocols for building application software.

application
The set of user-supplied files that the Zephyr build system uses to build an application image for a specified board configuration. It can contain application-specific code, kernel configuration settings, and at least one CMakeLists.txt file. The application's kernel configuration settings direct the build system to create a custom kernel that makes efficient use of the board's resources. An application can sometimes be built for more than one type of board configuration (including boards with different CPU architectures), if it does not require any board-specific capabilities.

application image
A binary file that is loaded and executed by the board for which it was built. Each application image contains both the application's code and the Zephyr kernel code needed to support it. They are compiled as a single, fully-linked binary. Once an application image is loaded onto a board, the image takes control of the system, initializes it, and runs as the system's sole application. Both application code and kernel code execute as privileged code within a single shared address space.

board
A target system with a defined set of devices and capabilities, which can load and execute an application image. It may be an actual hardware system or a simulated system running under QEMU. The Zephyr kernel supports a variety of boards.

board configuration
A set of kernel configuration options that specify how the devices present on a board are used by the kernel. The Zephyr build system defines one or more board configurations for each board it supports. The kernel configuration settings that are specified by the build system can be over-ridden by the application, if desired.

device runtime power management
Device Runtime Power Management (PM) refers the capability of devices to save energy independently of the system power state. Devices will keep reference of their usage and will automatically be suspended or resumed. This feature is enabled via the CONFIG_PM_DEVICE_RUNTIME Kconfig option.

idle thread
A system thread that runs when there are no other threads ready to run.

IDT
(Interrupt Descriptor Table) a data structure used by the x86 architecture to implement an interrupt vector table. The IDT is used to determine the correct response to interrupts and exceptions.
ISR
(Interrupt Service Routine) Also known as an interrupt handler, an ISR is a callback function
whose execution is triggered by a hardware interrupt (or software interrupt instructions)
and is used to handle high-priority conditions that require interrupting the current code
executing on the processor.

kernel
The set of Zephyr-supplied files that implement the Zephyr kernel, including its core ser-
vices, device drivers, network stack, and so on.

power domain
A power domain is a collection of devices for which power is applied and removed collect-
ively in a single action. Power domains are represented by device.

power gating
Power gating reduces power consumption by shutting off areas of an integrated circuit that
are not in use.

SoC
System on a chip

system power state
System power states describe the power consumption of the system as a whole. System
power states are represented by pm_state.

west
A multi-repo meta-tool developed for the Zephyr project. See West (Zephyr’s meta-tool).

west installation
An obsolete term for a west workspace used prior to west 0.7.

west manifest
A YAML file, usually named west.yml, which describes projects, or the Git repositories
which make up a west workspace, along with additional metadata. See Basics for general
information and West Manifests for details.

west manifest repository
The Git repository in a west workspace which contains the west manifest. Its location is
given by the manifest.path configuration option. See Basics.

west workspace
A directory on your system with a .west subdirectory and a west manifest repository. You
close the Zephyr source code onto your system by creating a west workspace using the west
init command. See Basics.

XIP
(eXecute In Place) a method of executing programs directly from long term storage rather
than copying it into RAM, saving writable memory for dynamic data and not the static pro-
gram code.
Bibliography

[a] Real Time Counter (RTC)
[b] Programmable Peripheral Interconnect (PPI)
[c] Distributed Programmable Peripheral Interconnect (DPPI)
[d] Software Interrupt (SWI)
[e] Random Number Generator (RNG)
[f] AES Electronic Codebook Mode Encryption (ECB)
[g] Cipher Block Chaining (CBC) - Message Authentication Code with Counter Mode encryption (CCM)
[h] Accelerated Address Resolver (AAR)
[i] General Purpose Input Output (GPIO)
[j] GPIO tasks and events (GPIOTE)
[k] Temperature sensor (TEMP)
[l] Universal Asynchronous Receiver Transmitter (UART)
[m] Interprocess Communication peripheral (IPC)

[th-imboot] Must boot with an immutable bootloader.
[th-authrepl] Application image shall only be replaced with an authorized image.
[th-timely-update] Application updates shall be done in a timely manner.
[th-atomic-update] Application updates shall be atomic.
[th-root-certs] TLS must have a list of trusted root certificates.
[th-root-check] TLS must verify root certificate from server is valid.
[th-secret-storage] There must be a mechanism to securely store client secrets. The least amount of code necessary shall have access to these secrets.
[th-time] System must have moderately accurate notion of the current date/time.
[th-conf] The system must receive, and keep configuration data.
[th-logs] The system must log security-related events, and either store them locally, or send to a service.
[th-all-tls] All communications with the cloud service shall use TLS.
[th-tls-ciphers] TLS shall be configured to allow only generally agreed cipher suites (including forward secrecy).
[th-tls-client-auth] The device shall authenticate itself with the cloud provider using one of the methods described.
[th-entropy] The TLS layer shall use a modern, accepted cryptographic random-bit generator seeded by an entropy source within the SoC.
[th-initial-provision] The device shall have a per-device secret loaded before deployment.
[th-initial-secret] The initial secret shall be securely maintained, and destroyed in any external location as soon as the device is provisioned.
[th-reprovision] Reprovisioning a device shall be done securely.
[th-destruction] Upon decommissioning, the device secret shall be rendered ineffective.
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